

Inverter



8400

E84AVTCxxxxx...

Inverter Drives 8400 TopLine C _ _ _ _ _

Reference manual

EN



Lenze

Overview of technical documentation for Inverter Drives 8400

Project planning, selection & ordering

- ☐ 8400 hardware manual
- ☒ Catalogue

Mounting & wiring

- ☒ MA 8400 BaseLine/StateLine/HighLine/TopLine
- ☒ MA for the communication module
- ☒ MA for the extension module
- ☒ MA for the safety module
- ☒ MA for the accessories

Parameterisation

- ☒ BA keypad
- ☐ SW 8400 BaseLine
- ☐ SW 8400 StateLine
- ☐ SW 8400 HighLine
- ☐ SW 8400 TopLine
- ☐ KHB for the communication module

← This documentation

Drive commissioning

- ☐ SW 8400 BaseLine/StateLine/HighLine/TopLine
 - chapter "Commissioning"
 - chapter "Diagnostics & error management"
- ☐ Remote maintenance manual

Networking

- ☐ KHB for the communication medium used

Legend:

- ☒ Printed documentation
- ☐ Online documentation (PDF/Engineer online help)

Abbreviations used:

- BA Operating Instructions
- KHB Communication manual
- MA Mounting instructions
- SW Software/reference manual

Contents

1	About this documentation	23
1.1	Document history	23
1.2	Conventions used	24
1.3	Terminology used	25
1.4	Definition of the notes used	27
2	Introduction: Parameterising the controller	28
2.1	Integrated technology applications	30
2.1.1	Purpose of the technology applications	31
2.1.2	Application cases for a technology application	31
2.1.3	Technology application = function block interconnection	32
2.2	Selection of the appropriate commissioning tool	33
2.2.1	Overview: Accessories for commissioning	34
2.3	General notes on parameters	35
2.3.1	Changing the parameterisation with the keypad	36
2.3.2	Change parameter settings with PC and Lenze software	39
2.3.3	Save parameter settings in the memory module safe against mains failure	40
2.3.4	User menu for quick access to frequently used parameters	42
2.4	Device access protection	43
2.4.1	Password protection	44
2.4.2	Individual password protection for single communication channels	46
2.4.3	Device personalisation	48
2.4.4	Unlocking the controller with a MasterPin	50
2.5	Device identification	51
2.5.1	Automatic acceptance of the device name in the »Engineer«	51
2.5.2	Extended item designation	51
3	Commissioning	52
3.1	Safety instructions with regard to commissioning	53
3.2	Notes on motor control	54
3.3	Preconditions for commissioning with the »Engineer«	55
3.4	Trouble-shooting during commissioning	56
3.5	Commissioning wizard 8400	56
3.6	Manual motor direction of rotation check (manual control)	58
3.7	Commissioning of the "Actuating drive speed" technology application	59
3.7.1	Prepare controller for commissioning	60
3.7.2	Creating an »Engineer« project & going online	61
3.7.3	Parameterising the motor control	62
3.7.4	Parameterise application	63
3.7.5	Saving parameter settings safe against mains failure	65
3.7.6	Enable controller and test application	65
3.8	Commissioning of the "Table positioning" technology application	67
3.8.1	Prepare controller for commissioning	69
3.8.2	Creating an »Engineer« project & going online	70
3.8.3	Parameterising the motor control	71
3.8.4	Parameterise application	72
3.8.4.1	Set machine parameters	73
3.8.4.2	Set the position encoder	74
3.8.4.3	Set homing	76
3.8.4.4	Enter one or more profiles	78
3.8.5	Saving parameter settings safe against mains failure	80
3.8.6	Enable controller and test application	80

Contents

3.9	Commissioning of the "Switch-off positioning" technology application	82
3.9.1	Prepare controller for commissioning	84
3.9.2	Creating an »Engineer« project & going online	85
3.9.3	Parameterising the motor control	86
3.9.4	Parameterise application	87
3.9.5	Saving parameter settings safe against mains failure	89
3.9.6	Enable controller and test application	89
3.10	PC manual control	90
3.10.1	Activate PC manual control	90
3.10.2	Speed control	93
3.10.3	Set/reset home position	95
3.10.4	Manual jog	96
3.10.5	Positioning (relative or absolute)	97
4	Device control (DCTRL)	99
4.1	Device commands (C00002/x)	101
4.1.1	Load Lenze setting	104
4.1.2	Load all parameter sets	105
4.1.3	Save all parameter sets	106
4.1.4	Enable/Inhibit controller	107
4.1.5	Activate/deactivate quick stop	108
4.1.5.1	Optional settings	109
4.1.5.2	Flow diagram	110
4.1.6	Reset error	111
4.1.7	Delete logbook	112
4.1.8	Device search function	112
4.2	Device state machine and device states	113
4.2.1	FirmwareUpdate	114
4.2.2	Init	115
4.2.3	Ident	116
4.2.4	SafeTorqueOff	117
4.2.5	ReadyToSwitchOn	118
4.2.6	SwitchedOn	119
4.2.7	OperationEnabled	120
4.2.8	TroubleQSP	121
4.2.9	Trouble	122
4.2.10	Fault	123
4.2.11	SystemFault	123
4.3	Automatic restart after mains connection/fault...	124
4.3.1	"Inhibit at power-on" auto-start option	124
4.3.2	Auto-start option "Inhibit at Lenze setting"	126
4.4	Internal interfaces "LS_DriveInterface" system block	127
4.4.1	wCANControl/wMCIControl control words	130
4.4.2	wDeviceStatusWord status word	132

5	Motor control (MCTRL)	134
5.1	Motor selection/Motor data	135
5.1.1	Selecting a motor from the motor catalogue in the »Engineer«	139
5.1.2	Automatic motor data identification	141
5.1.3	Application notes for asynchronous motors with high slip speed	148
5.2	Selecting the control mode	149
5.2.1	Selection help	153
5.3	Defining current and speed limits	154
5.4	V/f characteristic control (VFCplus)	157
5.4.1	Parameterisation dialog/signal flow	158
5.4.2	Basic settings	160
5.4.2.1	Defining the V/f characteristic shape	161
5.4.2.2	Defining current limits (Imax controller)	162
5.4.3	Optimising the control mode	163
5.4.3.1	Adapting the V/f base frequency	164
5.4.3.2	Adapting the Vmin boost	166
5.4.3.3	Optimising the Imax controller	168
5.4.3.4	Optimising the stalling behaviour	169
5.4.3.5	Torque limitation	170
5.4.3.6	Defining a user-defined V/f characteristic	172
5.4.4	Remedies for undesired drive behaviour	175
5.5	V/f characteristic control - energy-saving (VFCplusEco)	176
5.5.1	Parameterisation dialog/signal flow	177
5.5.2	Comparison of VFCplusEco - VFCplus	179
5.5.3	Basic settings	180
5.5.4	Optimising the control mode	181
5.5.4.1	Improving the behaviour at high dynamic load changes	182
5.5.4.2	Adapting the slope limitation for lowering the Eco function	183
5.5.4.3	Optimising the cos/phi controller	183
5.5.5	Remedies for undesired drive behaviour	184
5.6	V/f control (VFCplus + encoder)	186
5.6.1	Parameterisation dialog/signal flow	187
5.6.2	Basic settings	189
5.6.2.1	Parameterising the slip regulator	190
5.7	Sensorless vector control (SLVC)	193
5.7.1	Parameterisation dialog/signal flow	194
5.7.2	Types of control	196
5.7.2.1	Speed control with torque limitation	196
5.7.2.2	Torque control with speed limitation	197
5.7.3	Basic settings	198
5.7.4	Optimising the control mode	199
5.7.4.1	Optimising the starting performance after a controller enable	199
5.7.4.2	Optimise speed controller	200
5.7.4.3	Optimising dynamic performance and field weakening behaviour	201
5.7.4.4	Optimising the stalling behaviour	202
5.7.4.5	Optimise response to setpoint changes and determine mass inertia	203
5.7.4.6	Slip calculation from motor equivalent circuit diagram data	206
5.7.4.7	Optimising field feedforward control and torque feedforward control	207
5.7.5	Remedies for undesired drive behaviour	208

Contents

5.8	Sensorless control for synchronous motors (SLPSM)	209
5.8.1	Parameterisation dialog/signal flow	211
5.8.2	Types of control	214
5.8.3	Basic settings	215
5.8.4	Optimising the control mode	217
5.8.4.1	Optimise current controller	218
5.8.4.2	Optimise speed controller	219
5.8.4.3	Optimise response to setpoint changes and determine mass inertia	222
5.9	Servo control (SC)	226
5.9.1	Parameterisation dialog/signal flow	227
5.9.2	Types of control	232
5.9.2.1	Speed control with torque limitation	232
5.9.2.2	Torque control with speed limitation	234
5.9.3	Basic settings	235
5.9.4	Optimising the control mode	236
5.9.4.1	Optimise current controller	237
5.9.4.2	Optimise speed controller	238
5.9.4.3	Optimise response to setpoint changes and determine mass inertia	241
5.9.4.4	Setting the current setpoint filter (band-stop filter)	244
5.9.4.5	Adapting the max. acceleration change (jerk limitation)	245
5.9.4.6	Slip calculation from motor equivalent circuit diagram data	246
5.9.4.7	Temperature compensation within the motor control	248
5.9.4.8	Optimising the behaviour of the asynchronous motor in the field weakening range	250
5.9.4.9	Feedforward control of the current controller	255
5.10	Parameterisable additional functions	256
5.10.1	Selection of switching frequency	256
5.10.2	Operation with increased rated power	260
5.10.3	Current-dependent stator leakage inductance Ppp(I)	262
5.10.4	Flying restart function	264
5.10.5	DC-injection braking	267
5.10.5.1	Manual DC-injection braking (DCB)	268
5.10.5.2	Automatic DC-injection braking (Auto-DCB)	268
5.10.6	Slip compensation	271
5.10.7	Oscillation damping	272
5.10.7.1	Oscillation damping voltage range	273
5.10.7.2	Oscillation damping in the field weakening range	274
5.10.8	Phase sequence reversal for correcting misconnected UVW motor phases	275
5.10.9	Field weakening for synchronous motors	276
5.11	Position control/additive speed specification	280
5.12	Braking operation/brake energy management	281
5.12.1	Setting the voltage source for braking operation	284
5.12.2	Selecting the response to an increase of the DC-bus voltage	284
5.12.2.1	Inverter motor brake	286
5.12.3	Avoiding thermal overload of the brake resistor	289
5.12.4	Control of multiple internal brake choppers in the DC-bus system	289
5.13	Monitoring	292
5.13.1	Device overload monitoring (Ixt)	293
5.13.2	Motor load monitoring (I2xt)	294
5.13.3	Motor overcurrent monitoring	296
5.13.4	Motor temperature monitoring (PTC)	297
5.13.5	Brake resistor monitoring (I2xt)	298
5.13.6	Motor phase failure monitoring	300
5.13.7	Motor phase error monitoring before operation	301
5.13.8	Mains phase failure monitoring	303

5.13.9	Maximum current monitoring	303
5.13.10	Maximum torque monitoring	304
5.13.11	Motor speed monitoring	304
5.14	Internal interfaces System block "LS_MotorInterface"	305
5.15	Internal status signals System block "LS_DeviceMonitor"	311
6	Encoder/feedback system	314
6.1	Encoder selection	315
6.1.1	Signal flow - encoder interface	317
6.2	Resolver (X7)	319
6.2.1	Parameterising the resolver	319
6.2.2	Optimising resolver behaviour	321
6.2.3	Internal interfaces "LS_Resolver" system block	324
6.3	Multi-Encoder (X8)	325
6.3.1	Incremental TTL and SinCos encoder	326
6.3.2	SinCos absolute value encoder with HIPERFACE® protocol	328
6.3.2.1	Initialisation	328
6.3.2.2	Parameterising the encoder	330
6.3.2.3	Display of the current position	333
6.3.2.4	Notes on evaluating absolute value encoder of SEL37 and SELxx types by SICK	334
6.3.2.5	Configuration example 1: Absolute wire draw encoder "XKS09-HTBM0527" by SICK	335
6.3.2.6	Configuration example 2: Distance sensor "DME5000-117" by SICK	336
6.3.3	SSI absolute value encoder with Stegmann-SSI protocol	337
6.3.3.1	Parameterising the encoder	337
6.3.3.2	Important notes for using an SSI laser position encoder	341
6.3.3.3	Configuration example 1: Optical multi-turn rotary encoder "GOM2H Z04" by Baumer	342
6.3.3.4	Configuration example 2: Distance sensor "DME5000-111" by SICK	343
6.3.4	Digital frequency coupling	345
6.3.4.1	Problem description - speed variations	347
6.3.4.2	Internal interfaces System block "LS_DFOut"	348
6.3.5	Internal interfaces System block "LS_MultiEncoder"	349
6.3.5.1	Scaling of position value	351
6.3.5.2	Setting of a static position offset	351
6.4	Frequency HTL encoder (DI1/DI2, DI6/DI7)	352
6.4.1	Parameterising digital inputs as encoder inputs	353
6.4.2	HTL encoder at DI1/DI2	355
6.4.3	HTL encoder at DI6/DI7	357
6.5	Pole position identification (PPI)	358
6.5.1	Pole position identification 360°	360
6.5.2	Pole position identification without motion	364
6.6	Mounting	367
6.7	Monitoring	368
6.7.1	Resolver/multi-encoder open-circuit monitoring	369
6.7.2	Open-circuit monitoring HTL encoder	370
6.7.3	Encoder - angular drift monitoring	371
6.7.4	Encoder value monitoring	372
6.7.5	Motor temperature monitoring (KTY)	373

Contents

7	I/O terminals	376
7.1	Digital input terminals	377
7.1.1	Change function assignment	379
7.1.1.1	Using DI1(6) and DI2(7) as digital inputs	380
7.1.1.2	Using DI1(6) and DI2(7) as frequency inputs	381
7.1.1.3	Using DI1(6) as counting input	386
7.1.2	Internal interfaces System block "LS_DigitalInput"	390
7.1.2.1	Output of the encoder position of the DI1/DI2 frequency input	393
7.1.2.2	Switching status of the motor holding brake at the high current output	397
7.2	Digital output terminals	398
7.2.1	Internal interfaces System block "LS_DigitalOutput"	400
7.3	Analog terminals	401
7.3.1	Parameterising analog input	404
7.3.1.1	Signal adaptation by means of characteristic	406
7.3.2	Parameterising analog output	408
7.3.3	Internal interfaces System block "LS_AnalogInput"	409
7.3.4	Internal interfaces System block "LS_AnalogOutput"	410
7.4	Touch probe detection	411
7.4.1	Parameter setting	413
7.4.1.1	Z-track encoder as a touch probe signal source	416
7.4.1.2	Z-track resolver as a touch probe signal source	416
7.4.2	Internal interfaces System block "LS_TouchProbe"	417
7.4.2.1	Application example: "Position measurement"	419
7.5	Configuring exception handling of the output terminals	420
7.6	User-defined terminal assignment	421
7.6.1	Source-destination principle	422
7.6.2	Changing the terminal assignment with the keypad	423
7.6.3	Changing the terminal assignment with the »Engineer«	425
8	Technology applications	428
8.1	Selection of the technology application and the control mode	429
8.2	TA "Actuating drive speed"	430
8.2.1	Basic signal flow	431
8.2.2	Internal interfaces application block "LA_NCtrl"	433
8.2.3	Terminal assignment of the control modes	441
8.2.3.1	Terminals 0	442
8.2.3.2	Terminals 2	443
8.2.3.3	Terminals 11	444
8.2.3.4	Terminal 16	445
8.2.3.5	Keypad	446
8.2.3.6	PC	447
8.2.3.7	CAN	448
8.2.3.8	MCI	449
8.2.4	Process data assignment for fieldbus communication	450
8.2.5	Setting parameters (short overview)	452
8.2.6	Configuration parameters	454

Contents

8.3	TA "actuating drive speed (AC Drive Profile)"	457
8.3.1	I/O assemblies	458
8.3.2	Basic signal flow	459
8.3.3	Internal interfaces application block "LA_NCtrl"	462
8.3.4	Terminal assignment of the control modes	471
8.3.4.1	Terminals 0	472
8.3.4.2	Terminals 2	473
8.3.4.3	Terminals 11	474
8.3.4.4	Terminal 16	475
8.3.4.5	Keypad	476
8.3.4.6	PC	477
8.3.4.7	CAN	478
8.3.4.8	MCI	479
8.3.5	Process data assignment for fieldbus communication	480
8.3.5.1	Run/Stop event	481
8.3.5.2	Scaling of speed and torque values	482
8.3.6	AC Drive Profile diagnostic parameters	483
8.3.7	Setting parameters (short overview)	483
8.3.8	Configuration parameters	485
8.4	TA "Table positioning"	490
8.4.1	Basic signal flow	491
8.4.1.1	Possibilities for the position selection	492
8.4.2	Internal interfaces application block "LA_TabPos"	494
8.4.3	Terminal assignment of the control modes	504
8.4.3.1	Terminals 0	505
8.4.3.2	Terminals 2	506
8.4.3.3	Terminals 11	507
8.4.3.4	Terminal 16	508
8.4.3.5	Keypad	509
8.4.3.6	PC	510
8.4.3.7	CAN	511
8.4.3.8	MCI	512
8.4.4	Process data assignment for fieldbus communication	513
8.4.5	Setting parameters (short overview)	515
8.4.6	Configuration parameters	516
8.5	TA "Switch-off positioning"	519
8.5.1	Basic signal flow	521
8.5.2	Internal interfaces application block "LA_SwitchPos"	522
8.5.2.1	Truth table for activating the pre-switch off	529
8.5.3	Terminal assignment of the control modes	530
8.5.3.1	Terminals 0	531
8.5.3.2	Terminals 2	532
8.5.3.3	Terminals 11	533
8.5.3.4	Terminal 16	534
8.5.3.5	Keypad	535
8.5.3.6	PC	536
8.5.3.7	CAN	537
8.5.3.8	MCI	538
8.5.4	Process data assignment for fieldbus communication	539
8.5.5	Setting parameters (short overview)	541
8.5.6	Configuration parameters	543

Contents

8.6	"GeneralPurpose" functions	546
8.6.1	Analog switch	546
8.6.2	Arithmetic	547
8.6.3	Multiplication/Division	547
8.6.4	Binary delay element	548
8.6.5	Binary logic	548
8.6.6	Analog comparison	549
8.6.7	Binary signal monitor	549
8.6.8	Analog signal monitor	550
8.6.9	D-FlipFlop	550
8.6.10	Counter	551
9	Basic drive functions (MCK)	552
9.1	Basic signal flow	553
9.2	Internal interfaces System block "LS_MotionControlKernel"	554
9.2.1	MCK control word	560
9.2.2	MCK status word	562
9.2.2.1	Status bit "HomPosAvailable"	564
9.2.2.2	Status bit "S_ShapingActive"	565
9.2.3	MCK state machine	566
9.2.3.1	"StandBy" operating mode	567
9.2.4	Interface to safety system	568
9.2.5	Consideration of residual value in case of external profile calculation	569
9.3	MCKInterface	570
9.3.1	Control inputs "L_MckCtrlInterface" function block	572
9.3.1.1	Alternative functions for control bit "PosExecute"	577
9.3.1.2	Operating mode change with profile number	578
9.3.2	Status outputs FB "L_MckStateInterface"	579
9.4	Basic settings	582
9.4.1	Machine parameters	582
9.4.1.1	Gearbox ratio	584
9.4.1.2	Feed constant	585
9.4.1.3	Activation of the modulo measuring system	586
9.4.2	Min/Max speed	589
9.4.3	Limit position monitoring	590
9.4.3.1	Software limit positions	590
9.4.3.2	Hardware limit switch	592
9.4.4	Target position monitoring (status "drive in target")	594
9.4.5	Monitoring of the maximum travel distance	596
9.4.6	Following error monitoring system	597
9.4.6.1	Monitoring of the following error in case of controller inhibit	598
9.4.7	Setpoint holdback for bus runtime compensation	599
9.4.8	Setting or activation of maximum jerk for traversing profiles	603
9.5	Speed follower	604
9.5.1	Parameter setting	604
9.5.1.1	Functional settings	604
9.5.2	Requesting the operating mode	605
9.5.3	Setpoint selection	605

Contents

9.6	Homing	606
9.6.1	Parameter setting	607
9.6.1.1	Functional settings	608
9.6.1.2	Homing mode	609
9.6.1.3	Home position & home value offset	621
9.6.1.4	Traversing a sequence profile after completion of homing	621
9.6.1.5	Measurement of the distance between pre-stop mark/limit switch and TP/MP	621
9.6.1.6	Option "Actual MCTRL position received at mains switch-off"	622
9.6.2	Requesting the operating mode	622
9.6.3	Execute homing	623
9.6.3.1	Homing on the fly	624
9.7	Manual jog	625
9.7.1	Parameter setting	626
9.7.1.1	Functional settings	627
9.7.1.2	Smooth start and quick stop of the drive	628
9.7.1.3	Second speed	628
9.7.1.4	Time-based start of second speed	629
9.7.2	Requesting the operating mode	630
9.7.3	Executing manual jogging	630
9.7.3.1	Manual jog to limit position	631
9.7.3.2	Retracting of an operated limit switch	632
9.8	Positioning	633
9.8.1	Possible motion profiles	634
9.8.2	Parameter setting	635
9.8.2.1	Functional settings	636
9.8.2.2	Profile entry	637
9.8.2.3	Positioning modes	640
9.8.2.4	Touch probe positioning	641
9.8.2.5	S-ramp time for jerk limitation	642
9.8.3	Requesting the operating mode	644
9.8.4	Carrying out positioning	644
9.8.4.1	Stipulation of the profile to be executed	644
9.8.4.2	Starting/cancelling a traversing task	645
9.8.4.3	Override of the parameterised positioning mode	646
9.8.4.4	Position teaching	647
9.9	Stop	648
9.9.1	Parameter setting	648
9.9.2	Requesting the operating mode	648
9.10	Position follower	649
9.10.1	Parameter setting	649
9.10.1.1	Functional settings	649
9.10.2	Requesting the operating mode	650
9.10.3	Setpoint selection	650
9.11	Override	651
9.11.1	Speed override	652
9.11.2	Acceleration override	653
9.11.3	S-ramp smoothing override	654

Contents

9.12	Holding brake control	655
9.12.1	Internal interfaces	656
9.12.2	Parameter setting	658
9.12.2.1	Operating mode	659
9.12.2.2	Functional settings	661
9.12.2.3	Switching thresholds	662
9.12.2.4	Application and release time	663
9.12.2.5	Ramp time for approaching the setpoint speed	665
9.12.2.6	Motor magnetising time (only with asynchronous motor)	666
9.12.2.7	Actual value monitoring	666
9.12.3	Process when brake is released	667
9.12.4	Process when brake is closed	668
9.12.5	Behaviour in case of pulse inhibit	670
9.12.6	Feedforward control of the motor before release	671
10	Diagnostics & error management	673
10.1	Basics on error handling in the controller	673
10.2	LED status displays	674
10.2.1	LED status displays of the device status	675
10.3	Drive diagnostics with the »Engineer«	676
10.3.1	Display details of the error	678
10.4	Drive diagnostics via keypad/bus system	679
10.5	Logbook	682
10.5.1	Functional description	682
10.5.2	Filtering logbook entries	683
10.5.3	Automatic recording of device-internal signals at the time the error occurs	683
10.5.4	Reading out logbook entries	684
10.5.5	Exporting logbook entries to a file	685
10.5.6	Storing the logbook in the project	686
10.5.7	Reading out the logbook from an external control/visualisation	687
10.6	Monitoring	689
10.6.1	Monitoring configuration	690
10.6.2	Setting the error response	691
10.6.3	AutoFailReset function	692
10.7	Maloperation of the drive	693
10.8	Operation without mains supply	695
10.9	Error messages of the operating system	696
10.9.1	Structure of the 32-bit error number (bit coding)	696
10.9.2	Structure of the 16 bit error number (bit coding)	699
10.9.3	Reset error message	700
10.9.4	Export error texts	701
10.9.5	Short overview (A-Z)	702
10.9.6	Cause & possible remedies	705
10.10	"LS_SetError_1" system block	731
10.11	"LS_SetError_2" system block	732

Contents

11	Oscilloscope function	733
11.1	Technical data	734
11.2	User interface	735
11.3	Operation	737
11.3.1	Selecting the variables to be recorded	737
11.3.2	Selecting the recording time/sample rate	738
11.3.3	Defining the trigger condition	739
11.3.4	Starting recording	740
11.3.5	Adjusting the representation	740
11.3.6	Cursor function: Reading individual measured values	743
11.4	Managing oscillograms (measured data sets)	744
11.4.1	Commenting the oscillogram	744
11.4.2	Saving the oscillogram	745
11.4.3	Loading the oscillogram	746
11.4.4	Closing the oscillogram	747
11.4.5	Overlay function	747
11.4.6	Deleting a data set saved in the project	748
12	System bus "CAN on board"	749
12.1	General information	750
12.1.1	General data and application conditions	750
12.1.2	Supported protocols	751
12.1.3	Communication time	752
12.2	Possible settings via DIP switch	753
12.2.1	Activating the bus terminating resistor	753
12.2.2	Setting the baud rate	754
12.2.3	Setting the node address	754
12.3	LED status displays for the system bus	755
12.4	Going online via the system bus	756
12.5	Reinitialising the CANopen interface	756
12.6	Structure of the CAN data telegram	757
12.6.1	Identifier	757
12.6.2	User data	759
12.7	Communication phases/network management	760
12.7.1	Status transitions	761
12.7.2	Network management telegram (NMT)	762
12.7.3	Parameterising the controller as CAN master	763
12.8	Process data transfer	764
12.8.1	Available process data objects	765
12.8.1.1	RPDO1 Port block "LP_CanIn1"	766
12.8.1.2	RPDO2 "LP_CanIn2" port block	768
12.8.1.3	RPDO3 "LP_CanIn3" port block	770
12.8.1.4	RPDO4 "LP_CanIn4" port block	772
12.8.1.5	TPDO1 "LP_CanOut1" port block	774
12.8.1.6	TPDO2 "LP_CanOut2" port block	775
12.8.1.7	TPDO3 "LP_CanOut3" port block	776
12.8.1.8	TPDO4 "LP_CanOut4" port block	777
12.8.2	Identifiers of the process data objects	778
12.8.3	Transmission type	780
12.8.4	PDO synchronisation via sync telegram	782
12.8.5	Monitoring of the RPDOs for data reception	783
12.8.6	Configuring exception handling of the CAN PDOs	783

Contents

12.9	Parameter data transfer	785
12.9.1	Identifiers of the parameter data objects	786
12.9.2	User data	786
12.9.2.1	Command	787
12.9.2.2	Addressing by means of index and subindex	788
12.9.2.3	Data 1 ... Data 4	789
12.9.2.4	Error messages	790
12.9.3	Parameter data telegram examples	792
12.9.3.1	Read parameters	792
12.9.3.2	Write parameters	793
12.9.3.3	Read block parameters	794
12.10	Monitoring	797
12.10.1	Integrated error detection	797
12.10.2	Heartbeat protocol	798
12.10.2.1	Telegram structure	798
12.10.2.2	Parameter setting	799
12.10.2.3	Commissioning example	800
12.10.3	Emergency telegram	801
12.11	Implemented CANopen objects	802
12.12	Internal interfaces System block "LS_CANManagement"	828
13	Fieldbus interface (MCI)	829
13.1	Process data transfer	830
13.2	Control mode "MCI"	832
13.2.1	Port block "LP_MciIn"	833
13.2.2	Port block "LP_MciOut"	834
13.3	CAN gateway	835
14	Axis bus	836
14.1	LED status displays of the axis bus	837
14.2	Data transfer axis bus	838
14.2.1	Topologies	838
14.2.2	Transfer mechanisms	838
14.2.3	Activating the bus terminating resistor	840
14.2.4	Parameter setting	841
14.2.4.1	Required settings at the master	842
14.2.4.2	Required settings for the slaves	842
14.2.4.3	Boot-up phase	843
14.2.4.4	Disconnect nodes from the axis bus	843
14.2.4.5	Configuring exception handling of the received data	844
14.2.4.6	Integrated error detection	845
14.2.4.7	Axis bus data error monitoring	846
14.2.5	Internal interfaces System block "LS_AxisBusOut"	847
14.2.6	Internal interfaces System block "LS_AxisBusIn"	848
14.2.7	Internal interfaces System block "LS_AxisBusAux"	849
14.3	IO axis bus	851
14.3.1	"Master/slave" function	852
14.3.2	"IO" function	855
14.3.3	Internal interfaces System block "LS_AxisBusIO"	856
15	Synchronisation of the internal time base	857
15.1	Internal interfaces System block "LS_SyncManagement"	858

Contents

16	Parameter change-over	859
16.1	Configuring parameter change-over via the »Engineer« parameterisation dialog	860
16.1.1	Configuring the parameter list(s)	861
16.1.2	Configuring control inputs	864
16.1.3	Functional settings	865
16.1.4	Error indication	865
16.2	Configuring the definable parameter list by means of parameterisation	866
16.3	Configuring the motor data parameter list by means of parameterisation	867
16.4	Internal interfaces System block "LS_WriteParamList"	870
17	Parameter reference	872
17.1	Structure of the parameter descriptions	873
17.1.1	Data type	874
17.1.2	Parameters with read-only access	874
17.1.3	Parameters with write access	875
17.1.3.1	Parameters with setting range	875
17.1.3.2	Parameters with selection list	875
17.1.3.3	Parameters with bit-coded setting	876
17.1.3.4	Parameters with subcodes	877
17.1.4	Parameter attributes	877
17.2	Parameter list	879
17.3	Selection list - analog signals	1295
17.4	Selection list - digital signals	1301
17.5	Selection list - angle signals	1308
17.6	Table of attributes	1310
18	Working with the FB Editor	1329
18.1	Basics	1329
18.1.1	Basic components of a drive solution	1330
18.1.1.1	What is a function block?	1331
18.1.1.2	Parameterisable function blocks	1332
18.1.1.3	What is a system block?	1332
18.1.1.4	What is a port block?	1333
18.1.1.5	What is an application block?	1333
18.1.2	Conventions used for input/output identifiers	1334
18.1.3	Scaling of physical units	1335
18.2	User interface	1336
18.2.1	Toolbar	1337
18.2.2	Search function	1338
18.2.3	Level selection	1339
18.2.4	Editor view/overview	1341
18.2.5	Context menu	1342
18.2.6	Status bar	1342
18.2.7	Overview window	1343
18.3	Using the FB Editor as "Viewer"	1345
18.3.1	Following connections of inputs and outputs	1346
18.3.2	Keyboard commands for navigation	1347
18.3.3	Change online display format	1348
18.4	Reconfiguring the predefined interconnection	1350
18.4.1	Inserting/Deleting objects	1350
18.4.1.1	Inserting a function block	1351
18.4.1.2	Inserting a system block	1353
18.4.1.3	Inserting a port block	1355
18.4.1.4	Inserting a comment	1357
18.4.1.5	Deleting objects that are no longer required	1359

Contents

18.4.2	Changing connector visibilities	1360
18.4.3	Arranging objects in the drawing area	1361
18.4.4	Creating/deleting connections	1362
18.4.4.1	Creating a connection using the connection line	1364
18.4.4.2	Creating a connection using port identifiers	1365
18.4.4.3	Creating a connection via connection dialog	1366
18.4.4.4	Deleting connections that are no longer required	1367
18.4.5	Changing the processing order	1368
18.4.6	Copying interconnection elements (across all devices)	1370
18.4.6.1	Insert options for copied elements	1372
18.4.7	Resetting changed interconnection	1373
18.5	Adjusting online and offline interconnection	1374
18.6	Printing the interconnection	1375
18.7	Comparing interconnections	1376
18.8	Copying an interconnection	1379
18.9	Exporting/Importing an interconnection	1380
19	Function library	1381
19.1	Function blocks	1381
19.1.1	L_Absolut_1	1386
19.1.2	L_Absolut_2	1386
19.1.3	L_AddSub_1	1387
19.1.4	L_AnalogSwitch_1	1388
19.1.5	L_AnalogSwitch_2	1389
19.1.6	L_AnalogSwitch_3	1390
19.1.7	L_AnalogSwitch_4	1391
19.1.8	L_AnalogSwitch_5	1392
19.1.9	L_And_1	1393
19.1.10	L_And_2	1394
19.1.11	L_And_3	1395
19.1.12	L_And5_1	1396
19.1.13	L_And5_2	1397
19.1.14	L_Arithmetik_1	1398
19.1.15	L_Arithmetik_2	1399
19.1.16	L_Arithmetik_3	1400
19.1.17	L_Arithmetik_4	1401
19.1.18	L_Arithmetik_5	1402
19.1.19	L_ArithmetikPhi_1	1403
19.1.20	L_ArithmetikPhi_2	1404
19.1.21	L_ArithmetikPhi_3	1405
19.1.22	L_ArithmetikPhi_4	1406
19.1.23	L_ArithmetikPhi_5	1407
19.1.24	L_ArithmetikPhi_6	1408
19.1.25	L_CalcDiameter_1	1409
19.1.25.1	Set initial value	1412
19.1.25.2	Calculate diameter	1412
19.1.25.3	Select change direction, web break monitoring	1412
19.1.25.4	Holding the current value	1412
19.1.25.5	Limit value monitoring	1413
19.1.25.6	Converting diameter in 1/D	1413
19.1.25.7	Physical state variables	1413

19.1.26	L_Compare_1	1414
19.1.26.1	Function 1: $nln1 = nln2$	1415
19.1.26.2	Function 2: $nln1 > nln2$	1416
19.1.26.3	Function 3: $nln1 < nln2$	1417
19.1.26.4	Function 4: $ nln1 = nln2 $	1418
19.1.26.5	Function 5: $ nln1 > nln2 $	1418
19.1.26.6	Function 6: $ nln1 < nln2 $	1418
19.1.27	L_Compare_2	1419
19.1.28	L_Compare_3	1420
19.1.29	L_Compare_4	1421
19.1.30	L_Compare_5	1422
19.1.31	L_ComparePhi_1	1423
19.1.31.1	Function 1: $dln1 = dln2$	1424
19.1.31.2	Function 2: $dln1 > dln2$	1425
19.1.31.3	Function 3: $dln1 < dln2$	1426
19.1.31.4	Function 4: $ dln1 = dln2 $	1427
19.1.31.5	Function 5: $ dln1 > dln2 $	1427
19.1.31.6	Function 6: $ dln1 < dln2 $	1427
19.1.32	L_ComparePhi_2	1428
19.1.33	L_ComparePhi_3	1429
19.1.34	L_ComparePhi_4	1430
19.1.35	L_ComparePhi_5	1431
19.1.36	L_ConvActPos_1	1432
19.1.36.1	Determining limit positions	1434
19.1.36.2	Monitoring the dancer position	1434
19.1.36.3	Circumferential speed of the reel	1434
19.1.36.4	Additional torque for damping the dancer control	1434
19.1.37	L_ConvAP_1	1435
19.1.38	L_ConvAP_2	1436
19.1.39	L_ConvAP_3	1437
19.1.40	L_ConvBitsToWord_1	1438
19.1.41	L_ConvBitsToWord_2	1439
19.1.42	L_ConvBitsToWord_3	1440
19.1.43	L_ConvDIntToWords_1	1441
19.1.44	L_ConvDIntToWords_2	1442
19.1.45	L_ConvDIntToWords_3	1443
19.1.46	L_ConvPA_1	1444
19.1.47	L_ConvPA_2	1445
19.1.48	L_ConvPA_3	1446
19.1.49	L_ConvPP_1	1447
19.1.50	L_ConvPP_2	1448
19.1.51	L_ConvPP_3	1449
19.1.52	L_ConvUnitsToIncr_1	1450
19.1.53	L_ConvUnitsToIncr_2	1452
19.1.54	L_ConvUnitsToIncr_3	1454
19.1.55	L_ConvW_1	1456
19.1.56	L_ConvW_2	1458
19.1.57	L_ConvW_3	1459
19.1.58	L_ConvW_4	1460
19.1.59	L_ConvWordsToDInt_1	1461
19.1.60	L_ConvWordsToDInt_2	1462
19.1.61	L_ConvWordsToDInt_3	1463
19.1.62	L_ConvWordToBits_1	1464
19.1.63	L_ConvWordToBits_2	1465
19.1.64	L_ConvWordToBits_3	1466

Contents

19.1.65	L_ConvX_1	1467
19.1.66	L_ConvX_2	1468
19.1.67	L_ConvX_3	1469
19.1.68	L_Counter_1	1470
19.1.69	L_Counter_2	1472
19.1.70	L_Counter_3	1474
19.1.71	L_Curve_1	1476
19.1.71.1	Function 3: nOut_a = f(table)	1477
19.1.72	L_Curve_2	1480
19.1.73	L_Curve_3	1482
19.1.73.1	Use of the L_Curve_3 for tensile force characteristic	1484
19.1.74	L_DFliPlop_1	1487
19.1.75	L_DFliPlop_2	1488
19.1.76	L_DFRFG_1	1489
19.1.76.1	Ramp function generator (profile generator)	1491
19.1.76.2	Quick stop	1493
19.1.76.3	Ramp function generator stop	1494
19.1.76.4	Reset angle setpoint	1494
19.1.76.5	Detecting the angular difference	1494
19.1.76.6	Offset setting	1495
19.1.77	L_DFSET_1	1498
19.1.77.1	Master value rail/slave cascade	1503
19.1.77.2	Setpoint conditioning with stretch factor and gearbox factor	1503
19.1.77.3	Processing correction values	1504
19.1.77.4	Synchronising slave drive to master drive	1506
19.1.77.5	Masking out touch probe signals	1509
19.1.77.6	Process monitoring functions	1509
19.1.78	L_DigitalDelay_1	1510
19.1.79	L_DigitalDelay_2	1512
19.1.80	L_DigitalDelay_3	1513
19.1.81	L_DigitalLogic_1	1514
19.1.82	L_DigitalLogic_2	1516
19.1.83	L_DigitalLogic_3	1518
19.1.84	L_DigitalLogic5_1	1520
19.1.85	L_DigitalLogic5_2	1522
19.1.86	L_DT1_1	1524
19.1.87	L_FixSet_a_1	1525
19.1.88	L_FixSet_w_1	1526
19.1.89	L_FixSet_w_2	1527
19.1.90	L_GainOffset_1	1528
19.1.91	L_GainOffset_2	1529
19.1.92	L_GainOffset_3	1530
19.1.93	L_GainOffsetP_1	1531
19.1.94	L_GainOffsetP_2	1532
19.1.95	L_GainOffsetP_3	1533
19.1.96	L_GainOffsetPhiP_1	1534
19.1.97	L_GainOffsetPhiP_2	1535
19.1.98	L_GearComp_1	1536
19.1.99	L_Interpolator_1	1538
19.1.99.1	Signal interpolation	1539
19.1.99.2	Signal monitoring	1540
19.1.99.3	Angle correction in case of transmission errors	1541
19.1.100	L_JogCtrlExtension_1	1542

Contents

19.1.101	L_Limit_1	1544
19.1.102	L_Limit_2	1545
19.1.103	L_LimitPhi_1	1546
19.1.104	L_LimitPhi_2	1547
19.1.105	L_LimitPhi_3	1548
19.1.106	L_MFail_1	1549
19.1.106.1	Procedure of the mains failure control	1551
19.1.106.2	Signal flow for mains failure control	1553
19.1.106.3	Activating the mains failure control	1555
19.1.106.4	Parameterising the mains failure control	1556
19.1.106.5	Commissioning the mains failure control	1557
19.1.106.6	Fine adjustment of the mains failure control	1558
19.1.106.7	Reset mains failure control	1559
19.1.106.8	Restart protection	1559
19.1.106.9	Quick mains recovery (KU)	1559
19.1.107	L_MPot_1	1560
19.1.107.1	Activate & control motor potentiometer	1562
19.1.107.2	Deactivate motor potentiometer	1563
19.1.108	L_MulDiv_1	1564
19.1.109	L_MulDiv_2	1565
19.1.110	L_Mux_1	1566
19.1.111	L_Negation_1	1567
19.1.112	L_Negation_2	1568
19.1.113	L_NLim_1	1569
19.1.114	L_NLim_2	1572
19.1.115	L_Not_1	1574
19.1.116	L_Not_2	1574
19.1.117	L_Not_3	1575
19.1.118	L_Not_4	1575
19.1.119	L_Not_5	1576
19.1.120	L_Not_6	1576
19.1.121	L_Not_7	1577
19.1.122	L_NSet_1	1578
19.1.122.1	Main setpoint path	1582
19.1.122.2	JOG setpoints	1582
19.1.122.3	Setpoint inversion	1583
19.1.122.4	Value range of the input signal	1583
19.1.122.5	Skip frequency function	1583
19.1.122.6	Ramp function generator for the main setpoint	1585
19.1.122.7	S-shaped ramp	1587
19.1.122.8	Additional setpoint	1588
19.1.122.9	Application example for the additional load function	1588
19.1.123	L_Odometer_1	1589
19.1.124	L_OffsetGain_1	1591
19.1.125	L_OffsetGain_2	1592
19.1.126	L_OffsetGain_3	1593
19.1.127	L_OffsetGainP_1	1594
19.1.128	L_OffsetGainP_2	1595
19.1.129	L_OffsetGainP_3	1596
19.1.130	L_OffsetGainPhiP_1	1597
19.1.131	L_OffsetGainPhiP_2	1598
19.1.132	L_Or_1	1599
19.1.133	L_Or_2	1600
19.1.134	L_Or_3	1601
19.1.135	L_Or_4	1602

19.1.136	L_Or5_1	1603
19.1.137	L_Or5_2	1604
19.1.138	L_PCTRL_1	1605
19.1.138.1	Control characteristic	1609
19.1.138.2	Ramp function generator	1610
19.1.138.3	Operating range of the PID process controller	1610
19.1.138.4	Evaluation of the output signal	1611
19.1.138.5	Comparison function "Actual value = setpoint"	1611
19.1.138.6	Control functions	1612
19.1.139	L_PhaseDiff_1	1613
19.1.140	L_PhaseDiff_2	1614
19.1.141	L_PhaseIntK_1	1615
19.1.141.1	Function at constant input value	1616
19.1.141.2	Function at input value with sign reversal	1617
19.1.141.3	Calculation of the output signal	1618
19.1.142	L_PhaseIntK_2	1619
19.1.143	L_PhiAdd_1	1621
19.1.144	L_PhiDiv_1	1622
19.1.145	L_PhiIntegrator_1	1623
19.1.145.1	Function	1625
19.1.145.2	Example	1626
19.1.146	L_PosCtrlLin_1	1627
19.1.147	L_PosCtrlLin_2	1630
19.1.148	L_PosiShaftCtrlInterface_1	1633
19.1.149	L_ProcessCtrl_1	1634
19.1.149.1	Control characteristic	1636
19.1.150	L_PT1_1	1638
19.1.151	L_PT1_2	1639
19.1.152	L_PT1_3	1640
19.1.153	L_RLQ_1	1641
19.1.154	L_RSFlipFlop_1	1642
19.1.155	L_RSFlipFlop_2	1643
19.1.156	L_SampleHold_1	1644
19.1.157	L_SampleHold_2	1645
19.1.158	L_Sequencer_1	1646
19.1.158.1	Connection to the basic drive functions (MCK)	1651
19.1.158.2	Priorities of the control signals	1652
19.1.158.3	States of the sequencer	1653
19.1.158.4	Overview: Available action types	1654
19.1.158.5	Action type "Program end"	1655
19.1.158.6	Action type "positioning"	1656
19.1.158.7	Action type "switching"	1657
19.1.158.8	Action type "Branching"	1658
19.1.158.9	Action type "Variable branching"	1659
19.1.158.10	Action type "Homing"	1660
19.1.158.11	Action type "Time waiting"	1661
19.1.158.12	Action type "Counter setting"	1662
19.1.158.13	Action type "Counting"	1663
19.1.158.14	"Stand-by" action type	1664
19.1.158.15	Example: Sequence table	1665
19.1.159	L_SignalMonitor_a	1666
19.1.160	L_SignalMonitor_b	1667

Contents

19.1.161	L_SignalSwitch_1	1668
19.1.162	L_SignalSwitch_2	1669
19.1.163	L_SignalSwitch_3	1670
19.1.164	L_SignalSwitch_4	1671
19.1.165	L_SignalSwitch32_1	1672
19.1.166	L_SignalSwitch32_2	1673
19.1.167	L_SignalSwitch32_3	1674
19.1.168	L_SQrt_1	1675
19.1.169	L_SRFG_1	1676
19.1.170	L_SRFG_2	1678
19.1.171	L_SwitchPoint_1	1680
	19.1.171.1 Definition of the switching range	1682
	19.1.171.2 Dead time compensation	1683
	19.1.171.3 Switching hysteresis	1683
	19.1.171.4 Position/time-based cams	1684
19.1.172	L_SwitchPointPar_1	1685
19.1.173	L_Transient_1	1688
	19.1.173.1 Function 0: Evaluate rising signal edges	1689
	19.1.173.2 Function 1: Evaluate falling signal edges	1689
	19.1.173.3 Function 2: Evaluate rising and falling signal edges	1690
19.1.174	L_Transient_2	1691
19.1.175	L_Transient_3	1692
19.1.176	L_Transient_4	1693
19.1.177	L_Transient_5	1694
19.1.178	L_Transient_6	1695
19.1.179	L_Transient_7	1696
19.1.180	L_Transient_8	1697
19.2	System blocks	1698
19.2.1	LS_AnalogInput	1700
19.2.2	LS_AnalogOutput	1700
19.2.3	LS_AxisBusAux	1700
19.2.4	LS_AxisBusIn	1700
19.2.5	LS_AxisBusIO	1700
19.2.6	LS_AxisBusOut	1701
19.2.7	LS_CANManagement	1701
19.2.8	LS_DataAccess	1701
19.2.9	LS_DeviceMonitor	1701
19.2.10	LS_DFOut	1701
19.2.11	LS_DigitalInput	1702
19.2.12	LS_DigitalOutput	1702
19.2.13	LS_DisFree	1702
19.2.14	LS_DisFree_a	1703
	19.2.14.1 Display of internal process variables in application units	1704
19.2.15	LS_DisFree_b	1705
19.2.16	LS_DisFree_p	1706
19.2.17	LS_DriveInterface	1706
19.2.18	LS_Keypad	1707
19.2.19	LS_MotionControlKernel	1708
19.2.20	LS_MotorInterface	1708
19.2.21	LS_MultiEncoder	1708

Contents

19.2.22	LS_ParFix	1709
19.2.23	LS_ParFree	1710
19.2.24	LS_ParFree_2	1711
19.2.25	LS_ParFree_a	1712
19.2.26	LS_ParFree_a_2	1713
19.2.27	LS_ParFree_b	1714
19.2.28	LS_ParFree_p	1715
19.2.29	LS_ParFree_v	1716
19.2.30	LS_ParFree_v_2	1717
19.2.31	LS_ParFree32	1718
19.2.32	LS_ParFreeUnit	1719
19.2.33	LS_ParFreeUnit_2	1720
19.2.34	LS_ParReadWrite_1-6	1721
19.2.34.1	Arithmetic function	1724
19.2.35	LS_PulseGenerator	1725
19.2.36	LS_Resolver	1726
19.2.37	LS_RetainData	1727
19.2.38	LS_SetError_1	1729
19.2.39	LS_SetError_2	1729
19.2.40	LS_SyncManagement	1729
19.2.41	LS_TouchProbe	1729
19.2.42	LS_WriteParamList	1729
Index		1730
Your opinion is important to us		1758

1 About this documentation

1.1 Document history

1 About this documentation



Danger!

The controller is a source of danger which may lead to death or severe injury of persons.

To protect yourself and others against these dangers, observe the safety instructions before switching on the controller.

Please read the safety instructions provided in the **8400 mounting instructions** and in the **8400 hardware manual**. Both documents are supplied with the controller.

Target group

This documentation addresses to all persons who would like to parameterise, configure and diagnose the 8400 TopLine with the Lenze engineering software »Engineer« and the X400 keypad.

Validity

The information in this documentation are valid for the following standard devices:

Product series	Type designation	from software version
8400 TopLine C	E84AVTCxxxxx	01.00

Screenshots/application examples

All screenshots provided in this documentation are application examples. Depending on the software version of the controller and the version of the installed »Engineer« software, the screenshots in this documentation may differ from the representation in the »Engineer«.



Tip!

Information and tools for Lenze products are provided in the download area at

<http://www.lenze.com> → Download



1.1 Document history

Version			Description
6.0	06/2014	TD05	Extended by new functions for 8400 TopLine C V15.00.00
5.0	11/2013	TD05	Extended by new functions for 8400 TopLine C V14.00.00
4.1	01/2013	TD05	Error corrections & supplements
4.0	11/2012	TD05	Extended by new functions for 8400 TopLine C V13.00.00 and converted to new layout.
3.1	09/2012	TD05	Error corrections & supplements
3.0	07/2012	TD05	Extended by new functions for 8400 TopLine C V12.00.00
2.0	08/2011	TD05	Extended by new functions for 8400 TopLine C V02.00.00

1.2

Conventions used

This documentation uses the following conventions to distinguish between different types of information:








Type of information	Writing	Examples/notes
Spelling of numbers		
Decimal separator	Point	The decimal point is generally used. Example: 1234.56
Hexadecimal number	0x	For hexadecimal numbers, the "0x" prefix is used. Example: 0x60F4
Binary number	0b	For binary numbers, the "0b" prefix is used. Example: 0b00010111
Text		
Version info	Blue text colour	All information that only applies to a certain controller software version or higher is identified accordingly in this documentation. Example: This function extension is available from software version V3.0!
Program name	» «	The Lenze »Engineer« PC software ...
Window	<i>italics</i>	The <i>Message</i> window ... / The <i>Options</i> dialog box...
Variable identifier		By setting <i>bEnable</i> to TRUE...
Control element	bold	The OK button... / The Copy command... / The Properties tab... / The Name input field...
Sequence of menu commands		If the execution of a function requires several commands, the individual commands are separated by an arrow: Select File→Open to...
Shortcut	<bold>	Press <F1> to open the online help.
		If a command requires a combination of keys, a "+" is placed between the key symbols: Use <Shift>+<ESC> to...
Hyperlink	<u>Underlined</u>	Optically highlighted reference to another topic. In this documentation activated by mouse-click.
Icons		
Page reference	 24	Optically highlighted reference to another page. In this documentation activated by mouse-click.
Step-by-step instructions		Step-by-step instructions are indicated by a pictograph.




All information that only applies to a certain controller software version or higher is identified accordingly in this documentation.

1 About this documentation

1.3 Terminology used

1.3 Terminology used

Term	Meaning
Engineering Tools	Software solutions for simple engineering at all stages
	 »EASY Navigator« – Ensures easy operator guidance <ul style="list-style-type: none">• All practical Lenze engineering tools at a glance• Tools can be selected quickly• Clearly arranged, simplifying the engineering process from the start
	 »EASY Starter« – Simple tool for service technicians <ul style="list-style-type: none">• Especially developed for the commissioning and maintenance of Lenze devices• Graphical user interface with few buttons• Simple online diagnostics, parameterisation and commissioning• No risk of accidentally changing the application• Ready applications can be loaded to the device
	 »Engineer« – Multi-device engineering <ul style="list-style-type: none">• For all products from our L-force portfolio• Practice-oriented user interface• Easy handling due to graphical user interfaces• Suitable for all project stages (configuration, commissioning, production)• Parameter setting and configuration
Application block	Block for a technology application (e.g. actuating drive speed) A technology application is a drive solution based on the experience and know-how of Lenze in which function blocks interconnected to a signal flow form the basis for implementing typical drive tasks.
ASM	Abbreviation for asynchronous motor
CAN	Abbreviation for Controller Area Network. CAN is an asynchronous, serial fieldbus system.
	CANopen® is a communication protocol based on CAN. The Lenze system bus (CAN on board) operates with a subset of this communication protocol. CANopen® is a registered community trademark of the CAN user organisation CiA® (CAN in Automation e. V.). ► System bus "CAN on board"
Code	Parameter used for controller parameterisation or monitoring. The term is usually called "index".
Display code	Parameter that displays the current status or value of an input/output of a system block.
Emergency brake	The emergency brake serves to shutdown rotary or translatory masses in motion in emergency situations. Emergency situations are exceptional situations that only occur sporadically.
	EtherCAT® is a real-time capable Ethernet system with maximum performanc. EtherCAT® is a registered trademark and patented technology, licensed by the Beckhoff Automation GmbH, Germany.
	Ethernet POWERLINK is a real-time capable fieldbus system based on Ethernet. For user data exchange, Ethernet POWERLINK specifies a communication protocol based on CANopen. Ethernet POWERLINK is a patented technology licensed by the Ethernet POWERLINK Standardization Group (EPSCG), Germany.
	EtherNet/IP™ (EtherNet Industrial Protocol) is a fieldbus system based on Ethernet which uses the Common Industrial Protocol™ (CIP™) for data exchange. EtherNet/IP™ and Common Industrial Protocol™ (CIP™) are trademarks and patented technologies licensed by the user organisation ODVA (Open DeviceNet Vendor Association), USA.
FB Editor	Abbreviation for function block editor. Graphic interconnection tool which is available in the »Engineer« for function block interconnections on the FB Editor . ► Working with the FB Editor

Term	Meaning
Function block	General designation of a function block for free interconnection in the FB Editor. A function block (short: FB) can be compared with an integrated circuit that contains a specific control logic and delivers one or several values when being executed. Example: "L_Arithmetik_1" (FB for arithmetic operations) Many function block are available several times (e.g. L_And_1, L_And_2 and L_And_3). ► Function blocks
Holding brake	The holding brake serves to statically hold e.g. a position during the downtimes of a robot/travelling/synchronous/hoist drive.
HIPERFACE®	HIPERFACE® stands for High Performance Interface and is a universal interface between motor feedback system and controller. HIPERFACE® is a registered trademark of the SICK STEGMANN GmbH.
	INTERBUS was developed as sensor/actuator/bus system for transmitting process data. Today, maintenance activities for the INTERBUS technologies are carried out by the user organisation PROFIBUS & PROFINET International (PI).
Keypad	The keypad is an alternative to the PC for the local operation, parameterisation, and diagnostics in a simple manner.
LA	Abbreviation for Lenze Application block Example: "LA_NCtrl" (block for the "Actuating drive speed" application)
Lenze setting	This setting is the default factory setting of the device.
LP	Abbreviation for Lenze Port block Example: "LP_CanIn1" (CAN1 port block)
LS	Abbreviation for Lenze System block Example: "LS_DigitalInput" (system block for digital input signals)
MCI	Abbreviation for Motionbus Communication Interface (fieldbus interface) The Inverter Drives 8400 can accommodate plug-in communication modules and can therefore take part in the data transfer of an existing fieldbus system. ► Fieldbus interface (MCI)
Port block	Block for implementing the process data transfer via a fieldbus
	PROFIBUS® (Process Field Bus) is fieldbus system used worldwide for automating machines and production plants. PROFIBUS® is a registered trademark and patented technology licensed by the user organisation PROFIBUS & PROFINET International (PI).
	PROFINET® (Process Field Network) is a real-time capable fieldbus system based on Ethernet. PROFINET® is a registered trademark and patented technology licensed by the user organisation PROFIBUS & PROFINET International (PI).
PSM	Abbreviation for permanently excited synchronous motor
QSP	Abbreviation for quick stop
SC	Abbreviation for Servo Control
Service brake	The service brake serves to shutdown rotary or translatory masses in motion in a controlled manner. The energy to be dissipated in this process is produced in the form of friction energy. Unlike emergency braking, this process is a regular and recurring operating mode.
SLPSM	Abbreviation for sensorless control of synchronous motors
SLVC	Abbreviation for SensorLess Vector Control
SSI	Abbreviation for Synchronous Serial Interface Interface for absolute angle encoders developed by SICK STEGMANN GmbH.
Subcode	If a code contains several parameters, these are stored in "subcodes". This Manual uses a slash "/" as a separator between code and subcode (e.g. "C00118/3"). The term is usually called "subindex".
System block	System blocks provide interfaces to basic functions, to "free codes" and to the hardware of the controller in the FB editor of the »Engineer« (e.g. to the digital inputs). Each system block is only available once. ► System blocks

Term	Meaning
USB diagnostic adapter	The USB diagnostic adapter is used for the operation, parameterisation, and diagnostics of the controller. Data are exchanged between the PC (USB connection) and the controller (diagnostic interface on the front) via the diagnostic adapter. Order designation: E94AZCUS
VFCplus	Abbreviation for Voltage Frequency Control

1.4

Definition of the notes used

The following signal words and symbols are used in this documentation to indicate dangers and important information:

Safety instructions

Layout of the safety instructions:

**Pictograph and signal word!**

(characterise the type and severity of danger)

Note

(describes the danger and gives information about how to prevent dangerous situations)

Pictograph	Signal word	Meaning
	Danger!	Danger of personal injury through dangerous electrical voltage Reference to an imminent danger that may result in death or serious personal injury if the corresponding measures are not taken.
	Danger!	Danger of personal injury through a general source of danger Reference to an imminent danger that may result in death or serious personal injury if the corresponding measures are not taken.
	Stop!	Danger of property damage Reference to a possible danger that may result in property damage if the corresponding measures are not taken.

Application notes

Pictograph	Signal word	Meaning
	Note!	Important note to ensure trouble-free operation
	Tip!	Useful tip for easy handling

2 Introduction: Parameterising the controller

Being a component of a machine which includes a speed-variable drive system, the controller needs to be adjusted to its drive task. The controller is adjusted by changing parameters which are saved in the memory module. The parameters can be accessed by keypad, by the »EASY Starter« or by the »Engineer«. Access is also possible by a master control via fieldbus communication. For this purpose, the "CAN on board" CAN interface and the MCI interface for using a communication module (e.g. PROFIBUS) are available.

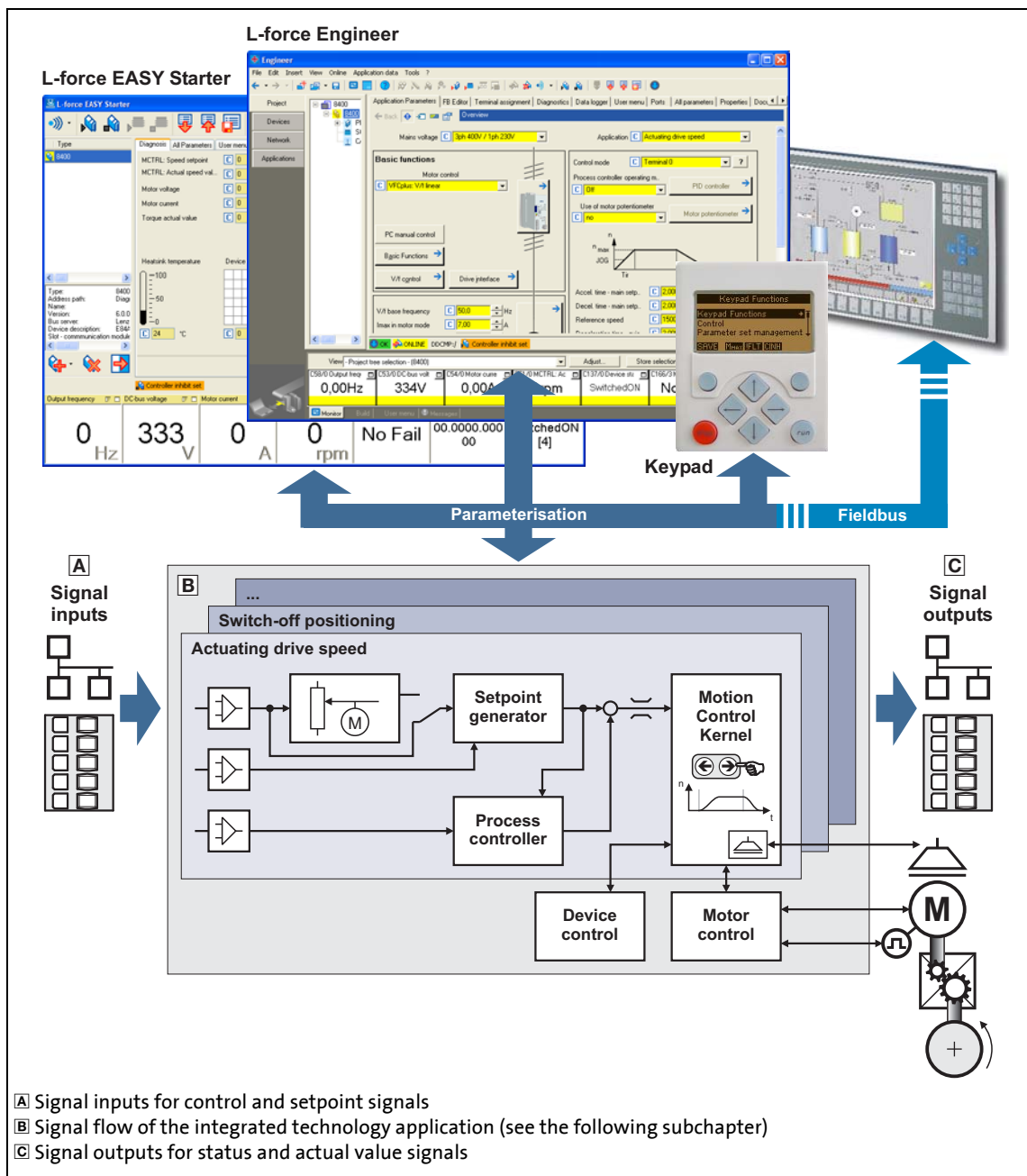


Danger!

In general, changing a parameter causes an immediate response in the controller!

An enabled controller can cause an unwanted behaviour at the motor shaft! For instance, setpoint sources can change over abruptly (e.g. when the signal source is configured for the main setpoint).

Certain device commands or settings which may cause critical states of drive behaviour constitute exceptions. Such parameter changes are only possible if the controller is inhibited. Otherwise, a corresponding error message will be issued.



[2-1] Adaptation of the drive solution via parameter setting

2.1 Integrated technology applications

The following technology applications integrated in the drive controller 8400 TopLine provide the main signal flow for the implementation of a general or a special drive solution:



Technology application "Actuating drive speed"

This preset technology application serves to solve speed-controlled drive tasks, e.g. conveyor drives (interconnected), extruders, test benches, vibrators, travelling drives, presses, machining systems, metering units.



technology application "Actuating drive speed (AC Drive Profile)"

This technology application available [from version 13.00.00](#) provides a speed and torque control by means of "AC Drive Profile". The fieldbuses EtherNet/IP™ and system bus (CANopen) are supported.



Technology application "Table positioning"

This technology application serves to solve position-controlled drive tasks which are normally controlled by a higher-level control via a fieldbus, e.g. transport facilities, rotary tables, storage and retrieval units, feed drives, metering units, hoists.

Note: This TA requires an external sequence control!

[From version 12.00.00](#), the FB [L_Sequencer 1](#) can also be used as internal sequence control. This FB processes a positioning program based on a sequence table.



"Switch-off positioning" technology application

This technology application is used to solve speed-controlled drive tasks which require a pre-switch off or stopping at certain positions, e.g. roller conveyors and conveying belts. The pre-switch off is implemented by connecting switch-off sensors.



Note!

Please note that the "StateLine", "HighLine" and "TopLine" device types differ with regard to the number, functional range, and flexibility of the technology applications offered.



Detailed information on each technology application can be found in the main chapter ["Technology applications"](#). (428)

2.1.1 Purpose of the technology applications

The stepped Inverter Drives 8400 series provides solutions for simple to complex applications – depending on the user's experience and knowledge about the handling of drives and drive tasks.

On the one hand, a great scope of standard drive tasks for frequency inverters is covered by the technology applications offered by Lenze, and on the other hand, the user is relieved from time-consuming programming activities. In practice, some drive tasks are alike so that minor modifications of the corresponding technology applications lead to quick results.

Other important features of technology applications are:

- Direct implementation of drive tasks without recreating a function block interconnection inside the device
- Operation via keypad and/or operation via convenient operator dialogs in the «Engineer».
- Commissioning via few operating and diagnosing parameters (local keypad operation).
- Achieving a transparency as high as possible via the integrated functionality of the device by representing signal flow diagrams.
- Provision of a basic functionality suitable and often sufficient for many applications.

2.1.2 Application cases for a technology application

You should use a technology application if

- the task can be solved completely or to a great extent by the basic functionality of the technology application.
- the end customer does not want to create the comprehensive core functions of the corresponding technology on his own.
- the creation time for a project is to be reduced by using the ready-made technology application
- the end customer wants to build upon the know-how of Lenze.



Tip!

If the end customer of the machine does not want to use ready-made Lenze functions, it is also possible to implement individual drive solutions with the "StateLine C", "HighLine C" and "TopLine C" versions in the form of "free interconnections". (In case of "StateLine C2, free interconnection is only possible from version 12.00.00 and »Engineer« V2.17.)

Here, a technology application can be used as starting basis, which has to be adapted to the requirement by a change or extension via function block editor (see the following chapter).

2.1.3 Technology application = function block interconnection

In case of the 8400 device version, each technology application is connected to a "function block interconnection" ("FB interconnection"). This FB interconnections serve to implement signal interconnections. Various FBs are available for digital signal processing, signal conversion and logic modules.

For special drive tasks it has proved of value to use the integrated technology applications as a basis for modifications or extensions of the available FB interconnections.

I/O level & application level

The interconnection of the interfaces is shown in the I/O level of the function block editor according to the selected control mode. In the "deeper" application level, the main signal flow is realised in the form of an interconnection of various function and system blocks.

For the device versions "StateLine C", "HighLine C" and "TopLine C" the following applies:

- The preconfigured signal links can be reconfigured in the I/O level if required.
- Moreover, applications integrated in the controller can be reconfigured in the application level and extended by individual functions.
- Moreover, experienced users are offered the opportunity to implement their own drive solutions independent of the predefined technology applications by using so-called "free interconnections". (In case of "StateLine C", free interconnection is only possible from version 12.00.00 and »Engineer« V2.17.)

Motion Control Kernel

Important basic (drive) functions as well as further basic functionalities are implemented in the firmware of the drive controller in the so-called **Motion Control Kernel** (MCK) which can be accessed by the active technology application via defined internal interfaces. By this means the expensive creation of single function block interconnections is omitted so that the expenditure and the complexity for the realisation of standard functions is minimised.

The **Motion Control Kernel** is integrated in the main setpoint path and, depending on the set operating mode, it creates the required control and setpoint signals for the motor control and the drive interface.



More detailed information:

- A detailed description of the basic functions implemented in the **Motion Control Kernel** can be found in the main chapter "[Basic drive functions \(MCK\)](#)". (📖 552)
- Detailed information on the creation or change of interconnections by means of the function block editor can be found in the main chapter "[Working with the FB Editor](#)". (📖 1329)
- All available function and system blocks are described in the main chapter "[Function library](#)". (📖 1381)

2.2 Selection of the appropriate commissioning tool

There are several possibilities for commissioning the 8400 TopLine controller:



Commissioning via keypad X400 (or diagnosis terminal X400)

The keypad is an alternative to the PC for the local operation, parameterisation, and diagnostics in a simple manner. The keypad is especially suited for test and demonstration purposes and for the case that only few parameters have to be adapted.



Commissioning using PC and »EASY Starter«

The »EASY Starter« is a Lenze tool for simple online diagnostics, parameterisation and commissioning of the controller.



Commissioning using PC and »Engineer«

The »Engineer« is a Lenze engineering software for parameter setting across all devices, configuring and diagnosing individual components (as for instance controllers, industrial PCs, motors, I/O systems) and machine control systems.






Tip!

The engineering tools »EASY Starter« and »Engineer StateLevel« are provided free of charge in the internet:

<http://www.lenze.com> → Download → Software Downloads

For communication between PC and controller, the USB diagnostic adapter can be used for instance (see the following subchapter).

2.2.1 Overview: Accessories for commissioning

Version	Features	Product key
Keypad X400 	Quick access to parameters and operating data <ul style="list-style-type: none"> • Supports hot plugging • Graphic display with plain texts • Backlighting • Easy user guidance • 4 navigation keys, 2 context-sensitive keys • Adjustable RUN/STOP function • Can be used for L-force Inverter Drives 8400 and Servo Drives 9400 	EZAEBK1001
Diagnosis terminal X400 	Keypad X400 in a robust housing, also suitable for installation into the control cabinet door. <ul style="list-style-type: none"> • Supports hot plugging • Graphic display with plain texts • Backlighting • Easy user guidance • 4 navigation keys, 2 context-sensitive keys • Adjustable RUN/STOP function • Incl. 2.5 m cable • Enclosure IP20; in case of front installation in control cabinet IP65 • Can be used for L-force Inverter Drives 8400 and Servo Drives 9400 	EZAEBK2001
USB diagnostic adapter 	For electrical isolation of your PC and the controller. <ul style="list-style-type: none"> • Supports hot plugging • Diagnostic LED for data transfer display • plug and play • Input-side voltage supply via USB connection from PC • Output-side voltage supply via the diagnostic interface of the controller • Connecting cables can be selected in various lengths: 	E94AZCUS
Connecting cable for USB diagnostic adapter	2.5 m length	EWL0070
	5 m length	EWL0071
	10 m length	EWL0072

2.3**General notes on parameters**

All parameters for controller parameterising or monitoring are saved as so-called "codes".

- The codes are numbered and indicated by the prefix "C" before the code, e.g. "C00002".
- Moreover, each code has a name and specific attributes, as for example access type (reading, writing), data type, limit values and default setting ("Lenze setting").
- For the sake of clarity, some codes contain "subcodes" for saving parameters. This Manual uses a slash "/" as a separator between code and subcode, e.g. C00118/3".
- According to their functionality, the parameters are divided into three groups:
 - Setting parameters: For specifying setpoints and for setting device / monitoring functions.
 - Configuration parameters: For configuring signal connections and terminal assignments.
 - Diagnostic/display parameters: For displaying device-internal process factors, current actual values and status messages. These are read-only parameters.

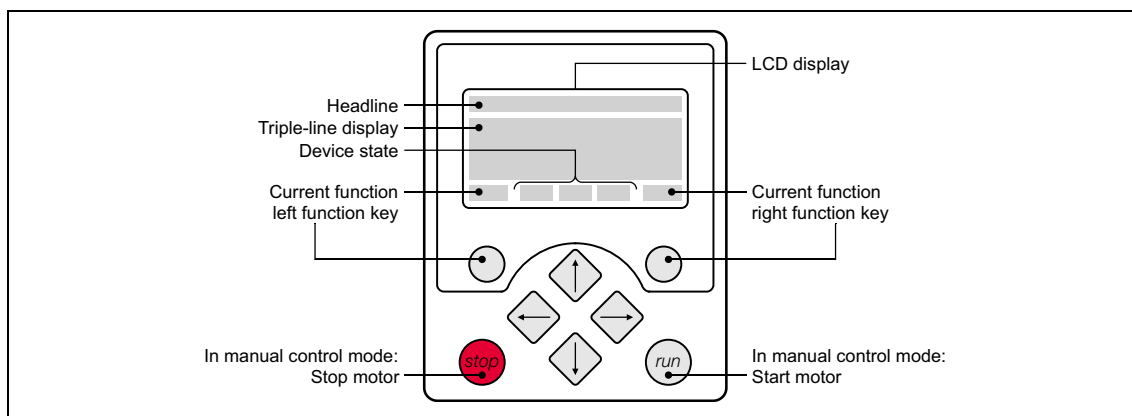
2.3.1 Changing the parameterisation with the keypad



The keypad is simply plugged on the diagnostic interface X6 ("DIAG") at the front of the standard device.

Plugging and unplugging the keypad is possible during operation.

Keypad display and control elements



LCD display

Headline

In the menu level: Menu name

In the parameter level: Parameter name







Three-part display








In the menu level: List of available menus

In the parameter level: Code/subcode and setting or actual value

Device status

RDY	Controller is switched on	IMP	Pulse inhibit active
RUN	Controller is enabled	ISFLT	System fault active
CINH	Controller is inhibited	IFLT	"Fault" device status is active
QSP	Quick stop active	ITRB	"Trouble" device status is active
Imax	Current limit exceeded	ITOSP	"TroubleQSP" device status is active
Mmax	Speed controller 1 in the limitation	WRN	A warning is indicated

LCD display			
Function - left function key		Function - right function key	
	Change parameter setting (change to editing mode)		Accept change in the controller (no saving with mains failure protection → SAVE)
	Back to main menu		Abort (discard change)
	Parameter can only be changed when the controller is inhibited		
	Save all parameter settings in the memory module safe against mains failure		

Control elements	
	Execute the function assigned to the function key (see LCD display)
	Execute the stop function set in C00469 (Lenze setting: Inhibit controller)
	Deactivate stop function again (Lenze setting: Enable controller again)
	In the menu level: Select menu/submenu In the parameter level: Select parameter
	In the editing mode: Change marked digits or select list entry
	In the menu level: Select submenu/change to parameter level In the editing mode: Cursor to the right
	In the menu level: One menu level higher (if available) In the parameter level: Back to the menu level In the editing mode: Cursor to the left

Menu structure

In the keypad, the parameters are classified into various menus and submenus.

- The **USER menu** includes a selection of frequently used parameters.
- The **Code list** contains all parameters.
- The **Go to param** function enables you to reach the corresponding parameter directly.
- The **Logbook** logs all errors and their chronological history.
- The **Diagnostics** menu contains diagnostic/display parameters for displaying device-internal process factors, current actual values and status messages.

Userlevel

From version **12.00.00 onwards**, the extent of menus, submenus and codes shown in the keypad can be adapted by selecting the "Userlevel" in [C00001/1](#):

- Userlevel **Standard** (Lenze setting): Only the most important menus and codes are shown in the keypad.
- Userlevel **Expert**: All menus and codes are shown in the keypad.
- Userlevel **Service**: For service purposes only (Lenze service).

When the Userlevel has been changed, the menus are restructured in the keypad according to the selected Userlevel. The parameters of a plugged in communication module are always displayed completely independent of the set Userlevel.

1. **Par1 8400 TopLine C**
USER - Menu
Code list →
Go To Param
SAVE









2. **Load Lenze setting**
C00002/001 →
Off / Finished
EDIT

3. **Fixed setpoint 1**
C00039/001 →
40.00 %
EDIT

4. **Fixed setpoint 2**
C00039/002 ↔
60.00 %
EDIT

5. **Fixed setpoint 2**
C00039/002
60.00 %
ESC **OK**

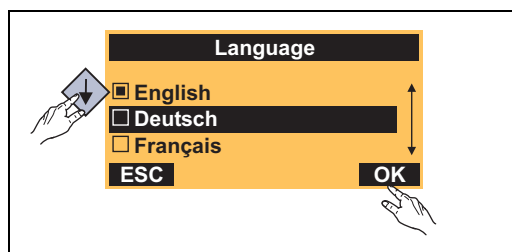
6.

1. Use the / navigation keys to select the desired menu.
 - Use the / navigation keys to reach a higher/lower menu level.
 - Use the  function key to return to the main menu.
2. Use the / navigation keys to select the parameter to be set within a submenu.
3. In order to select another subcode in case of a parameter with subcodes:
 - Press the navigation key  to change to the editing mode for the subcode.
 - Use the navigation keys to set the desired subcode.
4. Use the **EDIT** function key to switch over to the editing mode.
5. Use the navigation keys to set the desired value.
6. Use the **OK** function key to accept the change and to leave the editing mode.
 - Use the **ESC** function key to leave the editing mode without accepting the change.

[2-2] Example: Changing parameters with the keypad

All texts displayed in the keypad are in English.

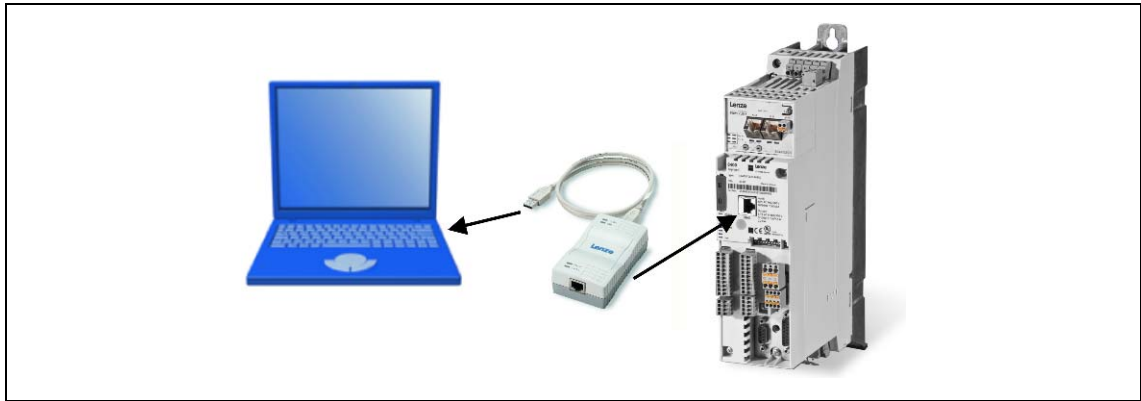
From version 02.00.00 onwards, the most important menus as well as diagnostic and configuration parameters can also be available in German and French. To set a different language, select the **Language selection** menu item in the main menu of the keypad.



- The multilingual texts are stored in the controller and do not have to be loaded into the device.
- For reasons of disc space, only the most important menus and parameters as well as the error messages are available in several languages.

2.3.2 Change parameter settings with PC and Lenze software

The USB diagnostic adapter, for instance, can be used for the communication between the PC (including the »Engineer« software) and the controller, see the following illustration. The USB diagnostic adapter is the connection between the PC (free USB port) and the controller (X6 diagnostic interface).



[2-3] Exemplary constellation for parameterising the controller

The **All parameters** tab in the »EASY Starter« and the »Engineer« provides a quick access to all parameters of the controller.

The given categories and subcategories correspond 1:1 to the menus and submenus of the keypad:

	C...	S...	Name	Value	Unit
2	1		Load Lenze setting	Off / ready	
2	6		Load all parameter sets	Off / ready	
2	19		Reset error	Off / ready	
5	0		Application	Actuating drive speed	
7	0		Control mode	Terminal 0	
10	1		AIN1: (+y0) = min	0,00	%
10	3		AIN1: (-y0) = (-min)	0,00	%
11	0		Appl.: Reference speed	1500	rpm
12	0		Accel. time - main setpoint	2,000	s
13	0		Decel. time - main setpoint	2,000	s
15	0		VEC: V/f base frequency	50,0	Hz

[A] Category
 [B] Subcategories

[2-4] All parameters tab in the »Engineer«

Moreover, the »Engineer« provides a commissioning interface on the **Application parameters** tab where you can commission the application in a few steps.



Detailed information on how to handle the »Engineer« can be found in the integrated online help that you can call with the [F1] function key.


2.3.3 Save parameter settings in the memory module safe against mains failure

Controller parameter changes via the EASY Starter / »Engineer«, the keypad, or a master control via fieldbus communication will be lost after mains switching of the controller unless the settings have been explicitly saved to the integrated memory module.

General information

- In the delivery state, the Lenze setting of the parameters has been saved to the integrated memory module. These parameters are
 - the parameters of the controller
 - the parameters of the communication module plugged into the MCI interface
 - the parameters of the possibly existing safety module (device variant)
- When the device or the external 24 V voltage supply is switched on, all parameters are automatically loaded from the memory module into the main memory of the controller.
- Full functionality of the memory module is even provided if the power supply has been switched off and only the electronic components of the controller are externally supplied by a 24 V DC voltage, e.g. via the X4/24E terminal.
- The memory module can be preconfigured with customised data.
- The memory module is available as a spare part - without any data.

During operation

- Parameter sets can be saved and loaded manually.
- Using the keypad, you can press function key **SAVE** to save the parameter settings.
- The »EASY Starter«/»Engineer« serves to execute the saving via the icon  in the *toolbar* or via the device command "Save all parameter sets" ([C00002/11](#) = "1: On / start").
 - The storage process may take a couple of seconds. After the device command has been called in [C00002/11](#), dynamic status information ("Work in progress 20%" → "Work in progress 40%" → "Work in progress 60%", etc.) is returned.



Note!

In order to prevent data inconsistencies during the saving process:

- Do not switch off the supply voltage!
- Do not remove the memory module from the device!

Automatic saving of changed parameter settings is explicitly not supported because this significantly reduces the service life of the memory module.

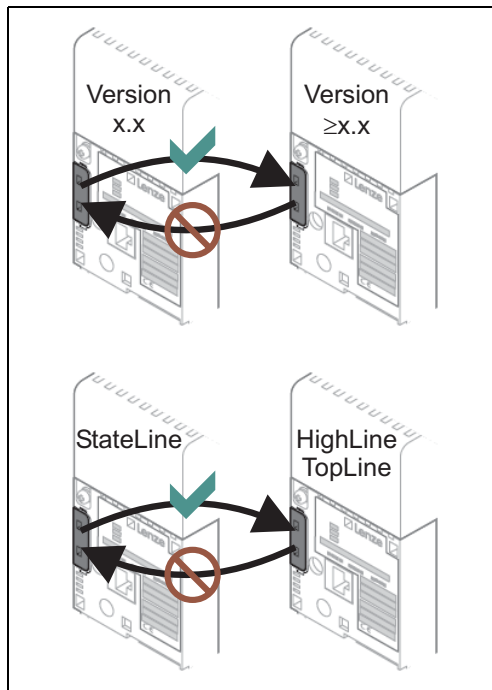
Unplugging the memory module

The memory module is hot-pluggable. A removal during operation causes a warning "[PS01: No memory module](#)" and should thus be avoided. The behaviour of the device, however, remains unchanged as all parameters are available in the RAM memory after the device has been started. The device can also be parameterised when the memory module has been unplugged. In this case, the parameter sets cannot be saved in the memory module.

Replacing the controller

In the event of a device replacement, the entire parameter data of an axis can be copied to the replacement device by "taking along" the memory module, so that additional PC or keypad operations are not required.

When replacing the controller, the versions of the old device and the new device are of importance. Before data are actually transferred, the versions are internally checked. Basically, the following applies:



- Parameter sets of old devices can only be processed on new devices with the same or higher device version (downward compatibility).
- Parameter sets of devices with versions that have less functions (e.g. 8400 StateLine) can be loaded into and executed on devices with versions that have more functions (e.g. 8400 HighLine). The reverse is not possible!
- If the parameter set saved in the memory module is not compatible with the standard device, the "[PS03: Par.set device invalid](#)" is output.

2.3.4 User menu for quick access to frequently used parameters

When a system is installed, parameters must be changed time and again until the system runs satisfactorily. The user menu of the controller contains a selection of frequently used parameters to be able to access and change these parameters quickly:

Parameter	Name	Lenze setting
C00051	MCTRL: Actual speed value	-
C00053	DC-bus voltage	-
C00054	Motor current	-
C00061	Heatsink temperature	-
C00137	Device status	-
C00166/3	Mess. - status det. error	-
C00011	Appl.: Reference speed	1500 rpm
C00039/1	Fixed setpoint 1	40.00 %
C00039/2	Fixed setpoint 2	60.00 %
C00012	Acceleration time - main setpoint	2.000 s
C00013	Deceleration time - main setpoint	2.000 s
C00015	VFC: V/f base frequency	50 Hz
C00016	VFC: Vmin boost	1.60 %
C00022	I _{max} in motor mode	depending on the device power
C00120	Setting of motor overload (I ² xt)	100.00 %
C00087	Rated motor speed	1460 rpm
C00099	Firmware version	-
C00200	Firmware product type	-
C00105	Decel. time - quick stop	2.000 s
C00173	Mains voltage	0: "3ph 400V / 1ph 230V"
Highlighted in grey = display parameter		



Tip!

The user menu can be freely configured in [C00517](#).

In the »Engineer«, you can configure the user menu comfortably via the **User menu** tab (see »Engineer« online help).

The [password protection](#) serves to restrict the access to parameters of the user menu. Then, all other parameters cannot be accessed without knowing the password and are thus protected against unwanted changes.

2.4 Device access protection

Various tasks can be executed via the functions of the device access protection:

- [Password protection](#)
 - Only authorised persons (with password knowledge) may read/change all parameters of the controller.
 - Non-authorised persons (without password knowledge) can only access the max. 32 parameters of the user menu.
- [Device personalisation](#)
 - Only controller personalised with a specific binding ID and memory modules can be used in the system.



Note!

If password protection/device personalisation is used:

- Inform the end customer that Lenze can only provide restricted service for the devices with access protection.
- It is not possible for Lenze to modify a replacement device via special accesses in such a way that it cooperates with a personalised memory module.
- The keypad does not support the alpha-numeric entry of a password, thus the keypad cannot be used for entry.

2.4.1 Password protection

When the password protection is active, only write/read access to the parameters of the user menu is possible.

- From version 15.00.00, the password protection can be configured individually for every single communication channel. ▶ [Individual password protection for single communication channels](#) (46)
- The following describes how to set/check/delete a password by means of the parameters relevant for these functions.
- From »Engineer« V2.14 onwards, these functions can also be executed via dialog (menu command **Online → Set/check/delete password**).



Note!

The password protection serves to only limit the access to parameters of the standard device. The access to parameters of a plugged-in communication module is not concerned.

Short overview of the relevant parameters for password protection:

Parameter	Info	Lenze setting						
C00505/3	<p>Password</p> <ul style="list-style-type: none">• The password must have a length of 4 ... 16 characters.• The password may consist of any character. However, this is not sensible. Recommended characters are: lower case letters (a - z), upper case letters (A - Z) and digits (0 - 9). <p>Note: After the execution of one of the device commands listed below, this parameter returns the current password status:</p> <table><tr><td>off</td><td>No password is set, password protection is not active (Lenze delivery status).</td></tr><tr><td>on</td><td>Password is set, password protection is active.<ul style="list-style-type: none">• This status is also displayed if checking/deleting the password has not been successful due to an invalid entry.</td></tr><tr><td>ok</td><td>Password is set, password protection is not active.<ul style="list-style-type: none">• The password protection is temporarily deactivated.</td></tr></table>	off	No password is set, password protection is not active (Lenze delivery status).	on	Password is set, password protection is active. <ul style="list-style-type: none">• This status is also displayed if checking/deleting the password has not been successful due to an invalid entry.	ok	Password is set, password protection is not active. <ul style="list-style-type: none">• The password protection is temporarily deactivated.	
off	No password is set, password protection is not active (Lenze delivery status).							
on	Password is set, password protection is active. <ul style="list-style-type: none">• This status is also displayed if checking/deleting the password has not been successful due to an invalid entry.							
ok	Password is set, password protection is not active. <ul style="list-style-type: none">• The password protection is temporarily deactivated.							
Device commands Before the following device commands are executed, enter the corresponding password in C00505/3 .								
C00002/31	Set password ▶ Activate the password protection	0: Off / ready						
C00002/32	Check password ▶ Temporarily deactivate the password protection	0: Off / ready						
C00002/33	Delete password ▶ Deactivate password protection/change password	0: Off / ready						
Highlighted in grey = display parameter								

Parameter	Info	Lenze setting	
Status displays			
C00003	Status of the last device command	-	
C00507/1	Password protection - all communication channels <ul style="list-style-type: none">• Bit coded display of the active protective functions:	-	
	Bit 0		Only access to user menu
	Bit 1		Parameter write protection
	Bit 2		Parameter read protection
	Bit 3 ... 14		Reserved
	Bit 15		Memory module binding on
	Note: As the password protection can be configured individually for each single communication channel from version 15.00.00 bit 1 and bit 2 indicate the active protection always with regard to the communication channel used .		
Highlighted in grey = display parameter			

Activate the password protection

The password protection is activated by setting a password.



How to set a password:

- Enter the desired password in [C00505/3](#).
 - The password must have a length of 4 ... 16 characters.
 - The password may consist of any character. However, this is not sensible. Recommended characters are: lower case letters (a - z), upper case letters (A - Z) and digits (0 - 9).
- Execute "Set password" device command: [C00002/31](#) = "1: On / start"
 - After successful execution, password status ON is displayed in [C00505/3](#) and password protection takes immediate effect.

Temporarily deactivate the password protection

The "Check password" device command serves to temporarily deactivate the password protection in order to execute password-protected functions.

- The password protection remains deactivated until
 - an invalid password will be entered and checked
 - or -
 - the external 24-V supply of the control electronics is switched off (< 19 V).



How to temporarily deactivate the active password protection:

- Enter the set password in [C00505/3](#).
- Execute "Check password" device command [C00002/32](#) = "1: On / start"
 - After a successful check, password status OK is displayed in [C00505/3](#).

Deactivate password protection/change password

The password protection is simply activated by deleting the set password. If you want to change the set password, first delete the set password as well. Then set the new password.



How to delete the set password:

1. Enter the set password in [C00505/3](#).
2. Execute "Delete password" device command [C00002/33](#) = "1: On / start"
 - After a successful deletion, password status OFF is displayed in [C00505/3](#).

2.4.2 Individual password protection for single communication channels

This function extension is available from version 15.00.00!

The 8400 TopLine can be parameterised via the following "communication channels":

- Internally via system blocks ([LS_ParReadWrite1-6](#) and [LS_WriteParamList](#))
- externally via
 - Diagnostics interface X6 ("DIAG")
 - CANopen interface X1 ("CAN on board")
 - Fieldbus interface (MCI)

As in some applications, only certain communication channels have to be protected, the parameters described in the following serve to configure individual access restrictions for each communication channel.

In the Lenze setting, all access restrictions are active for all communication channels when the password is set. This corresponds to the previous behaviour with a set password, i.e. only one write/read access to the parameters of the user menu is possible.



Note!

The configuration can only be changed if no password has been set!

- This means that even if the password has been deactivated temporarily by the "check password" device command, the configuration cannot be changed.
- As long as a password is set, the "Load Lenze setting" device command does not change the configuration either.

The password protection is activated by setting a password.

▶ [Activate the password protection](#) (📖 45)

▶ [Deactivate password protection/change password](#) (📖 46)

Short overview of the relevant parameters for configuring the password protection:

When the password is set, the respective restriction is active if the corresponding bit has been set:

Parameter	Info	Lenze setting
C00506/1	PW protection internal config	0x0007
	Bit 0 Only access to user menu • The menus in the keypad are reduced. • Only the user menu can be used to change parameters.	
	Bit 1 Parameter write protection • System blocks cannot be used to write into write/read parameters.	
	Bit 2 Parameter read protection • System blocks cannot be used to read write/read parameters.	
	Bit 3 ... 15 Reserved	
C00508/1	PW protection config. X6 (DIAG)	0x0006
	Bit 0 Reserved	
	Bit 1 Parameter write protection • The diagnostics interface X6 cannot be used to write into write/read parameters.	
	Bit 2 Parameter read protection • The diagnostics interface X6 cannot be used to read write/read parameters.	
	Bit 3 ... 15 Reserved	
C00509/1	PW protection config. X1 (CAN)	0x0006
	Bit 0 Reserved	
	Bit 1 Parameter write protection • The CANopen interface X1 cannot be used to write into write/read parameters.	
	Bit 2 Parameter read protection • The CANopen interface X1 cannot be used to read write/read parameters.	
	Bit 3 ... 15 Reserved	
C00510/1	PW protection config. MCI	0x0006
	Bit 0 Reserved	
	Bit 1 Parameter write protection • The feldbus interface (MCI) cannot be used to write into write/read parameters.	
	Bit 2 Parameter read protection • The feldbus interface (MCI) cannot be used to read write/read parameters.	
	Bit 3 ... 15 Reserved	

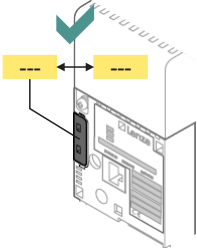
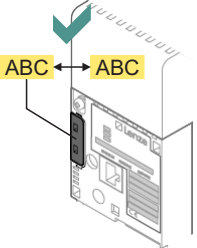
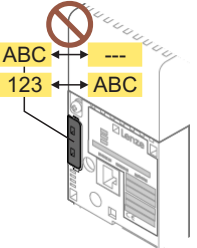
The parameter set must be saved to the device safe against mains failure to prevent password protection configured in the device from getting lost due to mains switching.



► [Save parameter settings in the memory module safe against mains failure](#) (40)

2.4.3 Device personalisation

The controller and the memory module are married via the device personalisation by means of a binding ID. When the device personalisation is active, all write/read actions between controller and memory module are only executed if both components have the same binding ID.

Lenze delivery status:	Procedure carried out by the customer:	Impermissible replacement by the end user:
		
No binding ID is set.	Customer sets binding ID for device personalisation.	When device personalisation is active: The replacement of the controller or memory module causes an error message if the binding ID is incorrect or not available.

If, for instance, a parameter set has been loaded from the memory module with an active device personalisation, saving of this parameter set on another memory module with a different or non-existent binding ID is not possible.

- Thus, copying the parameter set from a personalised memory module to a non-personalised memory module is not possible!

Two types of checks are distinguished:

- If a differing binding ID is detected when the controller is switched on (during device initialisation):
 - the "Fault" error response is returned.
 - The "[PS10: Invalid memory module binding](#)" error message is entered into the logbook.
- If a differing binding ID is detected while a device command for loading/saving the parameter set is executed:
 - Loading/saving is not executed.
 - A corresponding status for the device command is output in [C00003](#).

Short overview of the relevant parameters for device personalisation:

Parameter	Info	Lenze setting				
C00505/2	<div><div>Binding ID<ul style="list-style-type: none">• The binding ID must have a length of 4 ... 16 characters.• The binding ID may consist of any character. However, this is not sensible. Recommended characters are: lower case letters (a - z), upper case letters (A - Z) and digits (0 - 9).</div><div><div>Note:</div><div>After the execution of one of the device commands listed below, this parameter returns the current binding ID status:</div><table><tr><td>off</td><td>No binding ID is set.</td></tr><tr><td>on</td><td>Binding ID is set.</td></tr></table></div></div>	off	No binding ID is set.	on	Binding ID is set.	
off	No binding ID is set.					
on	Binding ID is set.					
Highlighted in grey = display parameter						

Parameter	Info	Lenze setting
Device commands		
Before the following device commands are executed, enter the corresponding binding ID in C00505/2 .		
C00002/29	Set binding ID ▶ Activate device personalisation	0: Off / ready
C00002/30	Delete binding ID ▶ Deactivate device personalisation/change binding ID	0: Off / ready
Status displays		
C00003	Status of the last device command	-
C00507/1	Password protection - all communication channels • Bit coded display of the active protective functions:	-
	Bit 0 Only access to user menu	
	Bit 1 Parameter write protection	
	Bit 2 Parameter read protection	
	Bit 3 ... 14 Reserved	
	Bit 16 Memory module binding on	
Highlighted in grey = display parameter		

Activate device personalisation

The device personalisation is activated by setting a binding ID.



How to set the binding ID:

- Enter the desired binding ID in [C00505/2](#).
 - The binding ID must have a length of 4 ... 16 characters.
 - The binding ID may consist of any character. However, this is not sensible. Recommended characters are: lower case letters (a - z), upper case letters (A - Z) and digits (0 - 9).
- Execute "Set binding ID" device command [C00002/29](#) = "1: On / start"
 - After successful execution, status ON is displayed in [C00505/2](#).

Deactivate device personalisation/change binding ID

The device personalisation is simply deactivated by deleting the set binding ID. If you want to change the set binding ID, first delete the set binding ID as well. Then set the new binding ID.



How to delete the binding ID:

- Enter the set binding ID in [C00505/2](#).
 - If controller and memory module do not have the same binding ID, enter the binding ID of the memory module to delete the binding ID of both components.
- Execute "Delete binding ID" device command [C00002/30](#) = "1: On / start"
 - After a successful deletion, status OFF is displayed in [C00505/2](#).

2.4.4 Unlocking the controller with a MasterPin

Every controller has an individual master password called "MasterPin". By entering the MasterPin, a controller inhibited by the password mechanisms can be reset to the delivery status.



Stop!

When the MasterPin is used, the parameter set is reset to the Lenze setting both in the controller and in the memory module!

- This results in a permanent loss of the customised parameterisation that must be recreated!
- A reset to the Lenze setting can result in unforeseen level changes at the I/O terminals (e.g. brake control)!



How to restore the delivery status:

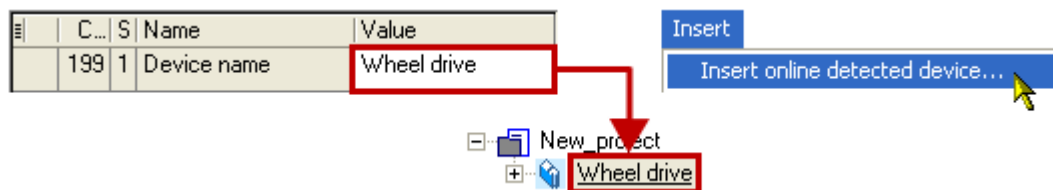
1. Inhibit the controller if it is enabled, e.g. via the [C00002/16](#) device command.
2. Enter the MasterPin in [C00505/1](#).
 - The MasterPin comprises the last 6 digits of the serial number of the memory module.
3. Execute "Check MasterPin" device command [C00002/28](#) = "1: On / start"

2.5 Device identification

For device identification, any device name (e.g. wheel drive) with max 32 characters can be set in [C00199/1](#) for the controller and saved in the memory module with mains failure protection.

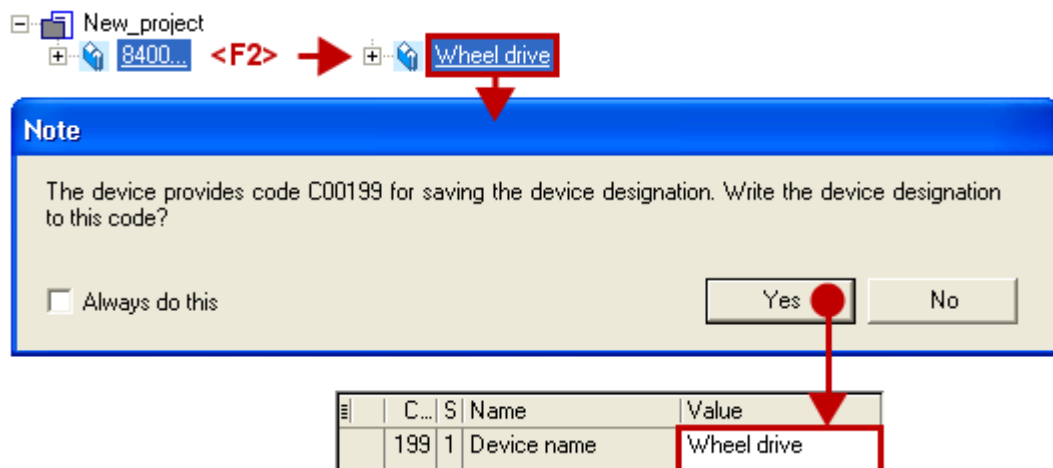
2.5.1 Automatic acceptance of the device name in the »Engineer«

If a device name is stored in [C00199/1](#) and the controller is added to the project in the »Engineer« via the **Einfügen → Insert device detected online...** function, the *device name* stored in ("8400 TopLine") [C00199/1](#) (here: wheel drive) is used as device name instead of the type:



This mechanism also functions in reverse direction:

If you rename the controller in the *project view* via **<F2>**, you will be asked afterwards if you want to take over the changed name in [C00199/1](#):



2.5.2 Extended item designation

This function extension is available from version 12.00.00!

In [C00199/2...5](#), four texts à max. 32 characters can be set for item designation and saved in the memory module safe against mains failure. These additional subcodes are not dependent on the previously described text acceptance mechanism in the »Engineer« for the device name ([C00199/1](#)).

3 Commissioning



Danger!

Unexpected motor movements can occur

Under certain conditions the motor may rotate after mains connection.

Possible consequences:

- Persons in the vicinity of the machine or plant risk getting hurt.
- Unexpected starting action may damage the machine or plant.

Protective measures:

- Commissioning with external 24 V supply and without mains voltage. In this case, the controller can only be parameterised and diagnosed during commissioning.
- Ensure that setpoints are not active.



Tip!

- Information on some of the operating statuses can quickly be obtained via the [LED status displays](#) on the front of the controller. (📖 674)
- **Check firmware:** Particularly with regard to the use of older controllers (e.g. if the customer is using one from stock) it makes sense to check the software (firmware) version. The software version of the controller can be seen on the nameplate in the "SW" line and can be determined by reading out code [C00099](#).
- **Restore delivery status:** Set code [C00002/1](#) to "1: On / start" to reset all parameter settings of the device to the Lenze setting. This leaves you with a defined device configuration. ▶ [Load Lenze setting](#) (📖 104)



The following chapters describe the commissioning of the available technology applications with the »Engineer«.

Information on how to commission using the keypad (or diagnosis terminal) can be found in the **8400 hardware manual**. The hardware manual has been stored in electronic form on the data carrier supplied with the 8400 controller.

3.1 Safety instructions with regard to commissioning

General safety instructions

In order to prevent injury to persons or damage to material assets

- check before connecting the mains voltage
 - the wiring for completeness, short circuit, and earth fault
 - the "emergency stop" function of the entire system
 - that the motor circuit configuration (star/delta) is adapted to the output voltage of the controller
 - the in-phase connection of the motor
- check the setting of the most important drive parameters before enabling the controller:
 - the V/f rated frequency must be adapted to the motor circuit configuration!
 - the drive parameters relevant for your application must be set correctly!
 - the configuration of the I/O terminals must be adapted to the wiring!
- ensure that there are no active speed setpoints before enabling the controller.

Safety instructions with regard to motor operation



Danger!

- For thermal reasons, continuous operation of self-ventilated motors at a low field frequency and rated motor current is not permissible!
 - In the Lenze setting, the [Motor temperature monitoring \(PTC\)](#) is activated. (📖 297)
 - Activate the [Brake resistor monitoring \(I2xt\)](#) if necessary. (📖 298)
- [C00015](#) must be used to select 87 Hz operation if a delta-connected asynchronous motor (nameplate data: 400 V Δ / 230 V Δ) is to be operated in conjunction with a drive controller for a mains voltage of 400 V.

3.2 Notes on motor control

In the Lenze setting, the V/f characteristic control (VFCplus) as motor control is set in [C00006](#) with a linear characteristic.

- V/f characteristic control (VFCplus) is a motor control mode for classic frequency inverter applications on the basis of a simple and robust control procedure for the operation of machines with a linear or quadratic load torque characteristic (e.g. fans).
- The presettings of the parameters ensure that the controller is immediately ready for operation and the motor works adequately without further parameterisation if a controller and a 50 Hz asynchronous machine with matching performances are assigned to each other.



Note!

Check the nameplate data against the motor data set in the controller. Further information is provided in the chapter "[Motor selection/Motor data](#)". (📖 135)

Recommendations for the following application cases:

- If the controller and motor differ greatly in terms of performance:
Set the I_{max} limit (in motor mode) in [C00022](#) to 2x rated motor current.
- If a high starting torque is required:
When the motor is idling, set a value for V_{min} boost in [C00016](#) which ensures that the rated motor current flows at a field frequency of $f = 3$ Hz (display in [C00058](#)).
- For noise optimisation:
In [C00018](#), set a switching frequency of "16 kHz var./drive-opt."
- If a high torque must be provided at small speeds without feedback:
Select "Sensorless vector control (SLVC) as motor control mode in [C00006](#).

Related topics:

▶ [Motor control \(MCTRL\)](#) (📖 134)

3.3

Preconditions for commissioning with the »Engineer«

For commissioning, you need

- a PC that satisfies the following requirements:
 - processor with 1.4 GHz or higher
 - at least 512 MB RAM and 650 MB free hard disc space
 - Microsoft® Windows® 2000 operating system (from service pack 2 onwards) or Windows® XP
- the Lenze »Engineer« PC software
- a connection to the controller, e.g. via a USB diagnostic adapter:
 - connect the USB diagnostic adapter to the X6 diagnostic interface.
 - establish a connection between the USB diagnostic adapter and the PC via a free USB port.

**Tip!**

How to obtain/update the »Engineer« software:

- **Download from the internet:** The full version of the »Engineer StateLevel« is provided free of charge in the internet:
<http://www.Lenze.com> → Download → Software downloads
- **Requesting the CD** You can also request the »Engineer« separately on CD free of charge at your Lenze representative. See the "About Lenze" area on our homepage for e.g. the corresponding German address.

3.4 Trouble-shooting during commissioning

When the »Engineer« is used, trouble during commissioning can be detected and eliminated conveniently. Proceed as follows:

- Check whether error messages appear in the »Engineer«.
 - On the **Diagnostics** tab, relevant actual states of the controller and pending error messages are displayed in a well-arranged visualisation.
- Check the input terminals for their corresponding setpoints.
 - The **Terminal assignment** tab displays the current input/output signals.
- Check the signal flow of the application.
 - For this purpose, click the **Signal flow** button on the **Application parameter** tab. The displayed signal flow shows active setpoints and their further processing.

Related topics:

- ▶ [Diagnostics & error management](#) (📖 673)
- ▶ [LED status displays](#) (📖 674)
- ▶ [Error messages of the operating system](#) (📖 696)

3.5 Commissioning wizard 8400

This function extension is supported by the »Engineer« from version 2.15 onwards!

The **commissioning wizard 8400** serves to carry out a guided commissioning of the controller based on the Lenze setting of the parameters. The set parameters can then be saved in the controller with mains failure protection.



Note!

Take all the necessary safety precautions before you carry out the following commissioning steps and switch the device on!

- ▶ [Safety instructions with regard to commissioning](#) (📖 53)




How to carry out a guided commissioning using the »Engineer«:

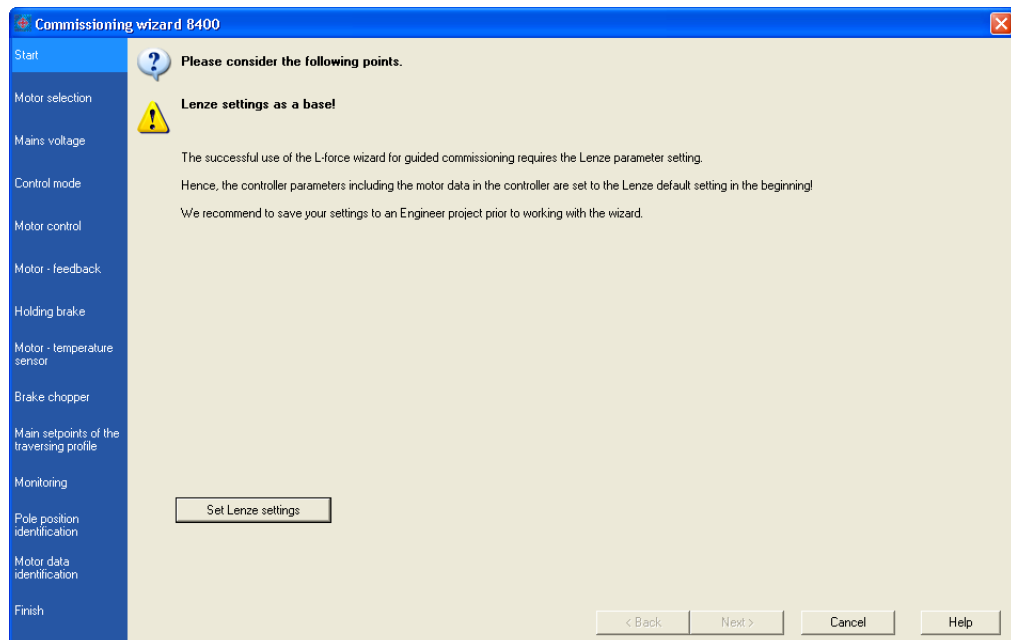
1. In the *Project view*, select the 8400 TopLine controller.

2.  Go online.

After a connection to the controller has been established, the following status is displayed in the *Status line*:



3. Click the  icon to open the *commissioning wizard 8400* dialog box.
 - Now the commissioning wizard guides you step by step through the setting of the important parameters for a quick commissioning.
 - The **Next** button can only be activated again after all parameter settings in the device have been reset via the **Load Lenze setting** button.



Related topics:

- ▶ [Commissioning of the "Actuating drive speed" technology application](#) (📖 59)

3.6

Manual motor direction of rotation check (manual control)

The »Engineer« function "Manual control" easily allows for controlling the direction of rotation of the motor. The manual control serves to let the motor connected to the controller with an adjustable speed for an adjustable time.

**Note!**

Take all the necessary safety precautions before you carry out the following commissioning steps and switch the device on!

► [Safety instructions with regard to commissioning](#) (53)

**How to carry out a manual motor direction of rotation check using the »Engineer«:**

1. In the *Project view*, select the 8400 TopLine controller.

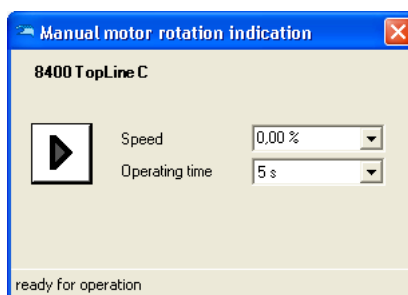
2. Go online.

After a connection to the controller has been established, the following status is displayed in the *Status line*:



3. Click the symbol to inhibit the controller via device command.
4. Ensure that the following conditions are met:
 - The mains voltage is switched on.
 - No trouble is active.
 - Safe torque off (STO) is not active.
5. Enable controller via terminal: Set terminal X5/RFR to HIGH level.
6. Click the icon to open the *Manual motor rotation indication* dialog box.

Note: If the "not ready for operation" status is displayed, check whether all conditions mentioned before (see steps 3 ... 5) have been met.



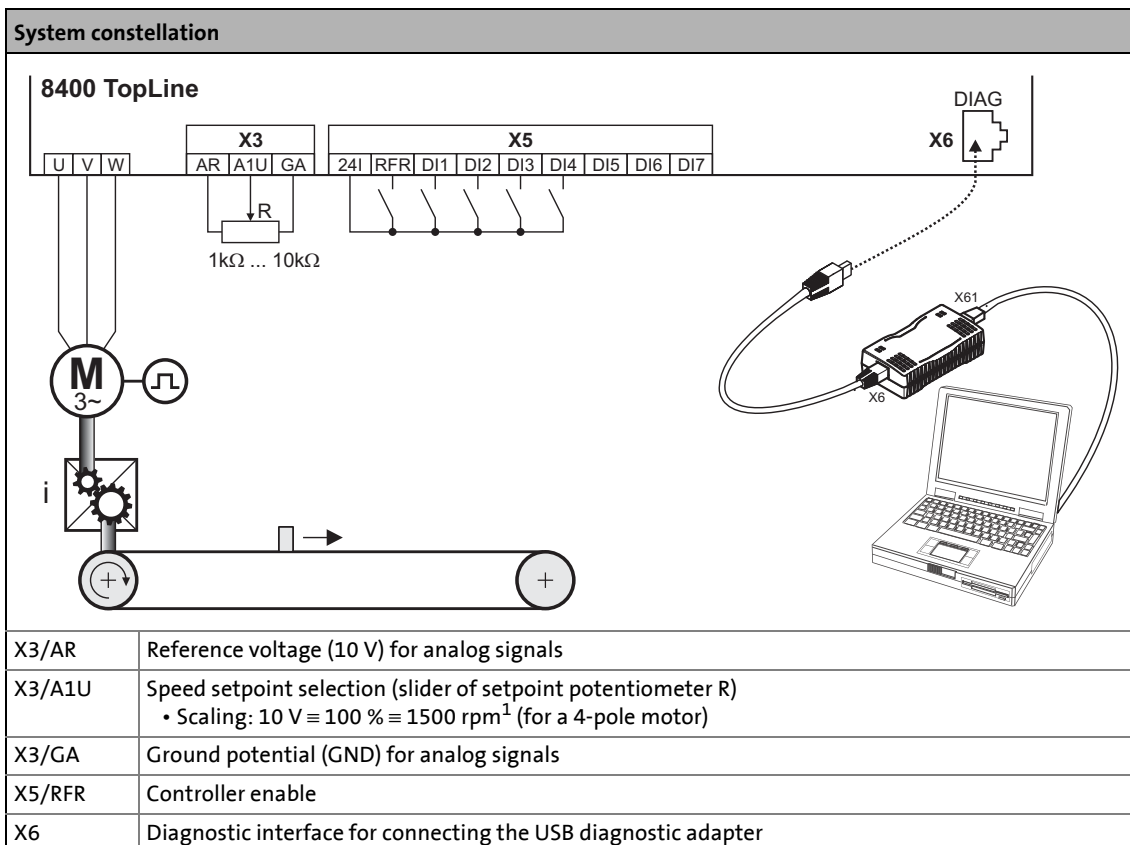
7. Set the desired speed and runtime.
(The speed refers to the reference speed set in [C00011](#).)
8. Click the button to let the motor rotate with the set speed for the set runtime.

By clicking the button, the function can be aborted.

**Note!**

Take all the necessary safety precautions before you carry out the following commissioning steps and switch the device on!

► [Safety instructions with regard to commissioning](#) (53)



[3-1] Block diagram for wiring the commissioning example for the "Actuating drive speed" application

Commissioning steps

Find a description of the commissioning steps of the "Actuating drive speed" technology application below.

Please observe the sequence of the steps in the following chapters and follow them through carefully. This will help you to commission your controller quickly and as safely as possible:

- [Prepare controller for commissioning](#) (60)
- [Creating an »Engineer« project & going online](#) (61)
- [Parameterising the motor control](#) (62)
- [Parameterise application](#) (63)

► [Saving parameter settings safe against mains failure](#) (📖 65)

► [Enable controller and test application](#) (📖 65)

3.7.1 Prepare controller for commissioning

1. Power terminal wiring.

Refer to the mounting instructions supplied with the drive controller to find help on how to correctly design the power connections to match the requirements of your device.

2. Control terminal wiring.

The assignment for your digital inputs should correspond to one of the preconfigured control modes ([C00007](#)) for terminal control:

Control mode	Assignment of the digital terminals			
	DI1	DI2	DI3	DI4
Terminals 0	JOG 1/3	JOG 2/3	DCB	Cw/Ccw
Terminals 2	JOG 1/3	JOG 2/3	QSP	Cw/Ccw
Terminals 11	Cw/Ccw	DCB	MPotUp	MPotDown
Terminal 16	JOG 1/3	JOG 2/3	Cw/QSP	Ccw/QSP
Abbreviations used:				
JOG	Selection of fixed setpoints 1 ... 3 parameterised in C00039/1...3			
DCB	Manual DC-injection braking			
Cw/Ccw	CW/CCW rotation			
QSP	Quick stop			
MPotUp	Motor potentiometer: Increase speed			
MPotDown	Motor potentiometer: Reduce speed			
Cw/QSP	Fail-safe selection of the direction of rotation in connection with quick stop			
Ccw/QSP				

3. Inhibit controller: Set terminal X5/RFR to LOW level or open contact.

4. Connect USB diagnostic adapter.

5. Switch on voltage supply of the controller.

- Without motor operation: Connect external 24 V supply.
- With motor operation: Connect mains voltage.

If the green "DRV-RDY" LED is blinking and the red "DRV-ERR" LED is off, the controller is ready for operation and commissioning can proceed.

Related topics:

► [Automatic restart after mains connection/fault...](#) (📖 124)

► [LED status displays](#) (📖 674)

3.7.2 Creating an »Engineer« project & going online



You can find detailed information on the general use of the »Engineer« in the online help which you can call with **[F1]**.

- The chapter "Working with projects" describes, among other things, all options of the *Start-up wizard* which are available to create a new »Engineer« project.

The following steps serve to describe a general method for creating a project with the **Select component from catalogue** option. For this purpose, individual components (controller, motor, etc.) are selected from selection lists.

1. Start the »Engineer«.
2. Create a new project with the *Start-up wizard* and the **Select component from catalogue** option:
 - In the **Component** step, select the 8400 TopLine controller.
 - In the **Device modules** step, select the available communication module.
 - In the **Application** step, select the "Actuating drive speed" application. (The application can also be selected any time afterwards via the **Application parameter** tab or [C00005](#).)
 - Select the other components (motor/gearbox) to be added to the project in the **Other components** dialog step.

3.  Go online.

After a connection to the controller has been established, the following status is displayed in the *Status line*:



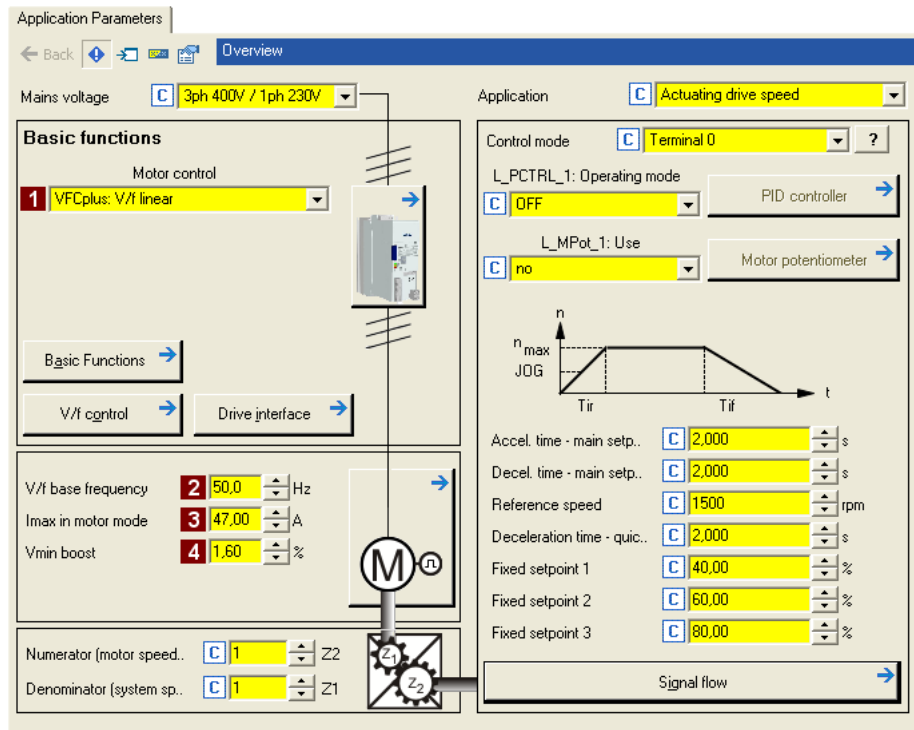
4.  Transfer parameter set to the device.

This command serves to overwrite the current parameter settings in the controller by parameter settings of the »Engineer« project.

3.7.3 Parameterising the motor control

1. Select the **Application parameters** tab from the *Workspace*.

The motor control parameters, among other things, can be found on the left:



2. In the **1 Motor control** list field ([C00006](#)), select the desired motor control.
3. Adapt the motor control parameters:

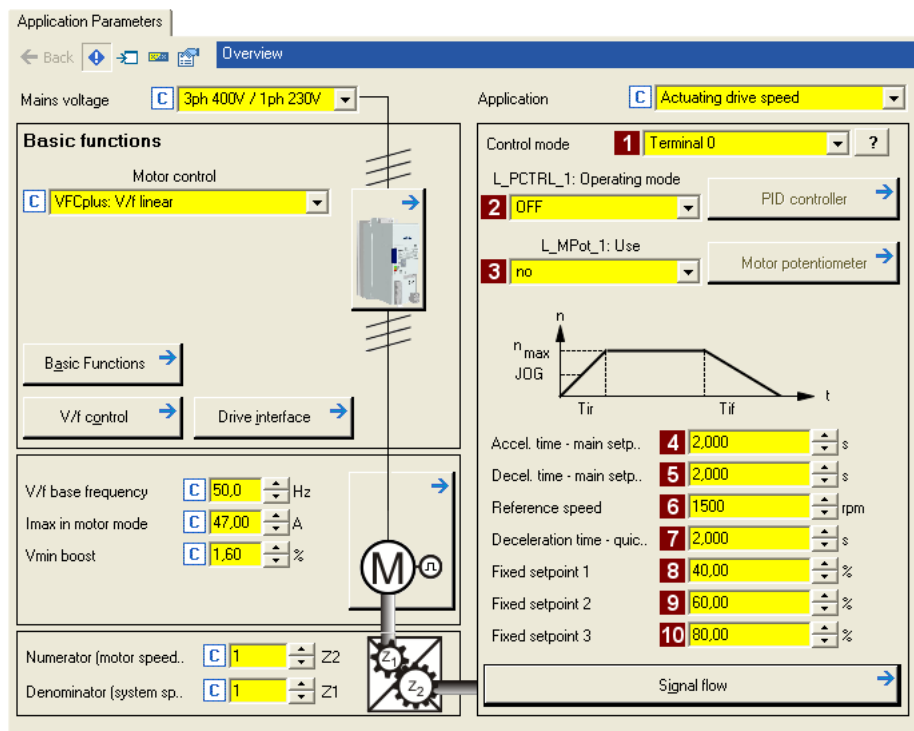
Parameter	Lenze setting		Info
	Value	Unit	
2 V/f base frequency (C00015)	50.0	Hz	► Adapting the V/f base frequency (164)
3 I _{max} in motor mode (C00022)	47.00	A	► Optimising the I_{max} controller (168)
4 V _{min} boost (C00016)	1.60	%	► Adapting the V_{min} boost (166)

Related topics:

- [Notes on motor control](#) (54)
- [Motor control \(MCTRL\)](#) (134)

3.7.4 Parameterise application

The application parameters can be found on the right side of the **Application parameter** tab:



1. In the **1 Control mode** list field ([C00007](#)), select the control mode suitable for the wiring of the terminals.
 - The corresponding wiring diagram is displayed in a pop-up window if you click the **?** button right to the list field.
 - For a detailed description, see the chapter "[Terminal assignment of the control modes](#)". ([441](#))
2. Optional: Use process controller.
 - For this purpose, select the desired operating mode in the **2 L_PCTRL_1: Operating mode** list field ([C00242](#)).
 - For a detailed description see the [L_PCTRL_1](#) function block. ([1605](#))
 - Go to the parameterisation dialog of the process controller via the **Process controller** button.
3. Optional: Use motor potentiometer.
 - For this purpose, select "1: On" in the **3 L_MPot_1: Use** list field ([C00806](#)).
 - For a detailed description see the [L_MPot_1](#) function block. ([1560](#))
 - Go to the parameterisation dialog of the motor potentiometer via the **Motor potentiometer** button.

4. Adapt the application parameters:

Parameter	Lenze setting		Info
	Value	Unit	
4 Accel. time - main setpoint (C00012)	2.000	s	The setpoint is led via a ramp function generator with linear characteristic. The ramp function generator converts setpoint step-changes at the input into a ramp. ▶ L_NSet_1 (431 1578)
5 Decel. time - main setpoint (C00013)	2.000	s	
6 Reference speed (C00011)	1500	rpm	All speed setpoint selections are provided in % and always refer to the reference speed set in C00011 . The motor reference speed is indicated on the motor nameplate.
7 Decel. time - quick stop (C00105)	2.000	s	If quick stop is requested, motor control is decoupled from the setpoint selection and, within the deceleration time parameterised in C00105 , the motor is brought to a standstill ($n_{act} = 0$). ▶ Activate/deactivate quick stop (431 108)
8 Fixed setpoint 1 (C00039/1)	40.00	%	A fixed setpoint for the setpoint generator can be activated instead of the main setpoint via the digital DI1 and DI2 inputs. • Fixed setpoints are selected in [%] based on the reference speed (C00011). ▶ L_NSet_1 (431 1578)
9 Fixed setpoint 2 (C00039/2)	60.00	%	
10 Fixed setpoint 3 (C00039/3)	80.00	%	

**Tip!**

- Click the **Signal flow** button to go down one dialog level to the signal flow of the application with further possible parameter settings. See chapter "[Basic signal flow](#)". (431 431)
- The preconfigured I/O connection in the selected control mode can be changed via configuration parameters. See chapter "[User-defined terminal assignment](#)". (431 421)

More detailed information on the technology application:

- ▶ [TA "Actuating drive speed"](#) (431 430)
- ▶ [Internal interfaces | application block "LA_NCtrl"](#) (431 433)
- ▶ [Process data assignment for fieldbus communication](#) (431 450)
- ▶ [Terminal assignment of the control modes](#) (431 441)
- ▶ [Setting parameters \(short overview\)](#) (431 452)
- ▶ [Configuration parameters](#) (431 454)

3.7.5 Saving parameter settings safe against mains failure

The parameter set must be saved to the device safe against mains failure to prevent parameter settings becoming lost due to mains switching.



Save parameter set.

3.7.6 Enable controller and test application



Stop!

Before stipulating a speed setpoint, check whether the brake in the form of a holding brake on the motor shaft has been released!



Note!

If the controller is enabled and the "Inhibit at power-on" auto-start option is activated in [C00142](#) (Lenze setting) when the mains is connected, the controller remains in the "ReadyToSwitchOn" state.

To be able to change to the "SwitchedOn" status, the controller enable must be deactivated first: set terminal X5/RFR to LOW level.

If the controller is in the "SwitchedOn" status:

1. Enable controller: Set terminal X5/RFR to HIGH level or close contact.
 - If there is no other active source for the controller inhibit, the controller changes from the "SwitchedOn" status to the "OperationEnabled" status.
 - The **Diagnostics** tab and [C00158](#) display all active sources for the controller inhibit.
2. Select the speed setpoint.

In the "Terminal 0" control mode by selecting a voltage at the analog input via the setpoint potentiometer or by selecting a fixed setpoint via the digital DI1/DI2 inputs:

DI1	DI2	Speed selection
LOW	LOW	The setpoint speed is selected via analog input 1 • Scaling: 10 V \equiv 100 % \equiv reference speed (C00011)
HIGH	LOW	Fixed setpoint 1 (C00039/1) is used as setpoint speed. • Lenze setting: 40 % of the reference speed (C00011)
LOW	HIGH	Fixed setpoint 2 (C00039/2) is used as setpoint speed. • Lenze setting: 60 % of the reference speed (C00011)
HIGH	HIGH	Fixed setpoint 3 (C00039/3) is used as setpoint speed. • Lenze setting: 80 % of the reference speed (C00011)



Note!

Observe the actual speed value (display in [C00051](#)) as well as the [LED status displays](#).
([674](#))

**Tip!**

Other control functions in the "Terminal 0" control mode:

- DI3: HIGH level \equiv Request DC-injection braking
- DI4: HIGH level \equiv Request a change of direction of rotation

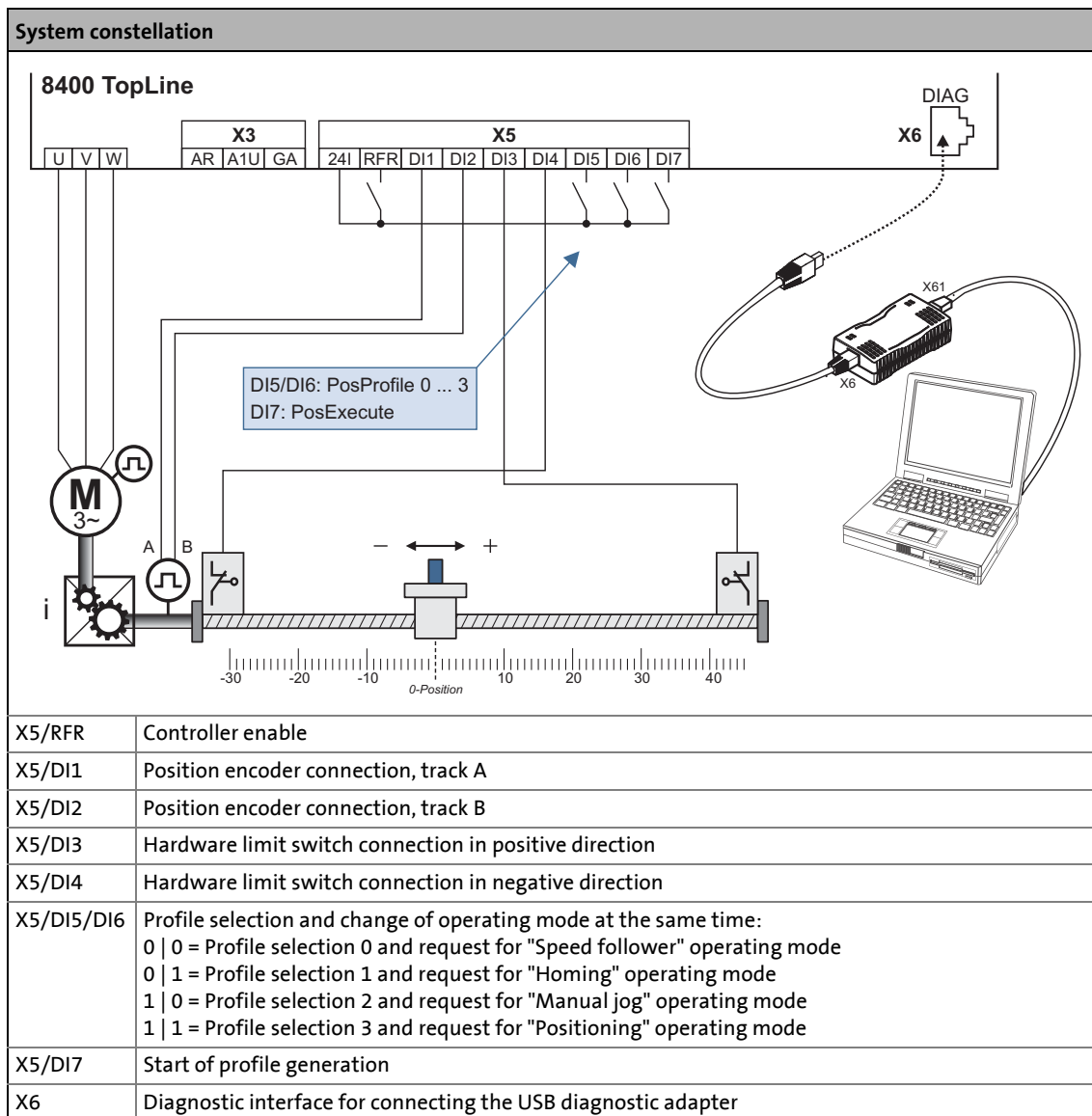
Related topics:

- ▶ ["Inhibit at power-on" auto-start option](#) (📖 124)
- ▶ [Trouble-shooting during commissioning](#) (📖 56)
- ▶ [Diagnostics & error management](#) (📖 673)

**Note!**

Take all the necessary safety precautions before you carry out the following commissioning steps and switch the device on!

► [Safety instructions with regard to commissioning](#) (53)



[3-2] Block diagram for wiring the commissioning example for the "Table positioning" application

Commissioning steps

Below find a description of the commissioning steps of the "Table positioning" application shown in illustration [\[3-2\]](#).

Please observe the sequence of the steps in the following chapters and follow them through carefully. This will help you to commission your controller quickly and as safely as possible:

- ▶ [Prepare controller for commissioning](#) (📖 69)
- ▶ [Creating an »Engineer« project & going online](#) (📖 70)
- ▶ [Parameterising the motor control](#) (📖 71)
- ▶ [Parameterise application](#) (📖 72)
- ▶ [Saving parameter settings safe against mains failure](#) (📖 80)
- ▶ [Enable controller and test application](#) (📖 80)

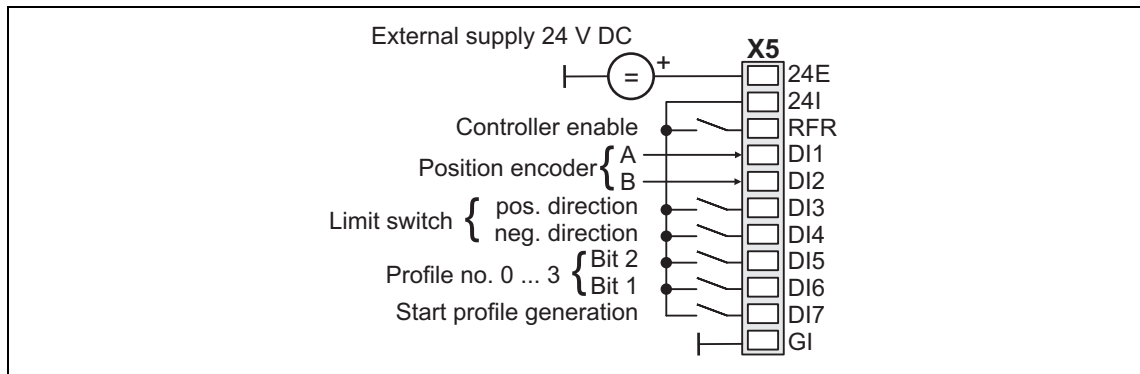
3.8.1 Prepare controller for commissioning

1. Power terminal wiring.

Refer to the mounting instructions supplied with the drive controller to find help on how to correctly design the power connections to match the requirements of your device.

2. Control terminal wiring.

The system constellation including position encoder and hardware limit switches shown in illustration [3-2] requires wiring according to control mode "[Terminals 0](#)":



3. Inhibit controller: Set terminal X5/RFR to LOW level or open contact.

4. Connect USB diagnostic adapter.

5. Switch on voltage supply of the controller.

- Without motor operation: Connect external 24 V supply.
- With motor operation: Connect mains voltage.

If the green "DRV-RDY" LED is blinking and the red "DRV-ERR" LED is off, the controller is ready for operation and commissioning can proceed.

Related topics:

- ▶ [Automatic restart after mains connection/fault...](#) (📖 124)
- ▶ [LED status displays](#) (📖 674)

3.8.2 Creating an »Engineer« project & going online



You can find detailed information on the general use of the »Engineer« in the online help which you can call with **[F1]**.

- The chapter "Working with projects" describes, among other things, all options of the *Start-up wizard* which are available to create a new »Engineer« project.

The following steps serve to describe a general method for creating a project with the **Select component from catalogue** option. For this purpose, individual components (controller, motor, etc.) are selected from selection lists.

1. Start the »Engineer«.
2. Create a new project with the *Start-up wizard* and the **Select component from catalogue** option:
 - In the **Component** step, select the 8400 TopLine controller.
 - In the **Device modules** step, select the available communication module.
 - In the **Application** step, select the "Table positioning" application. (The application can also be selected any time afterwards via the **Application parameter** tab or [C00005](#).)
 - Select the other components (motor/gearbox) to be added to the project in the **Other components** dialog step.

3.  Go online.

After a connection to the controller has been established, the following status is displayed in the *Status line*:



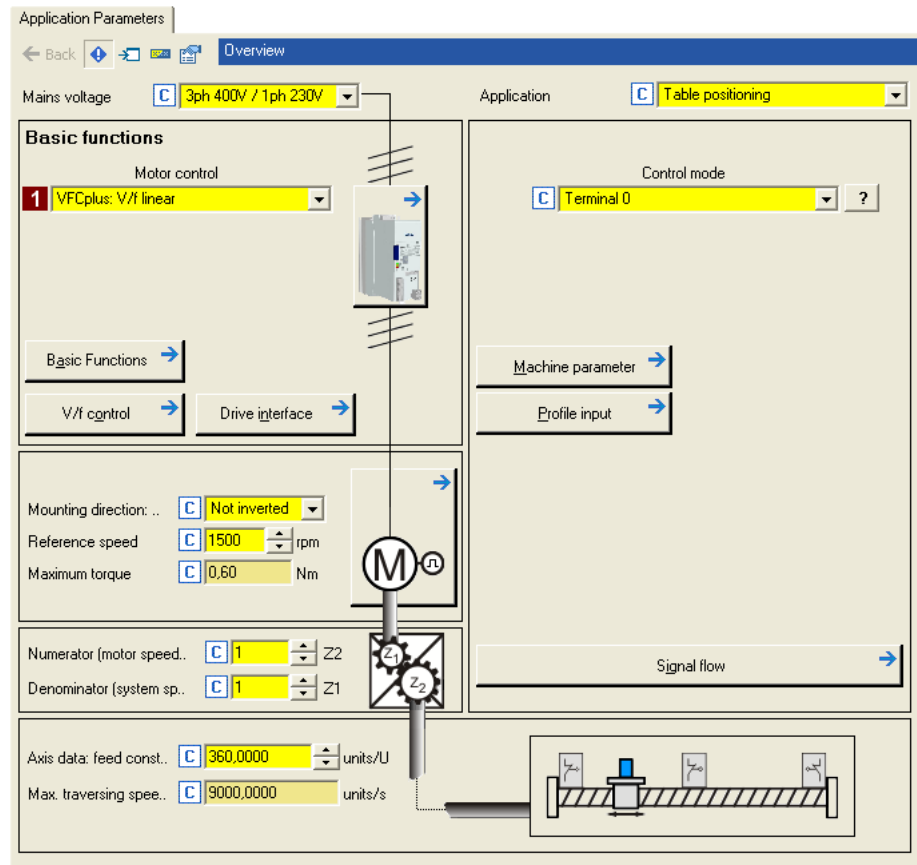
4.  Transfer parameter set to the device.

This command serves to overwrite the current parameter settings in the controller by parameter settings of the »Engineer« project.

3.8.3 Parameterising the motor control

1. Select the **Application parameters** tab from the *Workspace*.

The motor control parameters, among other things, can be found on the left:



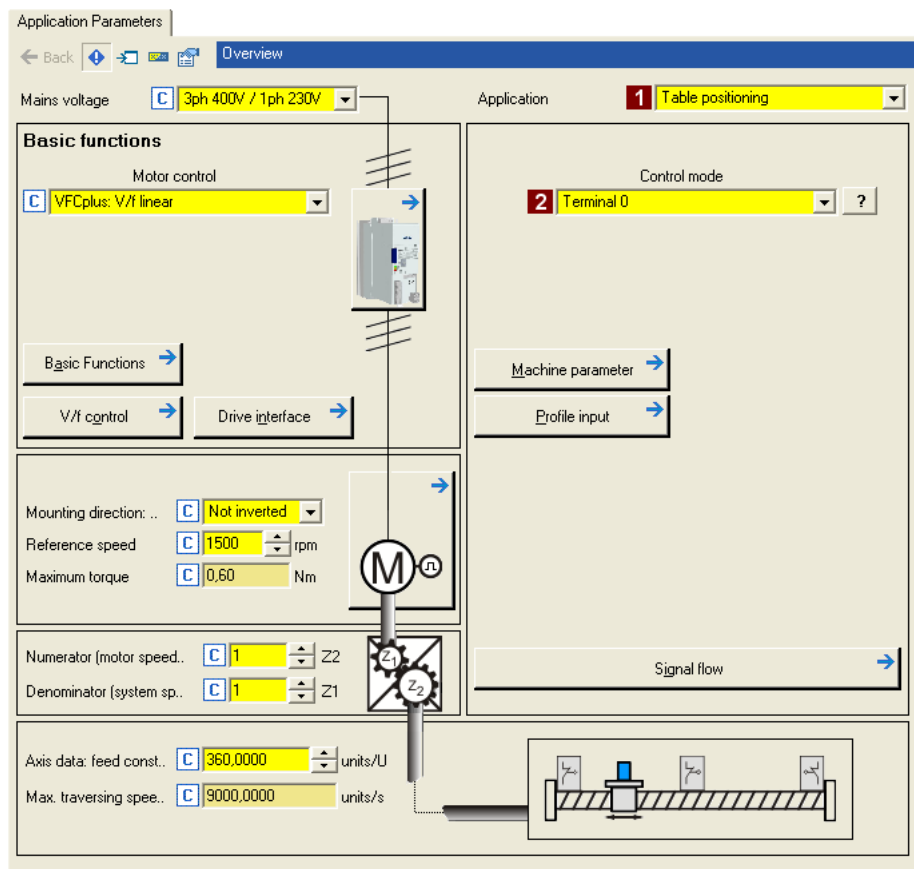
2. In the **1 Motor control** list field (**C00006**), select the desired motor control.

Related topics:

- ▶ [Notes on motor control](#) (54)
- ▶ [Motor control \(MCTRL\)](#) (134)

3.8.4 Parameterise application

The application parameters can be found on the right side of the **Application parameter** tab:



1. Select "Table positioning" in the **1 Application** list field ([C00005](#)) (if you have not already done so while creating the project).

After the "Table positioning" application is selected, the contents of the tab change, e.g. the **Machine parameters** and **Profile entry** buttons are shown now.

2. In the **2 Control mode** list field ([C00007](#)), the preset "[Terminals 0](#)" control mode is already suitable for the system constellation shown in illustration [3-2](#) and need not be changed.
 - The corresponding wiring diagram is displayed in a pop-up window if you click the **?** button right to the list field.
 - For a detailed description, see the chapter "[Terminal assignment of the control modes](#)". ([441](#))

3.8.4.1 Set machine parameters

**Note!**

Setting the machine parameters is a basic prerequisite for the operating modes "[Homing](#)", "[Manual jog](#)" and "[Positioning](#)".

The more precisely the machine parameters are set, the better the results of positioning!

Detailed information on the machine parameters is provided in chapter "Basic drive functions" in subchapter "[Machine parameters](#)". (p. 582)

- Go to the right side of the **Application parameter** tab and click the **Machine parameter** button to change to the **Overview → Machine parameter** dialog level:

- Set the machine parameters according to the system constellation at hand.

Parameter	Lenze setting		Info
	Value	Unit	
1 Mounting direction: Motor (C01206/1)	not inverted		Inversion if motor mounting is mirrored.
2 Numerator (Z2) (C01202/1)	1		Gearbox factor - motor • Entry of the gearbox factor as numerator/denominator ratio (numerator = motor speed and denominator = output speed of gearbox) or from the number of teeth of the gearbox arrangement.
3 Denominator (Z1) (C01202/2)	1		
4 Mounting direction: Position encoder (C01206/2)	not inverted		Inversion if position encoder mounting is mirrored.
5 Counter (C01203/1)	1		Gearbox factor - position encoder • Entry of the gearbox factor as numerator/denominator ratio, with numerator = motor speed and denominator = position encoder speed.
6 Denominator (C01203/2)	1		

Parameter	Lenze setting		Info
	Value	Unit	
7 Axis cycle (C01201/1)	0.0000	units	Cycle for Modulo measuring system <ul style="list-style-type: none"> The Modulo system is activated by setting a cycle (C01201/1) > 0 units. When the cycle (C01201/1) is set to 0 units (Lenze setting), the traversing range is unlimited (classical measuring system).
8 Feed constant (C01204)	360.0000	units/rev.	The feed constant corresponds to the movement of the machine during one revolution of the gearbox output shaft. <ul style="list-style-type: none"> The value is entered in application units referred to one revolution.
9 Reference speed (C00011)	1500	rpm	All speed setpoint selections are provided in % and always refer to the reference speed set in C00011 . The motor reference speed is indicated on the motor nameplate.

- After setting the machine parameters, click the **Back** button to change to the *Overview* dialog level.

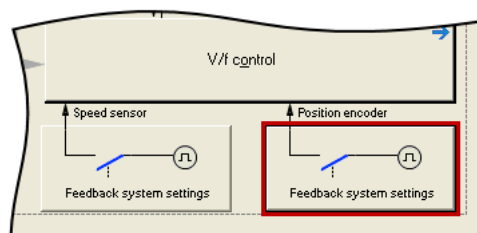
3.8.4.2 Set the position encoder

In the Lenze setting, the digital input terminals are configured as "normal" digital inputs. Since in this system constellation DI1 and DI2 are used to connect a two-track position encoder, the function assignment of these two inputs must be changed accordingly.



Detailed information on how to use a resolver/encoder as motor or position encoder can be found in the main chapter "[Encoder/feedback system](#)". (314)

- Go to the right side of the **Application parameter** tab and click the **Signal flow** button to change to the *Overview* → *Signal flow* dialog level.
- Click the **Feedback system settings** button in the signal flow:



The *Encoder/Feedback system* parameterisation dialog will be shown:

3. In the **1** **Position encoder selection** list field ([C00490](#)), select "Encoder signal FreqIn12".
4. In the **2** **Fct. DI 1/2 100kHz** list field ([C00115/1](#)), select "DI1(6)&DI2(7)=FreqIn (2-track)".
This selection ensures that the digital DI1 and DI2 input terminals are configured as frequency inputs.
5. Set the number of position encoder increments in the **3** **Number of encoder increments at FreqIn12** input field ([C00420/1](#)).
6. Click the **Close** button to close the parameterisation dialog again.

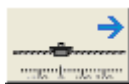
Related topics:


- ▶ [Digital input terminals](#) (377)
- ▶ [Using DI1\(6\) and DI2\(7\) as frequency inputs](#) (381)
- ▶ [Encoder/feedback system](#) (314)

3.8.4.3 Set homing



Detailed information on the "Homing" operating mode is provided in chapter "Basic drive functions" in subchapter "[Homing](#)". ([606](#))



- Click the  button (in the "MotionControlKernel" block) in the signal flow to change to the *Overview → Signal flow → Homing* dialog level:

Application Parameters

← Back Overview → Signal flow → Homing

Ref. TP-signal source

C No TP

Setting up TouchProbe ...

Homing mode

2 >_Lp

1 Homing mode

bHomeStartStop

Ref. home position

3 0,0000 unit

Ref. reference offset

4 0,0000 unit

Ref. sequence profile

C 0

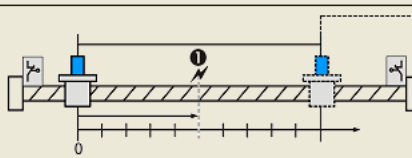
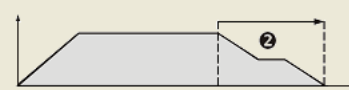
Homing active

Homing done

Home position available

Actual position

C 0,0000 units

1 Sensor mark (TP, MP) - home position in machine measuring system

2 Reference target position

Ref. S-ramp time

5 0,000 s

Ref. M-limit mode 14/15

C 10,00 %

Ref. waiting time mode 14/15

C 100 ms

Ref. start speed

6 720,0000 unit/s

Ref. start acceleration

7 720,0000 unit/s²

Positive SW limit position

C 0,0000 units

Ref. search speed

C 180,0000 unit/s

Ref. search acceleration

C 720,0000 unit/s²

Negative SW limit position

C 0,0000 units

- Select the homing mode and hence the type of homing via the **1 Homing mode** button or directly in the **2 Homing mode** list field ([C01221](#)).
 - A graphic display of all possible homing modes can be seen via the **Homing mode** button.
 - In this system constellation without touch probe, the preset ">_Lp" mode can be used: movement in positive direction, positive edge of the limit switch sets reference.
- Set the position to be used for loading the set position and the actual position after homing has finished in the **3 Homing home position** input field ([C01227/2](#)).

4. Recommendation: Set an offset in the **4 Homing home offset** input field ([C01227/1](#)) to prevent the machine from stopping at an activated limit switch.

Background: The load machine can also leave the travel range limit switch. There follows a return to the home position that was set with the positive edge of the travel range limit switch.

5. Set suitable profile parameters for the homing:

Parameter	Lenze setting		Info
	Value	Unit	
5 S-ramp time (C01226/1)	0.000	s	S-ramp time for reference search/homing. • Setting "0 s" ≡ no rounding
6 Start speed (C01224/1)	720.0000	unit/s	Starting speed for approaching the pre-stop signals.
7 Start acceleration (C01225/1)	720.0000	unit/s ²	Starting acceleration for the starting speed ramps.

6. After setting the parameters for the homing, click the **Back** button to change back to the *Overview* → *Signal flow* dialog level.

3.8.4.4 Enter one or more profiles



You can find detailed information on entering profiles in the chapter entitled "Basic drive functions", subchapter "[Profile entry](#)". (637)

1. Click the **Profile entry** button (in the "MotionControlKernel" block) in the signal flow to change to the *Overview* → *Signal flow* → *Profile entry* dialog level:

Application Parameters

← Back → Overview → Signal flow → Profile input

Profile number **1** < 03 >

Comments

Profile 3: Mode	2	Absolute (shortest path)	
Profile 3: Position	3	360,0000	Unit
Profile 3: Speed	4	360,0000	Unit/s
Profile 3: Accel.	5	720,0000	Unit/s²
Profile 3: Decel.	6	720,0000	Unit/s²
Profile 3: S-ramp time	7	0,000	s
Profile 3: Final speed	8	0,0000	Unit/s
Profile 3: Sequence profile	9	0	
Profile 3: TP-profile	10	0	
Profile 3: TP-source	11	TP-DigIn3	

G The TP window is only supported by digital inputs DI3, DI4 and DI5.
H

Setting up TouchProbe ...

**Note!**

In the Lenze setting, the profiles are assigned to certain operating modes, i.e. the selection of a profile also results in a change of operating mode:

- If profile 0 is selected: Activation of "Speed follower" operating mode
- If profile 1 is selected: Activation of "Homing" operating mode
- If profile 2 is selected: Activation of "Manual jog" operating mode
- If profile 3 ... 15 is selected: Activation of "Positioning" operating mode

2. Select number 3 in the **1** **Profile number** list field to enter a positioning profile which can be selected via digital inputs DI5 and DI6.

3. Set the profile parameters:

Parameter	Lenze setting		Info
	Value	Unit	
2 Profile x: Mode (C01300/x)	absolute (shortest way)t		Selection of the way in which positioning is to be carried out. ▶ Positioning modes (□ 640)
3 Profile x: Position (C01301/x)	360.0000	unit	Target position or distance to be traversed.
4 Profile x: Speed (C01302/x)	360.0000	unit/s	Maximum speed at which the target is to be approached.
5 Profile x: Acceleration (C01303/x)	720.0000	unit/s ²	Stipulation of the change in speed at which maximum acceleration is to take place.
6 Profile x: Deceleration (C01304/x)	720.0000	unit/s ²	Stipulation of the change in speed at which maximum deceleration to a standstill is to take place.
7 Profile x: S-ramp time (C01306/x)	0.000	s	Due to stipulation of an S-ramp time for a profile, the profile is executed with S-shaped ramps, i.e. acceleration and braking processes are initiated smoothly in order to reduce jerk and thus the stress on the drive components.
8 Profile x: Final speed (C01305/x)	0.0000	unit/s	This specifies the speed at which the drive is to start the next profile after reaching the target position.
9 Profile x: Sequence profile (C01307/x)	0		Optional: Sequence profile for profile linkage / following block control. After execution of the profile (target position reached), the set following (subsequent) profile is started automatically. In this way, profile chains can be stipulated without additional control processes.
10 Profile x: TP profile (C01308/x)	0		Optional: Profile number of the profile (1 ... 15) that is to be executed after a touch probe has been detected. • If "0" is set, there will be no profile stepping through touch probe. • Only relevant for positioning modes with touch-probe.
11 Profile x: TP source (C01308/x)	TP-DigIn3		Optional: Selection of the signal source for touch probe detection. • Only relevant for positioning modes with touch-probe.

4. After entering the profile, click the **Back** button to change back to the *Overview* → *Signal flow* dialog level.

Related topics:

- ▶ [Touch probe detection](#) (□ 411)
- ▶ [Operating mode change with profile number](#) (□ 578)
- ▶ [Positioning](#) (□ 633)

More detailed information on the technology application:

- ▶ [TA "Table positioning"](#) (📖 490)
- ▶ [Basic signal flow](#) (📖 491)
- ▶ [Internal interfaces | application block "LA_TabPos"](#) (📖 494)
- ▶ [Process data assignment for fieldbus communication](#) (📖 513)
- ▶ [Terminal assignment of the control modes](#) (📖 504)
- ▶ [Setting parameters \(short overview\)](#) (📖 515)
- ▶ [Configuration parameters](#) (📖 516)

3.8.5 Saving parameter settings safe against mains failure

The parameter set must be saved to the device safe against mains failure to prevent parameter settings becoming lost due to mains switching.



Save parameter set.

3.8.6 Enable controller and test application**Stop!**

Before stipulating a speed setpoint, check whether the brake in the form of a holding brake on the motor shaft has been released!

**Note!**

If the controller is enabled and the "Inhibit at power-on" auto-start option is activated in [C00142](#) (Lenze setting) when the mains is connected, the controller remains in the "[ReadyToSwitchOn](#)" state.

To be able to change to the "[SwitchedOn](#)" status, the controller enable must be deactivated first: set terminal X5/RFR to LOW level.

If the controller is in the "[SwitchedOn](#)" status:

1. Enable controller: Set terminal X5/RFR to HIGH level or close contact.
 - If there is no other active source for the controller inhibit, the controller changes from the "[SwitchedOn](#)" status to the "[OperationEnabled](#)" status.
 - The **Diagnostics** tab and [C00158](#) display all active sources for the controller inhibit.
2. Select the respective control signals via the digital inputs (see sections below).

**Note!**

Observe the actual speed value (display in [C00051](#)) as well as the [LED status displays](#). (📖 674)

Homing

1. Request "homing" mode:
Set digital input DI5 to LOW level and digital input DI6 to HIGH level in order to select the profile 1 and request the "homing" mode at the same time.
2. Start homing:
Set digital input DI7 to HIGH level ("alternative function PosExecute").
3. Complete homing when home position has been reached:
Reset digital input DI7 to LOW level.

Positioning

1. Request "positioning" mode:
Set both digital inputs DI5 and DI6 to HIGH level to select the profile 3 and request the "positioning" mode at the same time.
2. Start positioning:
Set digital input DI7 to HIGH level ("alternative function PosExecute").
3. Complete positioning if target position has been reached:
Reset digital input DI7 to LOW level.

**Tip!**

The active operating mode ([C01243](#)) in the signal flow can also be controlled by means of the setting of the switch in the "Motion Control Kernel" block.

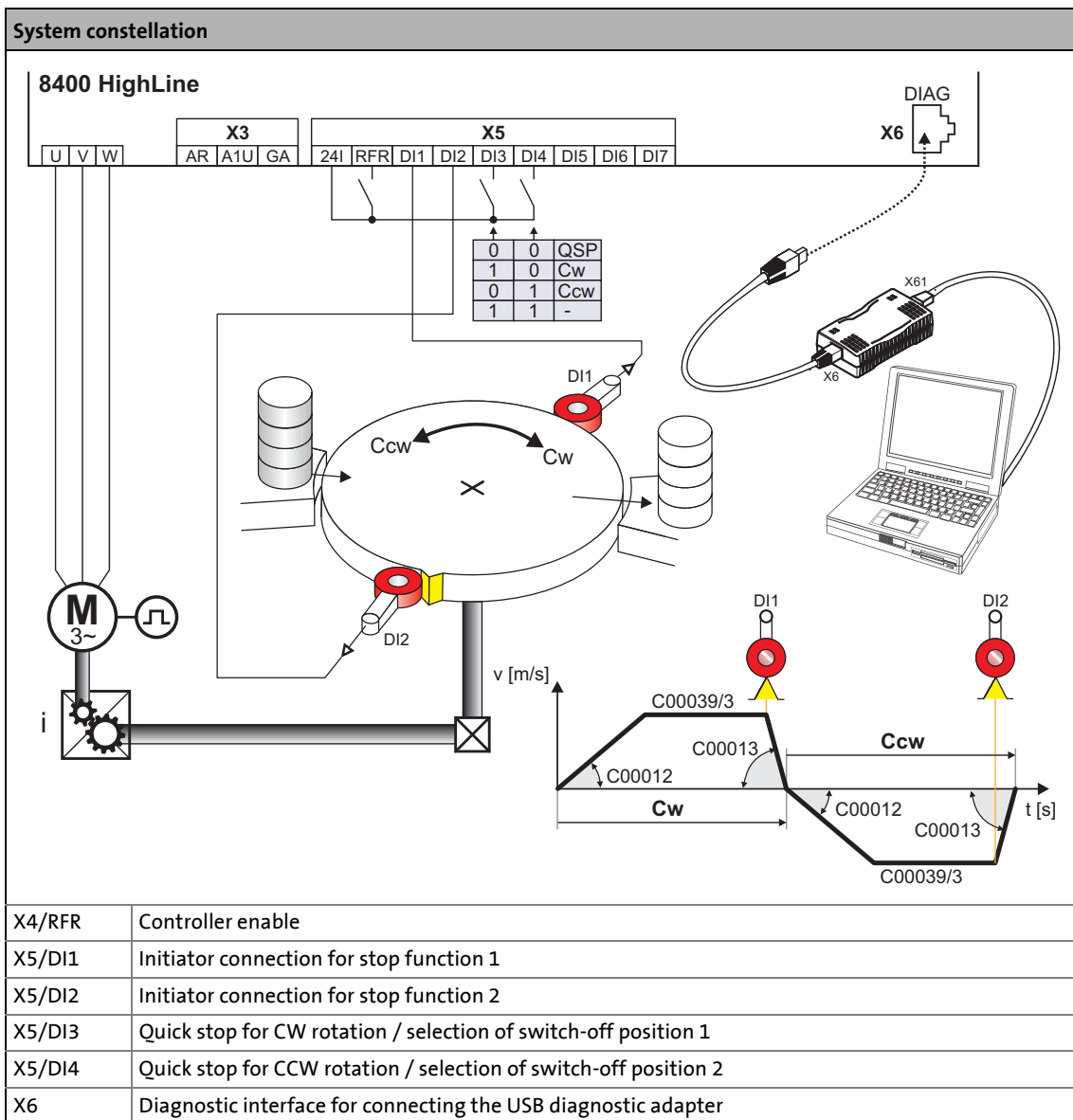
Related topics:

- ▶ ["Inhibit at power-on" auto-start option](#) (📖 124)
- ▶ [Trouble-shooting during commissioning](#) (📖 56)
- ▶ [Diagnostics & error management](#) (📖 673)

**Note!**

Take all the necessary safety precautions before you carry out the following commissioning steps and switch the device on!

► [Safety instructions with regard to commissioning](#) (53)



[3-3] Block diagram for wiring of the commissioning example for the "Switch-off positioning" application

Functional principle of a switch-off positioning without pre-switch off

In case of the switch-off positioning without pre-switch off shown above, it makes sense to use the "[Terminals 2](#)" control mode:

1. Set DI3 to HIGH level to activate CW rotation.
2. The drive accelerates along the acceleration ramp ([C00012](#)) up to the traversing speed set in [C00039/3](#).
3. After reaching the DI1 contact, the drive comes to a stop with quick stop (QSP) in the target position.
4. Reset DI3 to LOW level and set DI4 to HIGH level to activate CCW rotation now.
5. The drive is accelerated along the acceleration ramp ([C00012](#)) up to the traversing speed set in [C00039/3](#).
6. After the DI2 contact has been reached, the drive is braked to standstill with quick stop (QSP) in the initial position.



Tip!

- In order to avoid positioning inaccuracy due to signal propagation delays, the initiators can be directly evaluated by the drive controller. Limit switch evaluation can be configured in the drive controller. In code [C00488/x](#) you can change the method of detecting position signals from level evaluation to edge evaluation.
- In order to prevent unintended movements of the load in the target position, the use of a holding brake is recommended as an alternative to DC-injection braking (limited torque).
- The device terminals and their function assignment do not appear in the FB Editor. The assignment of (hardware) terminals to (software) functions is explained in the chapter "[Terminal assignment of the control modes](#)". ([530](#))

Commissioning steps

As shown in illustration [\[3-3\]](#), below find a description of the commissioning steps of the "Switch-off positioning" application without pre-switch off.

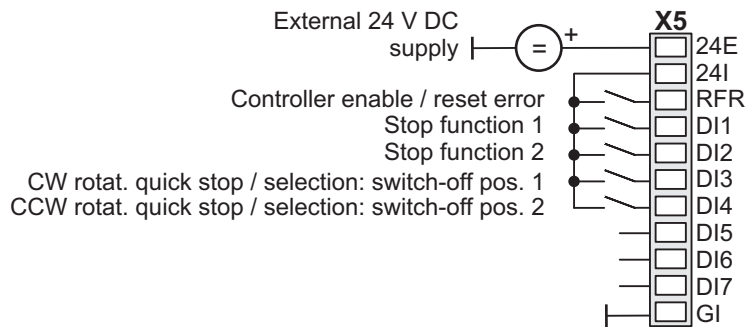
Please observe the sequence of the steps in the following chapters and follow them through carefully. This will help you to commission your controller quickly and as safely as possible:

- ▶ [Prepare controller for commissioning](#) ([84](#))
- ▶ [Creating an »Engineer« project & going online](#) ([85](#))
- ▶ [Parameterising the motor control](#) ([86](#))
- ▶ [Parameterise application](#) ([87](#))
- ▶ [Saving parameter settings safe against mains failure](#) ([89](#))
- ▶ [Enable controller and test application](#) ([89](#))

Prepare controller for commissioning

- Refer to the mounting instructions supplied with the drive controller to find help on how to correctly design the power connections to match the requirements of your device.

- In case of the application shown in illustration [3-3], switch-off positioning without pre-switch off, wiring according to the "Terminals 2" control mode makes sense:



- Without motor operation: Connect external 24 V supply.
- With motor operation: Connect mains voltage.

If the green "DRV-RDY" LED is blinking and the red "DRV-ERR" LED is off, the controller is ready for operation and commissioning can proceed.

Related topics:

- ▶ [Automatic restart after mains connection/fault...](#) (📖 124)
- ▶ [LED status displays](#) (📖 674)

3.9.2 Creating an »Engineer« project & going online



You can find detailed information on the general use of the »Engineer« in the online help which you can call with **[F1]**.

- The chapter "Working with projects" describes, among other things, all options of the *Start-up wizard* which are available to create a new »Engineer« project.

The following steps serve to describe a general method for creating a project with the **Select component from catalogue** option. For this purpose, individual components (controller, motor, etc.) are selected from selection lists.

1. Start the »Engineer«.
2. Create a new project with the *Start-up wizard* and the **Select component from catalogue** option:
 - In the **Component** step, select the 8400 TopLine controller.
 - In the **Device modules** step, select the available communication module.
 - In the **Application** step, select the "Switch-off positioning" application. (The application can also be selected any time afterwards via the **Application parameter** tab or [C00005](#).)
 - Select the other components (motor/gearbox) to be added to the project in the **Other components** dialog step.

3. Go online.

After a connection to the controller has been established, the following status is displayed in the *Status line*:



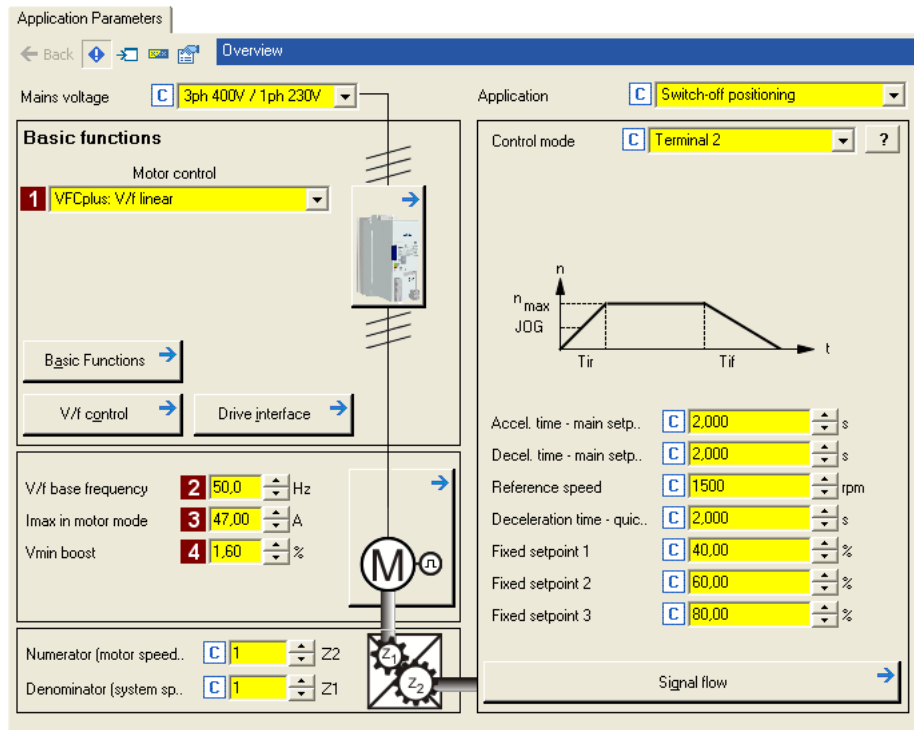
4. Transfer parameter set to the device.

This command serves to overwrite the current parameter settings in the controller by parameter settings of the »Engineer« project.

3.9.3 Parameterising the motor control

1. Select the **Application parameters** tab from the *Workspace*.

The motor control parameters, among other things, can be found on the left:



2. In the **1 Motor control** list field ([C00006](#)), select the desired motor control.
3. Adapt the motor control parameters:

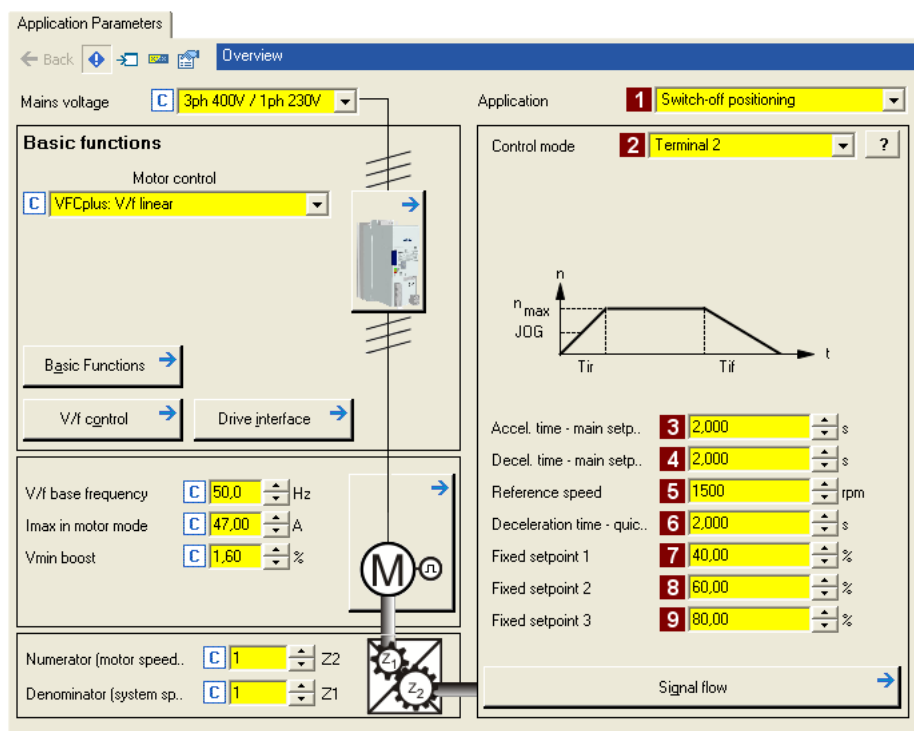
Parameter	Lenze setting		Info
	Value	Unit	
2 V/f base frequency (C00015)	50.0	Hz	► Adapting the V/f base frequency (164)
3 Imax in motor mode (C00022)	47.00	A	► Optimising the Imax controller (168)
4 Vmin boost (C00016)	1.60	%	► Adapting the Vmin boost (166)

Related topics:

- [Notes on motor control](#) (54)
- [Motor control \(MCTRL\)](#) (134)

3.9.4 Parameterise application

The application parameters can be found on the right side of the **Application parameter** tab:



1. In the **1 Application** list field ([C00005](#)), select the "Switch-off positioning" application (if you have not already done so while creating the project).
After the "Switch-off positioning" application is selected, the contents of the tab change, e.g. the **Process controller** and **Motor potentiometer** buttons are not shown any more.
2. In the **2 Control mode** list field ([C00007](#)) and in case of illustration [\[3-3\]](#), for the shown switch-off positioning without pre-switch off the "[Terminals 2](#)" control mode must be selected.
 - The corresponding wiring diagram is displayed in a pop-up window if you click the **?** button right to the list field.
 - For a detailed description, see the chapter "[Terminal assignment of the control modes](#)". ([441](#))

3. Adapt the application parameters:

Parameter	Lenze setting		Info
	Value	Unit	
3 Accel. time - main setpoint (C00012)	2.000	s	The setpoint is led via a ramp function generator with linear characteristic. The ramp function generator converts setpoint step-changes at the input into a ramp. Note: These settings only apply if no other ramp times have been selected at the L_NSet FB!
4 Decel. time - main setpoint (C00013)	2.000	s	
5 Reference speed (C00011)	1500	rpm	All speed setpoint selections are provided in % and always refer to the reference speed set in C00011 . The motor reference speed is indicated on the motor nameplate.
6 Decel. time - quick stop (C00105)	2.000	s	If quick stop is requested, motor control is decoupled from the setpoint selection and, within the deceleration time parameterised in C00105 , the motor is brought to a standstill ($n_{act} = 0$). ► Activate/deactivate quick stop (📘 108)
7 Fixed setpoint 1 (C00039/1)	40.00	%	Fixed setpoints are selected in [%] based on the reference speed (C00011). Fixed setpoint 2 must be smaller than fixed setpoint 3! Otherwise, the drive will be started with a low speed and accelerated after the pre-switch off.
8 Fixed setpoint 2 (C00039/2)	60.00	%	
9 Fixed setpoint 3 (C00039/3)	80.00	%	

**Tip!**

- Click the **Signal flow** button to go down one dialog level to the signal flow of the application with further possible parameter settings. See chapter "[Basic signal flow](#)". (📘 521)
- The preconfigured I/O connection in the selected control mode can be changed via configuration parameters. See chapter "[User-defined terminal assignment](#)". (📘 421)
- Low-jerk traversing profiles can be implemented by means of S-shaped ramps.
- In the case of high breakaway torques combined with horizontal motion sequences, "Sensorless vector control (SLVC)" can be used as motor control ([C00006](#)).
- For reversal of rotation direction (bidirectional motion), comprehensive configuration options are available in the drive controller (e.g. by means of the [L_DFlipFlop](#) function block).

More detailed information on the technology application:

- [TA "Switch-off positioning"](#) (📘 519)
- [Internal interfaces | application block "LA_SwitchPos"](#) (📘 522)
- [Process data assignment for fieldbus communication](#) (📘 539)
- [Terminal assignment of the control modes](#) (📘 530)
- [Setting parameters \(short overview\)](#) (📘 541)
- [Configuration parameters](#) (📘 543)

3.9.5 Saving parameter settings safe against mains failure

The parameter set must be saved to the device safe against mains failure to prevent parameter settings becoming lost due to mains switching.



Save parameter set.

3.9.6 Enable controller and test application



Stop!

Before stipulating a speed setpoint, check whether the brake in the form of a holding brake on the motor shaft has been released!



Note!

If the controller is enabled and the "Inhibit at power-on" auto-start option is activated in [C00142](#) (Lenze setting) when the mains is connected, the controller remains in the "[ReadyToSwitchOn](#)" state.

To be able to change to the "[SwitchedOn](#)" status, the controller enable must be deactivated first: set terminal X5/RFR to LOW level.

If the controller is in the "[SwitchedOn](#)" status:

1. Enable controller: Set terminal X5/RFR to HIGH level or close contact.
 - If there is no other active source for the controller inhibit, the controller changes from the "[SwitchedOn](#)" status to the "[OperationEnabled](#)" status.
 - The **Diagnostics** tab and [C00158](#) display all active sources for the controller inhibit.
2. Select the respective control signals via the digital inputs.



Note!

Observe the actual speed value (display in [C00051](#)) as well as the [LED status displays](#).
([674](#))

Related topics:

- ▶ ["Inhibit at power-on" auto-start option](#) ([674](#))
- ▶ [Trouble-shooting during commissioning](#) ([56](#))
- ▶ [Diagnostics & error management](#) ([673](#))

3.10 PC manual control

For the purpose of testing and demonstration and when an online connection has been established, the PC manual control enables the manual control of various drive functions from the »Engineer«.

Supported drive functions:

- Speed control (follow speed setpoint)
- Activate/deactivate quick stop
- Set/reset home position
- Manual jog
- Positioning (relative or absolute)

More control functions:

- Reset error message
- Set digital/analog outputs (in preparation)

Diagnostic functions:

- Display of the actual speed value and motor current (as time characteristic)
- Display of the current device status
- Display of the status determining error
- Display of the status of the digital/analog inputs (in preparation)

3.10.1 Activate PC manual control



Stop!

PC manual control must be explicitly activated by the user.

If PC manual control is activated, the controller is inhibited via device command ([C00002/16](#)) first.



Note!

With active PC manual control:

The online connection between PC and controller is monitored by the controller.

- If the online connection is interrupted longer than the timeout time set (Lenze setting: 2 s):
 - The error response "Fault" takes place, i.e. the motor becomes torqueless and coasts, if it has not yet been in standstill.
 - The "[Ck16: Time overflow manual control](#)" error message is entered into the logbook.

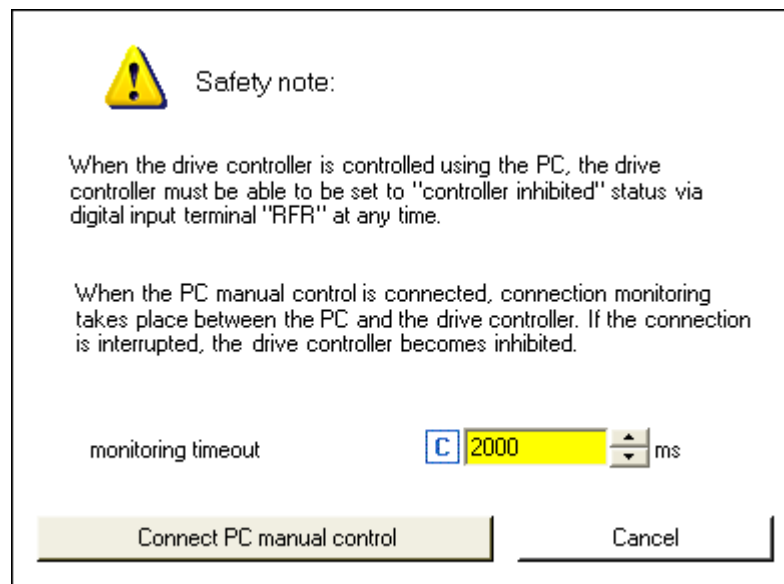
PC manual control provides the **Motion Control Kernel** and the motor interface with all required control signals and setpoint signals.

- The available application (function block interconnection) is now decoupled from these interfaces, but is continued to be processed and remains unchanged.
- It does not matter what type of motor control is set in [C00006](#).



How to activate the PC manual control:

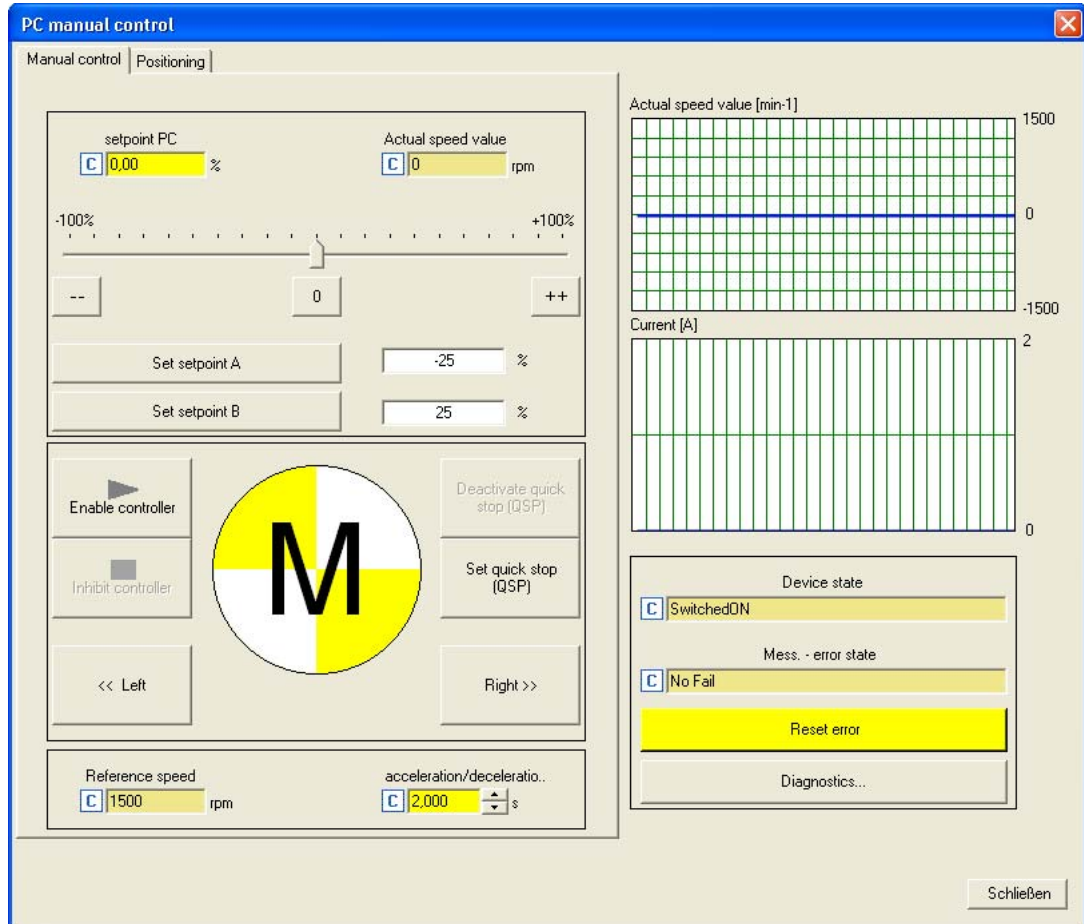
1. If an online connection to the controller has not been established yet:
 - Go online.
2. Select the **Application parameters** tab from the *Workspace*.
3. Go to the *Overview* dialog level and click the **PC manual control** button.
 - First, the following safety note is displayed:



- Click the **Cancel** button to abort the action and close the dialog box.
 - The **Timeout monitoring** input field serves to adapt the timeout for monitoring the connection between the PC and the controller.
4. To acknowledge the note and activate PC manual control:
 - Click the **Connect PC manual control** button.
 - The controller is inhibited via device command ([C00002/16](#)).
 - The *PC manual control* operator dialog is displayed.

PC manual control - operator dialog

On the left-hand side, the *PC manual control* operator dialog includes several tabs which serve to select various control functions. On the right-hand side, setpoint and status displays are provided for diagnostic purposes:



Note!

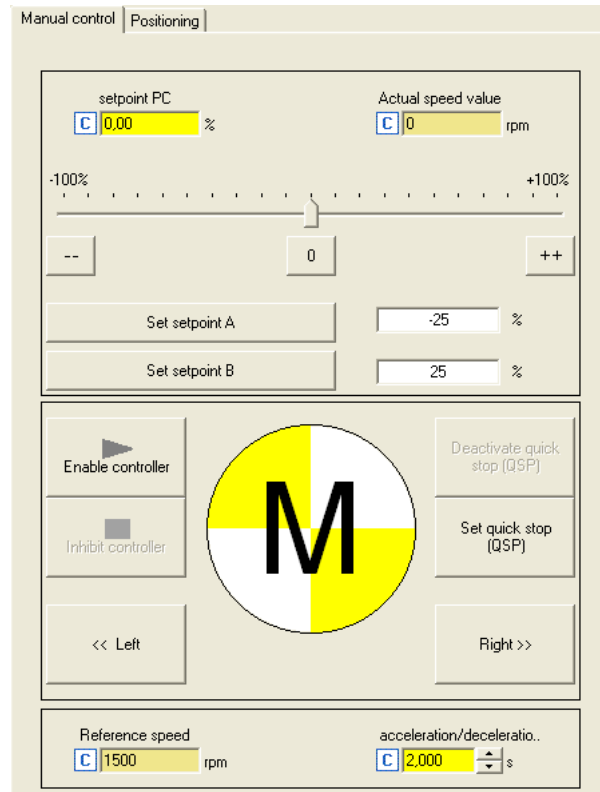
PC manual control can be exited any time by clicking the **Close** button.

If you exit PC manual control or change to another tab, the controller is inhibited via device command ([C00002/16](#)), i.e. the motor becomes torqueless and is coasting unless it already is at standstill.

The different versions are described in the following chapters.

3.10.2 Speed control

Via the **Speed control** tab, simply make the drive rotate in the "Speed follower" operating mode without the need to set control parameters or feedback systems:



How to easily rotate the motor:

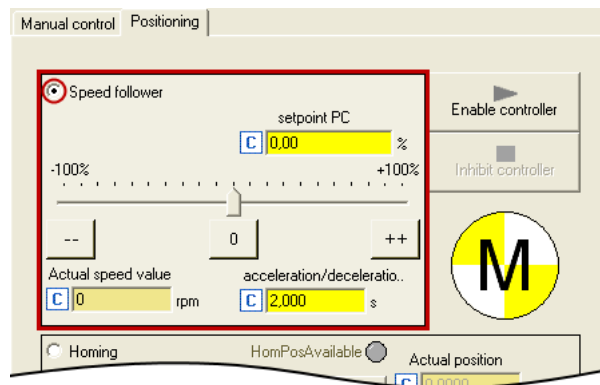
1. Set the desired speed setpoint in [%] based on the reference speed, e.g. directly in the **Setpoint PC** input field or via the slider.
 - Via the -- / 0 / ++ buttons, the currently set speed setpoint can be reduced/increased in steps of 10 percent or set to zero.
 - Via the **Set setpoint A/B** buttons, the speed setpoint can be set to a previously set constant value A/B.
2. To start the speed follower:

Enable the controller via the **Enable controller** button.

 - Please observe that the controller will not be enabled if other sources of controller inhibit (e.g. terminal RFR) are active.
 - The enabled drive now follows the defined speed setpoint.
 - In order to prevent shocks or overload at higher setpoint changes, the speed setpoint is lead via a linear ramp generator with adjustable acceleration/deceleration time.
 - Via the **Inhibit controller** button, the controller can be inhibited again, i.e. the motor becomes torqueless and is coasting unless it already is at standstill.

Further functions:

- If the **Set quick stop (QSP)** button is clicked, the motor is braked to a standstill within the deceleration time parameterised in [C00105](#).
 - Via the **Deactivate quick stop (QSP)** button, the quick stop can be deactivated.
- Via the << **Left** and **Right** >> buttons, the direction of rotation can be changed.
- The "Speed follower" operating mode can also be activated via the second tab **Positioning** without the previously described functions:



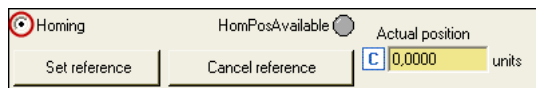
3.10.3 Set/reset home position

The measuring system in the machine is selected by means of homing and the 0 position is set within the possible physical travel range.



Detailed information on the "Homing" operating mode is provided in chapter "Basic drive functions" in subchapter "[Homing](#)". ([book 606](#))

The changeover to the "Homing" operating mode is effected by selecting the option of the same name on the **Positioning** tab:



How to set the reference manually with standing drive:

Click the **Set reference** button.

The current actual position in the machine measuring system now corresponds to the home position set in [C01227/2](#) (Lenze setting: 0.0000 units).



Stop!

If you set the reference with PC manual control, the drive is referenced with it.

If another home position is used for normal operation:

Click the **Cancel reference** button and reset the status signals *HomPosAvailable* and *HomePosDone* in the MCK status word in order that no mechanical problems can occur during normal operation.

- Setpoints and actual positions remain untouched until a renewed reference setting or homing.

3.10.4 Manual jog

In the "Manual jog" mode, the drive can be traversed manually in a clockwise or anticlockwise direction.



You can find detailed information on the "Manual jog" mode in the chapter entitled "Basic drive functions" in the subchapter "[Manual jog](#)". (625)

The change to the "Manual jog" mode can be made by selecting the correspondent option on the **Positioning** tab:

Manual control			
<< Left	speed 1	Deceleration	
	1 360,0000 units/s	3 720,0000 units/s	
Right >>	Acceleration	S-ramp time	
	2 720,0000 units/s	4 0,000 s	

- The profile parameters stored in the parameter set for the basic "manual jog" function are used:

Parameter	Lenze setting		Info
	Value	Unit	
1 Speed 1 (C01231/1)	360.0000	units/s	Manual jog speed
2 Acceleration (C01232/1)	720.0000	units/s ²	For accelerating and decelerating, different values can be set so that smooth starting and quick stopping of the drive can be implemented.
3 Delay (C01232/2)	720.0000	units/s ²	
4 S-ramp time (C01233/1)	0.000	s	In order to reduce jerking, the two ramps can be set in such a way that they are s-shaped. This is done by entering a relative S-ramp time.



How to traverse the drive manually in inching mode:

- If the controller is still inhibited, enable the controller via the **Enable controller** button.
 - Please observe that the controller will not be enabled if other sources of controller inhibit (e.g. terminal RFR) are active.

If the controller is in the "OperationEnabled" device status:
- Click << Left or Right >> (and keep it pressed) to traverse the drive in the corresponding direction of rotation.

3.10.5 Positioning (relative or absolute)

Positioning means that a workpiece/tool or material is moved from a starting position to a defined destination.



You can find detailed information on the "Positioning" mode in the chapter entitled "Basic drive functions" in the subchapter "[Positioning](#)". (□ 633)

The change to the "Positioning" operating mode and the simultaneous selection of the positioning mode (relative or absolute) is made by selecting the corresponding option on the **Positioning** tab:

The screenshot shows the "Positioning" tab interface. At the top, there are two radio buttons: "Relative positioning" (selected) and "Absolute positioning". Below these are several input fields for parameters:

- Run PDS:** Position (1) 360.0000 unit, Speed (2) 360.0000 unit/s
- Stop PDS:** Accel. (3) 720.0000 unit/s², Decel. (4) 720.0000 unit/s²
- Profile number:** A dropdown menu showing "01" and an "S-ramp time" (5) 0.000 s.

- The profile parameters stored in the parameter set for the basic "Positioning" function are used:

Parameter	Lenze setting		Info
	Value	Unit	
1 Position (C01301/1...15)	360.0000	units	Target position or distance to be traversed. • With "Relative positioning": Distance to starting position (current position). • With "Absolute positioning": Distance to defined zero position.
2 Velocity (C01302/1...15)	360.0000	units/s	Maximum speed at which the target is to be approached.
3 Acceleration (C01303/1...15)	720.0000	units/s ²	Stipulation of the change in speed at which maximum acceleration is to take place.
4 Delay (C01304/1...15)	720.0000	units/s ²	Stipulation of the change in speed at which maximum deceleration to a standstill is to take place.
5 S-ramp time (C01306/1...15)	0.000	s	A profile is traversed with S-shaped ramps by defining an S-ramp time for it.

**Note!**

In order that no complex travel motions occur, no forwarding to following profile set in the profile data takes place with PC manual control!

You can find detailed information on entering profiles in the chapter entitled "Basic drive functions", subchapter "[Profile entry](#)". (□ 637)

**How to carry out positioning:**

1. Select the profile to be travelled (1 ... 15) in the **Profile number** list field.
2. If the controller is still inhibited, enable the controller via the **Enable controller** button.
 - Please observe that the controller will not be enabled if other sources of controller inhibit (e.g. terminal RFR) are active.

If the controller is in the "OperationEnabled" device status:

3. Click the **Run POS** button to start the positioning process.
 - Click the **Stop POS** button to stop an active positioning process anytime.

4 Device control (DCTRL)

This chapter provides information on internal device control as well as the device commands which can be executed via the subcodes of [C00002](#).

- The device control causes the controller to take defined device statuses.
- The device control provides a multitude of status information in many ways:
 - Visually via the [LED status displays](#) on the front of the controller. ([book 675](#))
 - As text messages in the [Logbook](#). ([book 682](#))
 - As process signals via the outputs of the [LS_DriveInterface](#) system block. ([book 127](#))
 - Via diagnostic / display parameters which are included in the »Engineer« parameter list as well as in the **Diagnostics** category in the keypad.



Note!

The device statuses of the controller are based on the operating statuses of the CiA402 standard. ▶ [Device state machine and device states](#) ([book 113](#))

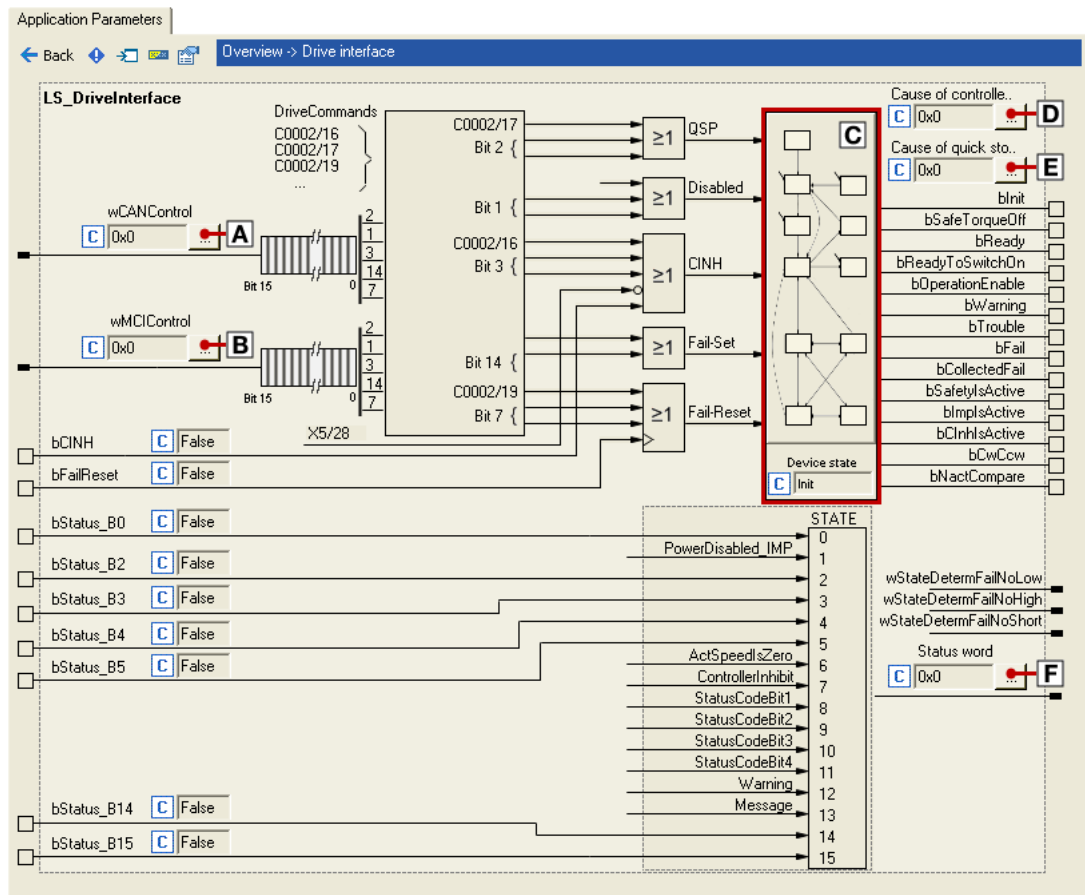


How to get to the parameterisation dialog of the device control:

1. »Engineer« Go to the *Project* view and select the 8400 TopLine controller.
2. Select the **Application parameters** tab from the *Workspace*.
3. Go to the *Overview* dialog level and click the **Drive interface** button.

Parameterisation dialog in the »Engineer«

The parameterisation dialog shows the input / output signals and the internal signal flow of the LS_DriveInterface system block which displays the device control in the function block editor:



Range / Meaning	Display parameter
A Display of the control word via system bus (CAN)	C00136/2
B Display of the control word via communication module (e.g. PROFIBUS)	C00136/1
C Display of the internal state machine and the current device status	C00137
D Display of all active sources of a controller inhibit	C00158
E Display of all active sources of a quick stop	C00159
F Display of the status word of the device control	C00150

4.1 Device commands (C00002/x)

This chapter describes the device commands which are provided in the subcodes of [C00002](#) and can be carried out using the keypad or, alternatively, the »Engineer« when an online connection has been established.

The device commands serve, among other things, to directly control the controller, to organise parameter sets, and to call diagnostic services.

Regarding the execution of the device commands, a distinction is drawn between:

- Device commands which have an immediate effect on control (e.g. "Activate quick stop")
 - After being called in [C00002/x](#), these device commands provide static status information ("On" or "Off").
- Device commands with longer execution duration (several seconds)
 - After being called in [C00002/x](#), these device commands provide dynamic status information ("Work in progress 20%" → "Work in progress 40%", etc.).
 - The execution of the device command has not finished successfully until the "Off / ready" status information is provided in [C00002/x](#).
 - In the event of an error, the "Action cancelled" status information is provided in [C00002/x](#). In this case, further details can be obtained from the status of the device command executed last which is displayed in [C00003](#).



Stop!

Before the supply voltage is switched off after a device command has been transmitted via [C00002/x](#), the device command must be checked for successful completion on the basis of the status information provided in [C00002/x](#)!

- This is of particular importance for device commands which save data to the memory module of the device. Incomplete storage processes may lead to data inconsistencies in the memory module.






Note!

- Before activating device commands by a master control, wait for the "Ready" signal of the controller.
- The device will reject a write process to [C00002/x](#) if the value is >1 and issue an error message.
- [C00003](#) displays the status of the device command that was executed last.

Activate device command

When an online connection has been established, simply use the »Engineer« to activate a device command by selecting the corresponding option from the **Parameters** tab in [C00002/x](#) ("0: off" or "1: On / start").

- Alternatively, the device command can also be activated via e.g. keypad or through a master control by writing to [C00002/x](#).
- Some of the frequently used device commands (such as "Save parameter set") can also be executed via the *Toolbar* icons of the »Engineer« when an online connection has been established:

Icon	Function
	Enable controller
	Inhibit controller
	Save parameter set (for 8400: Save all parameter sets)



Note!

Device commands that can be executed via the *Toolbar* of the »Engineer« always affect the element currently selected in the *Project view* including all subelements!

- If no controller but a system module is selected in the *Project view*, the corresponding device command will be activated in all lower-level controllers having an online connection with the »Engineer«.

Before the desired action is carried out, a confirmation prompt appears first, asking whether the action is really to be carried out.

Short overview of device commands

Device commands described in this chapter:

C00002 Subcode:	Device command	Controller inhibit required	Status information
1	Load Lenze setting	●	dynamic
6	Load all parameter sets	●	dynamic
11	Save all parameter sets		dynamic
16	Enable/Inhibit controller		static
17	Activate/deactivate quick stop		static
19	Reset error		static
21	Delete logbook		static
27	Device search function		static

Device commands described in other chapters:

C00002 Subcode:	Device command	Controller inhibit required	Status information
23	Motor parameter identification ▶ Automatic motor data identification	●	dynamic
25	Identify resolver error ▶ Optimising resolver behaviour	●	dynamic
26	CAN reset node ▶ Reinitialising the CANopen interface		static
28	Check MasterPin ▶ Unlocking the controller with a MasterPin	●	static
29	Set binding ID ▶ Device personalisation		static
30	Delete binding ID ▶ Device personalisation		static
31	Set password ▶ Password protection		static
32	Check password ▶ Password protection		static
33	Delete password ▶ Password protection		static
34	Identify pole position (360°) ▶ Pole position identification (PPI)	●	dynamic

4.1.1 Load Lenze setting

The [C00002/1](#) = "1: On / start" device command resets the parameters to the Lenze setting which are saved in the controller firmware.

- Can only be executed if the controller is inhibited; otherwise, the feedback [C00002/1](#) = "6: No access - controller inhibit" will be returned.
- All parameter changes made since the last saving of the parameter set will get lost!
- This device command has an effect on the settings of the parameters of the operating system, application and module.



How to load the Lenze setting:

1. If the controller is enabled, it must be inhibited, e.g. by executing the "Enable/Inhibit controller" device command ("[C00002/16](#) = "0: Off / ready").
2. Execute the "Load Lenze setting" device command:
[C00002/1](#) = "1: On / start"

The loading process may take a couple of seconds. After the device command has been called, [C00002/1](#) returns dynamic status information ("Work in progress 20 %" → "Work in progress 40 %" → "Work in progress 60 %", etc.).

Notes on execution time

The execution time of this device command usually is 2.5 s, independent of the communication module used. If - in addition to the device-internal time monitoring - a monitoring of the execution time is to be implemented for this device command in a higher-level control, the monitoring time has to be 2 ... 3 times higher.

4.1.2 Load all parameter sets

The [C00002/6](#) = "1: On / start" device command reloads all parameter settings from the memory module to the controller.

- Can only be executed if the controller is inhibited; otherwise, the feedback [C00002/6](#) = "6: No access - controller inhibit" will be returned.
- All parameter changes made since the last saving of the parameter set will get lost!
- This device command has an effect on the settings of the parameters of the operating system, application and module.



Note!

The controller is currently provided with one data record for all parameters, i.e. every parameter has a value. Several data records per controller are in preparation.

The basic function [Parameter change-over](#) provides a change-over between four sets with different parameter values for up to 32 freely selectable parameters. ([□ 859](#))



How to load the parameter settings from the memory module:

1. If the controller is enabled, it must be inhibited, e.g. by executing the "Enable/Inhibit controller" device command "[C00002/16](#) = "0: Off / ready".
2. Execute the "Load all parameter sets" device command:
[C00002/6](#) = "1: On / start"

The loading process may take a couple of seconds. After the device command has been called, [C00002/6](#) returns dynamic status information ("Work in progress 20 %" → "Work in progress 40 %" → "Work in progress 60 %", etc.).

Notes on execution time

The execution time of this device command depends on the communication module used. If - in addition to the device-internal time monitoring - a monitoring of the execution time is to be implemented for this device command in a higher-level control, the monitoring time has to be 2 ... 3 times higher than the times specified in the following table:

Communication module used	Typical execution time		
	StateLine C	HighLine C	TopLine C
Without communication module	3.5 s	3.5 s	3.5 s
PROFIBUS® or INTERBUS	3.5 s	3.5 s	3.5 s
EtherCAT®, PROFINET® or EtherNet/IP™	4.0 s	3.5 s	4.0 s
Ethernet POWERLINK	15.0 s	15.0 s	15.0 s

4.1.3 Save all parameter sets

If parameter settings are changed in the controller, those changes will be lost after mains switching of the controller unless the settings have been saved explicitly.

The [C00002/11](#) = "1: On / start" device command saves the current parameter settings safe against mains failure to the memory module of the controller.



Note!

When the device is switched on, all parameters are automatically loaded from the memory module to the main memory of the controller.

Observe the following to avoid data inconsistencies which cause errors when the parameters are loaded from the memory module:

During the storage process:

- Do not switch off the supply voltage!
- Do not remove the memory module from the device!

The controller is currently provided with one data record for all parameters, i.e. every parameter has a value. Several data records per controller are in preparation.



How to save the parameter settings to the memory module:

Execute the "Save all parameter sets" device command:

[C00002/11](#) = "1: On / start"

The storage process may take a couple of seconds. After the device command has been called in [C00002/11](#), dynamic status information ("Work in progress 20%" → "Work in progress 40%" → "Work in progress 60%", etc.) is returned.



Tip!

- This device command can also be activated via the icon in the *Toolbar*.
- The "[Load Lenze setting](#)" device command ([C00002/1](#) = "1: On / start") resets the parameter settings to the delivery status of the device.

Notes on execution time

The execution time of this device command depends on the communication module used. If - in addition to the device-internal time monitoring - a monitoring of the execution time is to be implemented for this device command in a higher-level control, the monitoring time has to be 2 ... 3 times higher than the times specified in the following table:

Communication module used	Typical execution time		
	StateLine C	HighLine C	TopLine C
Without communication module	2.0 s	2.5 s	2.5 s
PROFIBUS® or INTERBUS	3.5 s	3.5 s	4.0 s
EtherCAT®, PROFINET® or EtherNet/IP™	4.5 s	4.5 s	4.5 s
Ethernet POWERLINK	11.0 s	11.0 s	11.0 s

4.1.4 Enable/Inhibit controller

The [C00002/16](#) = "1: On / start" device command enables the controller, provided that no other source of a controller inhibit is active.

The [C00002/16](#) = "0: Off / ready" device command inhibits the controller again, i.e. the power output stages in the controller are inhibited and the speed/current controllers of the motor control are reset.

- The motor becomes torqueless and coasts, if it has not yet been in standstill.
- When the controller is inhibited, the status output *bClnhActive* of the [LS_DriveInterface](#) system block is set to TRUE.
- When the controller inhibit request is reset, the drive synchronises to the actual speed. For this purpose,
 - If the flying restart circuit is activated in [C00990](#), the flying restart function parameterised in [C00991](#) is used for the synchronisation to the rotary or standing drive. ▶ [Flying restart function](#) (□ 264)
 - In the case of an operation with feedback, the actual speed is read out by the encoder system.
 - In the case of a sensorless vector control (SLVC), the actual speed from the motor model of the motor control is used for the synchronisation.
- [C00158](#) provides a bit coded representation of all active sources/triggers of a controller inhibit:

Bit	Cause/Source of controller inhibit
Bit 0	Terminal controller enable
Bit 1	CAN control word
Bit 2	MCI control word
Bit 3	SwitchOn
Bit 4	Application (LS_DriveInterface system block: <i>bClnh</i> input)
Bit 5	Device command (C00002/16)
Bit 6	Error with a "Fault"/"Trouble" error response or system error, respectively
Bit 7	Internal signal
Bit 8	Reserved
Bit 9	Reserved
Bit 10	AutoStartLock
Bit 11	Motor parameter identification
Bit 12	Automatic brake operation
Bit 13	DCB-IMP
Bit 14	Reserved
Bit 15	Reserved



Tip!

The controller can also be enabled or inhibited via the  and  toolbar icons.

4.1.5 Activate/deactivate quick stop

The [C00002/17](#) = "1: On / start" device command activates the quick stop function, i.e. the motor control is separated from the setpoint selection, and within the deceleration time parameterised in [C00105](#) the motor is brought to a standstill ($n_{act} = 0$).

Parameter	Info	Lenze setting	
		Value	Unit
C00105	Decel. time - quick stop	2.000	s

- The motor is kept at a standstill during closed-loop operation.
- A pulse inhibit is set if the auto-DCB function has been activated via [C00019](#).
- From version 02.00.00, further options for the quick stop function can be activated in [C00104/1](#).
 ▶ [Optional settings](#) (109)
- [C00159](#) provides a bit coded representation of all active sources/triggers of a quick stop:

Bit	Cause/source for quick stop
Bit 0	Reserved
Bit 1	CAN control word (bit 2)
Bit 2	MCI control word (bit 2)
Bit 3	Reserved
Bit 4	Application (LS_MotorInterface system block: <i>bQspOn</i> input)
Bit 5	Device command (C00002/17)
Bit 6	Device error with "TroubleQSP" error response
Bit 7	Internal signal
Bit 8	Reserved
Bit 9	Reserved
Bit 10	Operating system
Bit 11	Reserved
Bit 12	MCK (System block LS_MotionControlKernel : Input <i>bQspOn</i>)
Bit 13	Reserved
Bit 14	Reserved
Bit 15	Reserved

Deactivate quick stop again

The [C00002/17](#) = "0: Off / ready" device command deactivates the quick stop again, provided that no other source of a quick stop is active.

4.1.5.1 Optional settings

From version 02.00.00, the options described in the following for the quick stop function can be activated in [C00104/1](#). In the Lenze setting, no option is activated.

Standstill position-controlled

When bit 0 is set in [C00104/1](#), the position control is activated at standstill.

- The basic conditions are shown in the [Flow diagram](#) for the quick stop function.
- More conditions for a proper function:
The inputs *nPosCtrlOutLimit_a* and *nPosCtrlPAdapt_a* at the [LS_MotorInterface](#) system block have to be set to 100 % (default setting for all technology applications).

Ramp position-controlled

If bit 1 is set in [C00104/1](#), the position control is activated while ramping down.

- The basic conditions are shown in the [Flow diagram](#) for the quick stop function.
- More conditions for a proper function:
The inputs *nPosCtrlOutLimit_a* and *nPosCtrlPAdapt_a* at the [LS_MotorInterface](#) system block have to be set to 100 % (default setting for all technology applications).

Continue following error

(from version 15.00.00)

If bit 2 is set in [C00104/1](#), the current following error is continued if the quick stop with position control is activated while ramping down.

Starting value is the setpoint speed

(from version 15.00.00)

If bit 3 is set in [C00104/1](#), the starting value for quick stop is the setpoint speed. If the bit is not set, the starting value for quick stop is the actual speed if this does not derive more than 5 rpm from the setpoint. This serves to prevent a jump to a setpoint with a high deviation.

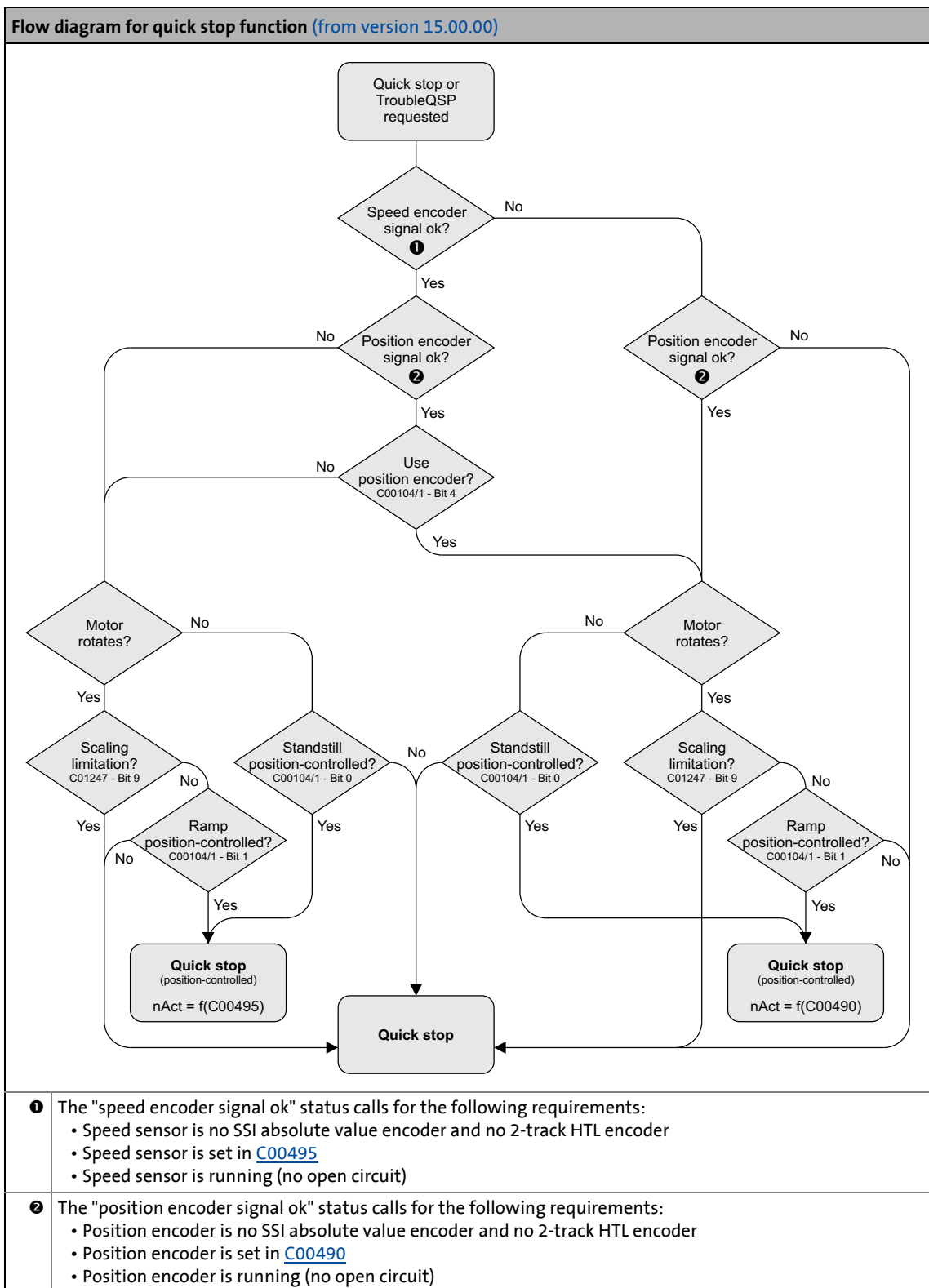
Use position encoder

(from version 15.00.00)

If bit 4 is set in [C00104/1](#), the position encoder is used instead of the speed encoder for quick stop with position control.

- The basic conditions are shown in the [Flow diagram](#) for the quick stop function.

4.1.5.2 Flow diagram



4.1.6 Reset error

The [C00002/19](#) = "1: On / start" device command acknowledges an existing error message if the error cause has been eliminated and thus the error is no longer pending.

- After the reset (acknowledgement) of the current error, further errors may be pending which must also be reset.
- The status determining error is displayed in [C00168](#).
- The current error is displayed in [C00170](#).

**Tip!**

An error message can also be acknowledged by activating the **Reset error** button in the **Diagnostics** tab.

Detailed information on error messages can be found in the "[Diagnostics & error management](#)" chapter. ([book icon](#) 673)

4.1.7 Delete logbook

The [C00002/21](#) = "1: On / start" device command deletes all logbook entries.



Tip!

To display the logbook in the »Engineer«, click the **Logbook** button on the **Diagnostics** tab. In the *Logbook* dialog box, it is also possible to delete all logbook entries by clicking the **Delete** button.

Detailed information on the logbook can be found in the "[Diagnostics & error management](#)" chapter. ([673](#))

4.1.8 Device search function


In some applications where controllers are installed in control cabinets or are positioned in a spacious plant, it is often difficult to locate a device connected online for e.g. maintenance work. There is an established online connection with the device but you do not know where the controller is located physically.

The [C00002/27](#) = "1: On / start" device command serves to carry out an "optical location":

- For the time set in [C00181/1](#), all four status LEDs at the front of the controller flash. Afterwards, the function is turned off automatically.
- If the device command is executed again within the set time period, the duration is extended accordingly.
- The setting [C00002/27](#) = "0: Off / ready" serves to abort or switch off the function.
- Adjustable time period: 0 ... 6000 s (Lenze setting: 5 s)

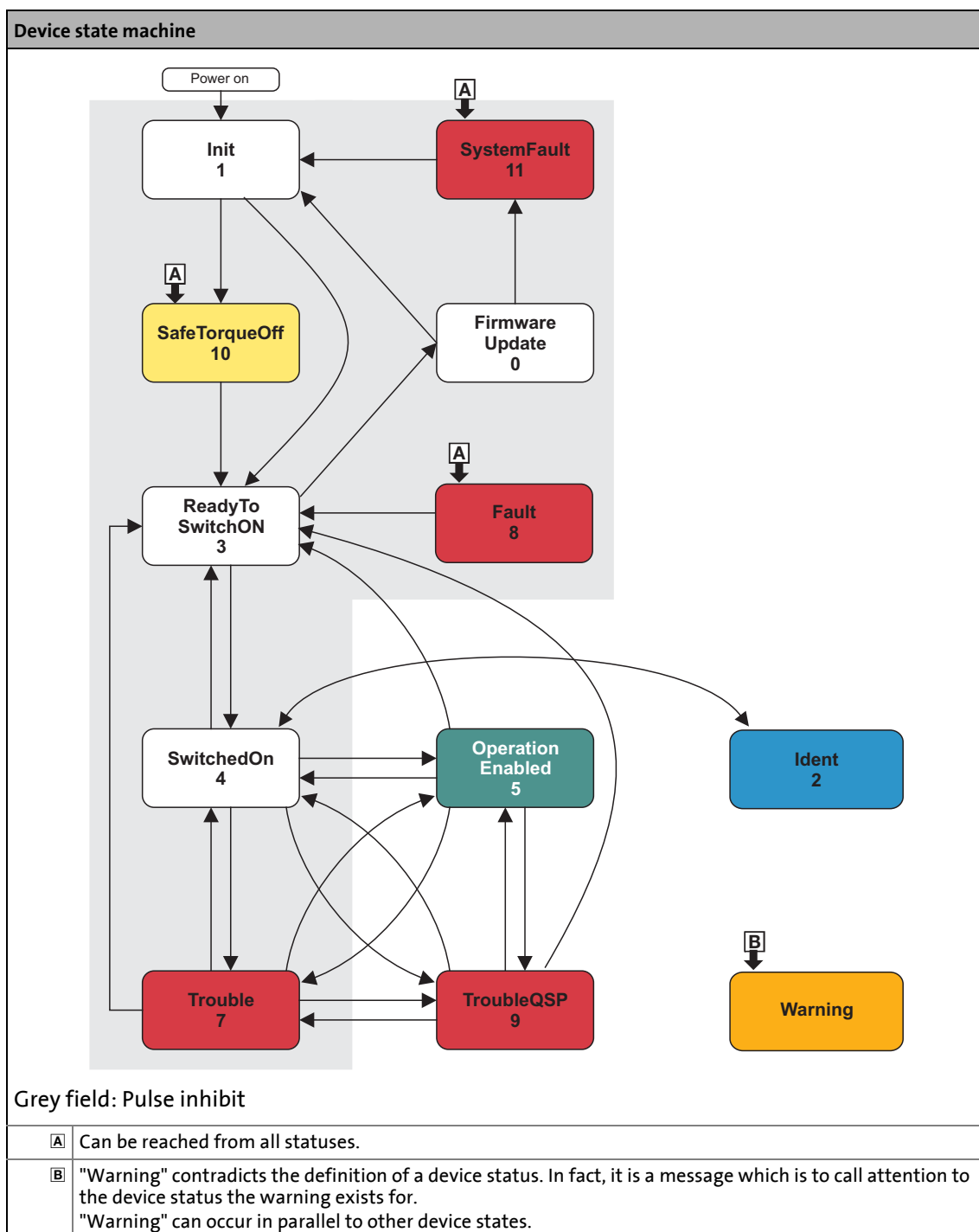


Tip!

The device search function can also be activated via the  *toolbar* icon.

4.2 Device state machine and device states

The behaviour of the controller is mainly determined by the current device status within the device state machine. Which device status is active and which device status is next depends on certain control signals (e.g. for controller inhibit and quick stop) and status parameters.



- The arrows between the device states mark possible state changes.
- The digits stand for the status ID (see table below).

- The change from one status to the other is carried out within a 1-ms cycle. If within this time there are several requests for status changes, the status with the higher priority is processed first (see table below).
- The [C00137](#) displays the current device status.
- [C00150](#) (status word) provides a bit coded representation of the current device status via bits 8 ... 11 (see table below).

ID	Device status (Display in C00137)	Priority	Status bits (Display in C00150)				Meaning
			Bit 11	Bit 10	Bit 9	Bit 8	
0	FirmwareUpdate	-	0	0	0	0	Firmware update function is active
1	Init	-	0	0	0	1	Initialisation active
2	Ident	-	0	0	1	0	Identification active
3	ReadyToSwitchOn	Prio 5	0	0	1	1	Device is ready to start
4	SwitchedOn	Prio 4	0	1	0	0	Device is switched on
5	OperationEnabled	Prio 1	0	1	0	1	Operation
6	-	-	0	1	1	0	-
7	Trouble	Prio 3	0	1	1	1	Fault active
8	Fault	Prio 7	1	0	0	0	Fault active
9	TroubleQSP	Prio 2	1	0	0	1	TroubleQSP is active
10	SafeTorqueOff	Prio 6	1	0	1	0	Safe torque off is active
11	SystemFault	Prio 8	1	0	1	1	System fault active

[4-1] Device statuses, priorities, and meaning of the status bits in the status word

4.2.1

FirmwareUpdate



Note!

This function may only be executed by qualified Lenze personnel!

4.2.2 Init

"DRV-RDY" LED	"DRV-ERR" LED	Display in C00137	Display in status word 1 (C00150)			
			Bit 11	Bit 10	Bit 9	Bit 8
OFF	OFF	Init	0	0	0	1

The controller is in this status immediately after switching on its 24 V supply voltage.

In the "Init" status, the operating system is initialised and all device components (communication module, memory module, power section, etc.) are identified. When identifying the power section, it is checked first if it is switched on or if the required voltage lies within the tolerance zone, respectively.

- The inverter is inhibited, i.e. the motor terminals (U, V, W) of the inverter are deenergised.
- The digital and analog inputs are not yet evaluated at this time.
- The bus systems (CAN, PROFIBUS etc.) do not work yet, i.e. communication is not possible.
- The application is not yet processed.
- The monitoring functions are not active yet.
- The controller cannot be parameterised yet and no device commands can be carried out yet.




Note!

If the 24V voltage supply is in the valid range (>19V) and the initialisation is finished, the device changes automatically to the "[ReadyToSwitchOn](#)" status.

If only the 24V voltage supply is available during the mains connection, the error message "[LU: Undervoltage in the DC bus](#)" is also entered into the logbook of the drive controller.

4.2.3 Ident

"DRV-RDY" LED	"DRV-ERR" LED	Display in C00137	Display in status word 1 (C00150)			
			Bit 11	Bit 10	Bit 9	Bit 8
	OFF	Ident	0	0	1	0

The controller has been provided with functions for automatically detecting the motor parameters, the resolver error and the pole position of a synchronous motor. If such an "identification" is active, the controller is in the "Ident" status.

The "Ident" device status can only be reached from the "[SwitchedOn](#)" device status, i.e. the controller must be inhibited first so that identification can be started afterwards via the corresponding device command:

Device command	Function	Detailed information
C00002/23	Motor parameter identification	► Automatic motor parameter identification
C00002/25	Identify resolver error	e ► Optimise resolver behaviour
C00002/34	Identify pole position (360°)	► Pole position identification

**Stop!**


During the identification of the motor parameters or the pole position, the controller does not respond to setpoint changes or control processes (e.g. speed setpoints, quick stop, torque limitations).

While an identification is being executed,

- the application remains active,
- all system interfaces (IO, bus systems, etc.) remain active,
- error monitoring remains active,
- the inverter is controlled independently of the setpoint sources.

After the identification is completed, the status changes back to "[SwitchedOn](#)".

4.2.4 SafeTorqueOff

"DRV-RDY" LED	"DRV-ERR" LED	Display in C00137	Display in status word 1 (C00150)			
			Bit 11	Bit 10	Bit 9	Bit 8
	OFF	SafeTorqueOff	1	0	1	0



Note!

[Up to and including version 13.xx.xx the following applies:](#)

This device status is only possible in connection with an integrated safety system and if a power section supply is available!

[From version 14.00.00 the following applies:](#)

This device status is only possible in connection with an integrated safety system!

Integrated safety systems with Inverter Drives 8400

Drive controller of the 8400 series can be equipped with the integrated "Safe torque off (STO)" safety system.

The integrated safety system is applicable on machines for the protection of persons.

The drive function is still carried out by the drive controller. The safety system provides safe inputs. If the safety system is activated, it executes control functions according to EN 60204-1 directly in the drive controller in case of errors.

Safety state

If the drive controller is switched off by the safety system, the device changes to the "SafeTorqueOff" status.

If the safety system deactivates the "Safe torque off (STO)" request, the device changes to the ["ReadyToSwitchOn"](#) status.




Detailed information on the integrated safety system can be found in the hardware manual!

The hardware manual contains important notes on the safety system which must be observed!

The hardware manual has been stored in electronic form on the data carrier supplied with the 8400 drive controller.

4.2.5 ReadyToSwitchOn

"DRV-RDY" LED	"DRV-ERR" LED	Display in C00137	Display in status word 1 (C00150)			
			Bit 11	Bit 10	Bit 9	Bit 8
	OFF	ReadyToSwitchOn	0	0	1	1

The controller is in this device status directly after the initialisation has been completed!

- The bus systems are running and the terminals and encoders are evaluated.
- The monitoring functions are active.
- The controller can be parameterised.
- The application is basically executable.



Note!

- The "ReadyToSwitchOn" state is not only activated after the mains connection, but also after the deactivation of "[Trouble](#)", "[Fault](#)" or "[SafeTorqueOff](#)".
- If [C00142](#) activates the autostart option "Inhibit at power-on" (Lenze setting), explicit deactivation of the controller inhibit after mains connection is always required for the controller to change from the "ReadyToSwitchOn" status to the "[SwitchedOn](#)" status.
- If only the 24V voltage supply is available during the mains connection, the error message "[LU: Undervoltage in the DC bus](#)" is entered into the logbook of the drive controller and the drive controller remains in the "ReadyToSwitchOn" status.




Danger!

If the "Inhibit at power-on" auto-start option has been deactivated in [C00142](#), the "ReadyToSwitchOn" status switches directly to the "[SwitchedOn](#)" status after mains connection.

► [Automatic restart after mains connection/fault...](#) (📖 124)

4.2.6 SwitchedOn

"DRV-RDY" LED	"DRV-ERR" LED	Display in C00137	Display in status word 1 (C00150)			
			Bit 11	Bit 10	Bit 9	Bit 8
	OFF	SwitchedON	0	1	0	0

The drive is in this device status if the DC bus voltage is applied and the controller is still inhibited by the user (controller inhibit).

- The bus systems are running and the terminals and encoders are evaluated.
- The monitoring functions are active.
- The application is basically executable.

If the controller inhibit is deactivated, the device changes to the "[OperationEnabled](#)" status and the motor follows the setpoint defined by the active application.



Tip!

[C00158](#) provides a bit coded representation of all active sources/triggers of a controller inhibit.


Depending on certain conditions, a status change takes place based on the "SwitchedOn" device status:

Change condition	Changeover to the device status
Control bit "EnableOperation" of all control channels = "1" AND terminal RFR = HIGH level (controller enable)	OperationEnabled
Control bit "SwitchOn" of a control channel = "0".	ReadyToSwitchOn
Identification requested.	Ident
Undervoltage in the DC bus.	Trouble/Fault (depending on C00600/1)
Error with error response "Trouble" occurs.	Trouble
Error with error response "TroubleQSP" occurs.	TroubleQSP

Related topics:

► [wCANControl/wMCIControl control words](#) (130)

4.2.7 OperationEnabled

"DRV-RDY" LED	"DRV-ERR" LED	Display in C00137	Display in status word 1 (C00150)			
			Bit 11	Bit 10	Bit 9	Bit 8
	OFF	OperationEnabled	0	1	0	1

The drive controller is in this device status if the controller inhibit is deactivated and no error ("Trouble" or "TroubleQSP") has occurred.

If the operation is enabled and the magnetisation in case of servo control (SC) and sensorless vector control (SLVC) has been completed, the motor follows the setpoint determined by the active application.

Depending on certain conditions, a status change takes place based on the "OperationEnabled" device status.



Change condition	Changeover to the device status
Control bit "EnableOperation" of a control channel = "0" OR terminal RFR = LOW level (controller inhibit).	SwitchedOn
Control bit "SwitchOn" of a control channel = "0".	ReadyToSwitchOn
Undervoltage in the DC bus.	Trouble/Fault (depending on C00600/1)
Error with error response "Trouble" occurs.	Trouble
Error with error response "TroubleQSP" occurs.	TroubleQSP

Related topics:

► [wCANControl/wMCIControl control words](#) (130)

4.2.8

TroubleQSP

"DRV-RDY" LED	"DRV-ERR" LED	Display in C00137	Display in status word 1 (C00150)			
			Bit 11	Bit 10	Bit 9	Bit 8
		TroubleQSP	1	0	0	1

This device status will be active as soon as a monitoring mode responds the error response "TroubleQSP" has been parameterised for.

- The drive is decelerated to standstill with torque within the deceleration time parameterised for quick stop independently of the defined setpoint and can be kept there.
- The device status can only be abandoned by acknowledging the error if the error cause is removed.
- When the controller is inhibited, it is possible to jump to the ["SwitchedOn"](#) status even during the error status since the controller inhibit function has a higher priority. As long as the error is pending and has not been acknowledged, the status is changed back to the "TroubleQSP" status when the controller is enabled afterwards.


Depending on certain conditions a status change takes place based on the "TroubleQSP" device status.

Change condition	Changeover to the device status
Control bit "SwitchOn" of a control channel = "0".	ReadyToSwitchOn
Control bit "EnableOperation" of all control channels = "1" AND terminal RFR = HIGH level (controller enable) AND error is reset by the control bit "ResetFault" AND no more errors are pending.	OperationEnabled
Control bit "EnableOperation" of a control channel = "0" OR terminal RFR = LOW level (controller inhibit) AND error is reset by the control bit "ResetFault" AND no more errors are pending.	SwitchedOn
A message is active in the system.	Trouble

Related topics:

- ▶ [wCANControl/wMCIControl control words](#) (📖 130)
- ▶ [Basics on error handling in the controller](#) (📖 673)
- ▶ [Error messages of the operating system](#) (📖 696)

4.2.9 Trouble

"DRV-RDY" LED	"DRV-ERR" LED	Display in C00137	Display in status word 1 (C00150)			
			Bit 11	Bit 10	Bit 9	Bit 8
OFF		Trouble	0	1	1	1

This device status becomes active as soon as a monitoring mode responds for which the error response "Trouble" has been parameterised.

- The motor has no torque (is coasting) due to the inhibit of the inverter.
- The "Trouble" device status is automatically abandoned if the error cause has been removed.



Note!

If in [C00142](#) the "Inhibit at trouble" is activated, explicit deactivation of the controller inhibit is required before this status can be abandoned.


Depending on certain conditions a status change takes place based on the "Trouble" device status.

Change condition	Changeover to the device status
The error cause is no longer active.	ReadyToSwitchOn
Control bit "EnableOperation" of all control channels = "1" AND terminal RFR = HIGH level (controller enable) AND the message has been cancelled.	OperationEnabled
Control bit "EnableOperation" of a control channel = "0" OR terminal RFR = LOW level (controller inhibit) AND the message has been cancelled.	SwitchedOn
In the system, there is an error configured on "TroubleQSP". AND the message has been cancelled.	TroubleQSP

Related topics:

- ▶ [wCANControl/wMCIControl control words](#) (📖 130)
- ▶ [Basics on error handling in the controller](#) (📖 673)
- ▶ [Error messages of the operating system](#) (📖 696)

4.2.10 Fault

"DRV-RDY" LED	"DRV-ERR" LED	Display in C00137	Display in status word 1 (C00150)			
			Bit 11	Bit 10	Bit 9	Bit 8
OFF		Fault	1	0	0	0

This device status will be active as soon as a monitoring mode responds the error response "Fault" has been parameterised for.

- The motor has no torque (is coasting) due to the inhibit of the inverter.
- The error must explicitly be reset ("acknowledged") in order to exit the device status, e.g. by the device command "[Reset error](#)" or via the control bit "ResetFault" in the control word *wCanControl* or *wMCIControl*.



Note!

If an undervoltage in the DC bus of the drive controller occurs (error message "LU"), the device changes to the "[Trouble](#)" status.

An additional error of higher priority leads the device into the "[Fault](#)" status.


According to the [Device state machine](#), the device changes to the "[ReadyToSwitchOn](#)" status after acknowledging the error although the undervoltage is still available!

If the "Inhibit at fault" auto-start option has been activated in [C00142](#), explicit deactivation of the controller inhibit is required before the status can be abandoned.

Related topics:

- ▶ [wCANControl/wMCIControl control words](#) (📖 130)
- ▶ [Basics on error handling in the controller](#) (📖 673)
- ▶ [Error messages of the operating system](#) (📖 696)

4.2.11 SystemFault

"DRV-RDY" LED	"DRV-ERR" LED	Display in C00137	Display in status word 1 (C00150)			
			Bit 11	Bit 10	Bit 9	Bit 8
OFF		SystemFault	1	0	1	1

This device status becomes active if a system fault occurs.

- The device status can only be abandoned by
 - mains switching or
 - a system restart (*in preparation*).

4.3

Automatic restart after mains connection/fault...

.../Error/undervoltage/loading of the Lenze setting

In [C00142](#), the starting performance of the controller after mains connection, undervoltage, loading of the Lenze setting as well as a "[Trouble](#)" or a "[Fault](#)" reset can be parameterised individually:

Auto-start option (C00142)		Lenze setting
Bit 0	"Inhibit at power-on" auto-start option	1 ≡ Inhibit is active
Bit 1	Inhibit at trouble	0 ≡ Inhibit is not active
Bit 2	Inhibit at fault	0 ≡ Inhibit is not active
Bit 3	Inhibit at undervoltage	1 ≡ Inhibit is active
Bit 4	Auto-start option "Inhibit at Lenze setting"	1 ≡ Inhibit is active
Bit 5	Reserved	0
Bit 6		
Bit 7		

**Note!**

In the Lenze setting, automatic restart after mains connection, undervoltage, and loading of the Lenze setting is inhibited.

4.3.1

"Inhibit at power-on" auto-start option

The auto-start option "Inhibit at power-on" prevents the change to the "[SwitchedOn](#)" status after mains connection if the controller is already enabled at mains connection.

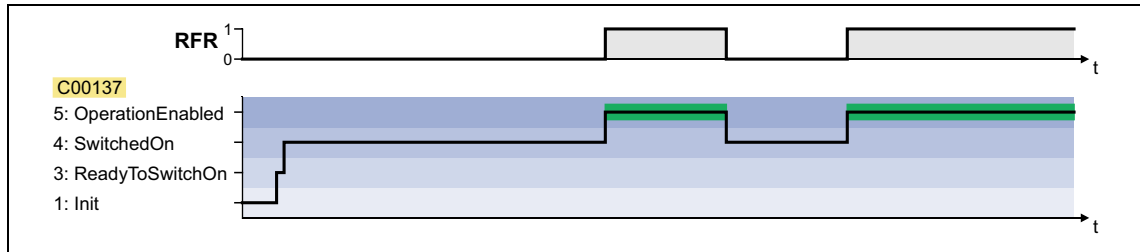
**Danger!**

If the "Inhibit at power-on" auto-start option has been deactivated in [C00142](#), (bit 0 = 0), the motor can directly start to run if the controller is enabled after mains connection!

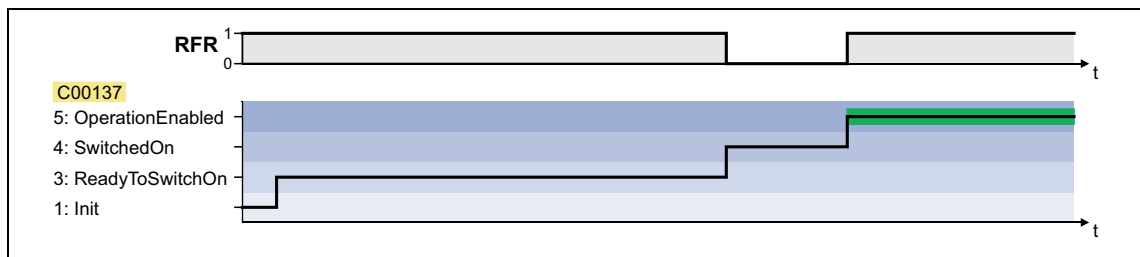
The following three cases describe the behaviour of the controller after mains connection depending on whether the controller is enabled and the set auto-start option. Here, it is assumed that after mains connection, no errors and trouble occur in the controller and the "EnableOperation" control bit in the *wDriveControl* is set to "1".

Case 1: No controller enable at mains connection

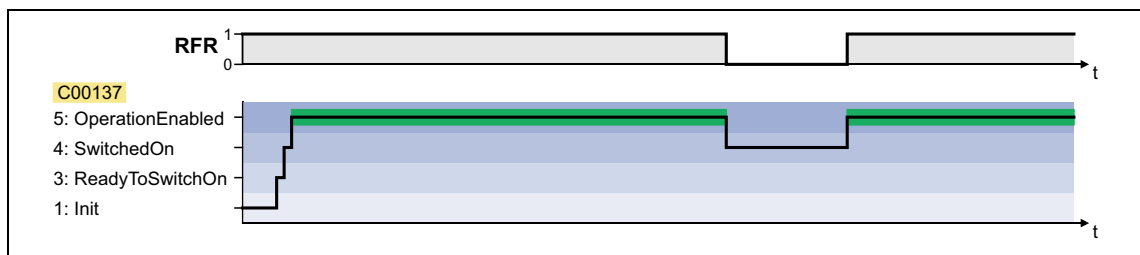
If the controller is not enabled at mains connection, the controller remains in the "[SwitchedOn](#)" status. Only with the controller enable, the device changes to the "[OperationEnabled](#)" status, independent of the set auto-start option:

**Case 2: Controller enable at mains connection and "Inhibit at power-on" activated**

If the controller is enabled at mains connection and the auto-start option "Inhibit at power-on" is activated, the controller remains in the "[ReadyToSwitchOn](#)" status. For changing to the "[SwitchedOn](#)" status, the controller enable must first be deactivated. Only when the controller is enabled again afterwards, the status changes to "[OperationEnabled](#)":

**Case 3: Controller enable at mains connection and "Inhibit at power-on" deactivated**

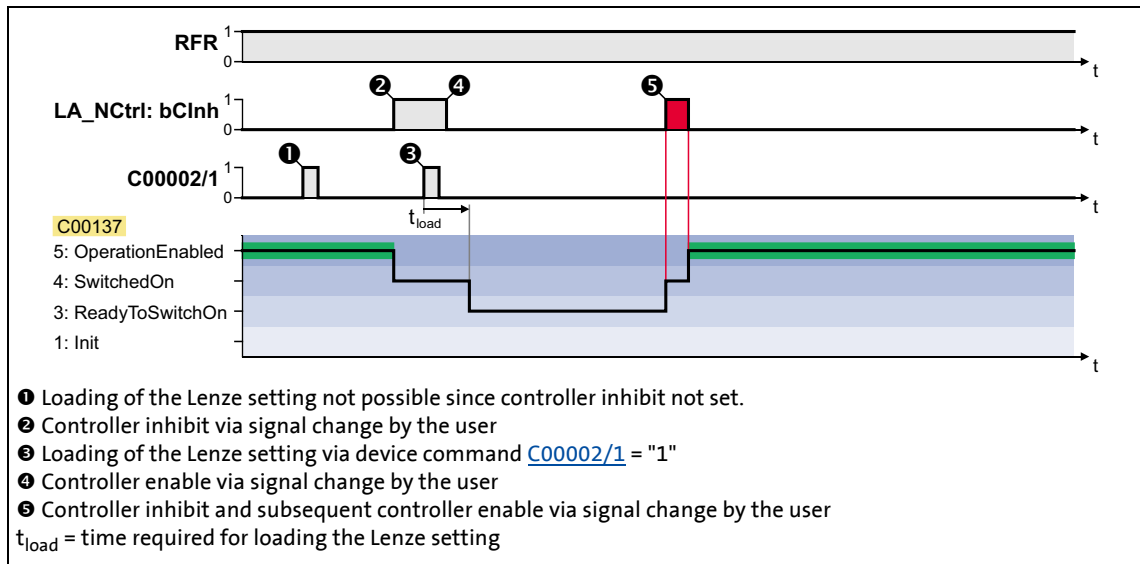
If in [C00142](#) the autostart option "Inhibit at power-on" is deactivated (bit 0 = 0), the status first changes from "[ReadyToSwitchOn](#)" to "[SwitchedOn](#)" and then to "[OperationEnabled](#)" after mains connection with an enabled controller:



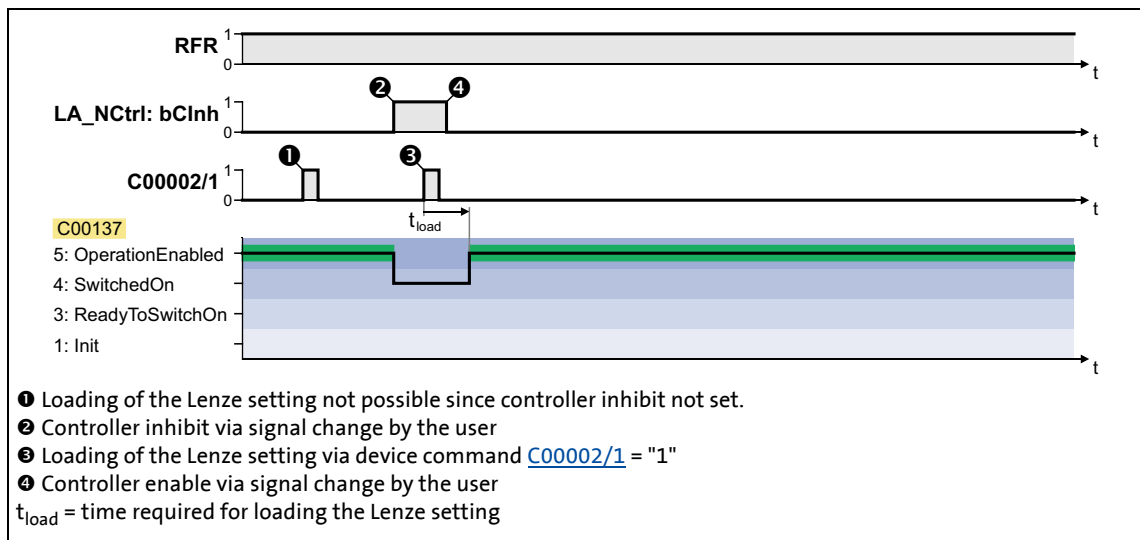
4.3.2 Auto-start option "Inhibit at Lenze setting"

The "Inhibit at Lenze setting" auto-start option configurable via bit 4 of [C00142](#) prevents the change to the "[SwitchedOn](#)" status after the Lenze setting has been loaded and the controller is enabled.

For a change to the "[SwitchedOn](#)" status, the controller enable must first be deactivated after the Lenze setting has been loaded. Only if the controller is enabled again afterwards, the status changes to "[OperationEnabled](#)":



[4-1] Example 1: Behaviour with activated auto-start option "Inhibit at Lenze setting" ([C00142](#): Bit 4 = "1")

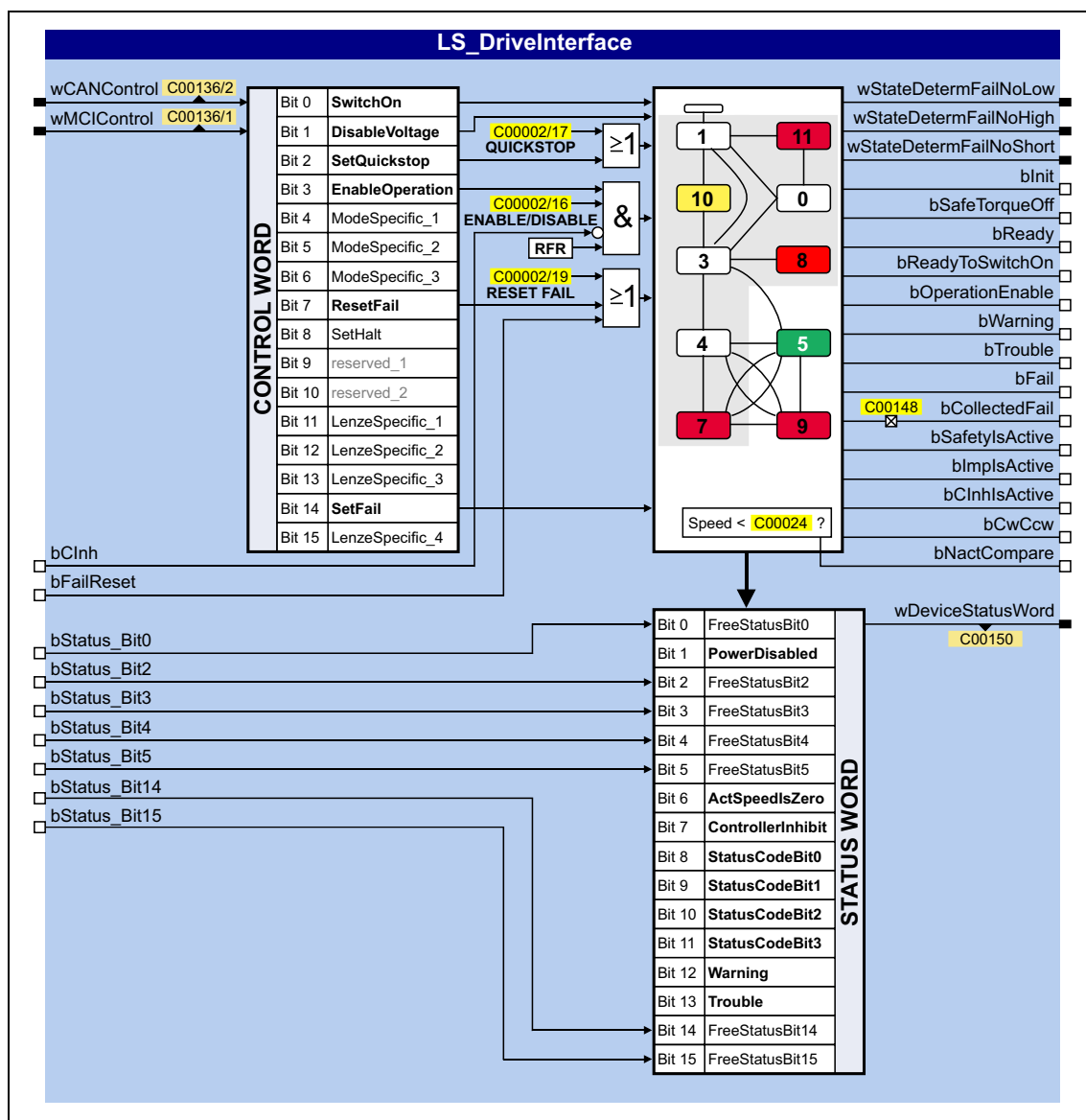


[4-2] Example 2: Behaviour with deactivated auto-start option "Inhibit at Lenze setting" ([C00142](#): Bit 4 = "0")

4.4

Internal interfaces | "LS_DriveInterface" system block

The LS_DriveInterface system block displays the device control in the FB Editor.



Inputs

Identifier DIS code data type	Information/possible settings				
wCANControl C00136/2 WORD	Control word via system bus (CAN) <ul style="list-style-type: none"> The controller controlled by a master control (e.g. IPC) receives its control word by the CANopen system bus interface. The process data word is provided at this input by the upstream port block LP_CanIn1. For a detailed description of the individual control bits, see chapter "wCANControl/wMCIControl control words". (130) 				
wMCIControl C00136/1 WORD	Control word via communication module (e.g. PROFIBUS) <ul style="list-style-type: none"> The controller controlled by a master control (e.g. IPC) receives its control word by a plugged-in communication module. The process data word is provided at this input by the upstream port block LP_McIn1. For a detailed description of the individual control bits, see chapter "wCANControl/wMCIControl control words". (130) 				
bCInh C00833/36 BOOL	<div>▶ Enable/Inhibit controller (107)</div> <table> <tr> <td>FALSE</td><td>Enable controller: The controller switches to the "OperationEnabled" device state, if no other source of a controller inhibit is active. <ul style="list-style-type: none"> C00158 provides a bit coded representation of all active sources/triggers of a controller inhibit. </td></tr> <tr> <td>TRUE</td><td>Inhibit controller (controller inhibit): The controller switches to the "SwitchedOn" device state.</td></tr> </table>	FALSE	Enable controller: The controller switches to the " OperationEnabled " device state, if no other source of a controller inhibit is active. <ul style="list-style-type: none"> C00158 provides a bit coded representation of all active sources/triggers of a controller inhibit. 	TRUE	Inhibit controller (controller inhibit): The controller switches to the " SwitchedOn " device state.
FALSE	Enable controller: The controller switches to the " OperationEnabled " device state, if no other source of a controller inhibit is active. <ul style="list-style-type: none"> C00158 provides a bit coded representation of all active sources/triggers of a controller inhibit. 				
TRUE	Inhibit controller (controller inhibit): The controller switches to the " SwitchedOn " device state.				
bFailReset C00833/37 BOOL	<div>▶ Reset error message (700)</div> <table> <tr> <td>FALSE → TRUE</td><td>The current error is reset.</td></tr> </table>	FALSE → TRUE	The current error is reset.		
FALSE → TRUE	The current error is reset.				
bStatus_Bit0 bStatus_Bit2 bStatus_Bit3 bStatus_Bit4 bStatus_Bit5 bStatus_Bit14 bStatus_Bit15 C00833/38 ... 44 BOOL	Freely assignable bits in the status word of the controller <ul style="list-style-type: none"> You can use these bits for returning information to the master control (e.g. IPC). 				
bFree_1 bFree_2 bFree_3 bFree_4 C00833/45 ... 48 BOOL	Reserved inputs have no function				

Outputs

Identifier DIS code data type	Value/meaning	
wDeviceStatusWord C00150 WORD	Status word of the controller (based on DSP-402) <ul style="list-style-type: none"> The status word contains all information relevant for controlling the controller. The status word is sent as a process data word to the master control via a port block: <ul style="list-style-type: none"> Port block LP_CanOut1 when the CANopen system bus interface is used or Port block LP_MciOut when a plugged-in communication module is used (e.g. PROFIBUS). For a detailed description of each status bit see chapter "wDeviceStatusWord status word". (□ 132) 	
wStateDetermFailNoLow WORD	Display of the status determining error (32-bit error number, Low-Word) <ul style="list-style-type: none"> If the "Use I16BitFailNo" (bit 15 = "1") option is activated in C00148, the short 16-bit error number (wStateDetermFailNoShort) is provided via this output as well. In this case, the wStateDetermFailNoHigh output is "0". Advantage: The bus transfer of the error numbers is possible via a data word without changing the interconnection of the technology application. 	
wStateDetermFailNoHigh WORD	Display of the status determining error (32-bit error number, High-Word)	
wStateDetermFailNoShort WORD	Display of the status determining error (16-bit error number)	
bInit BOOL	TRUE	"Init" device status is active
bSafeTorqueOff BOOL	TRUE	"SafeTorqueOff" device status is active
bReady BOOL	TRUE	"SwitchedOn" device status is active
bReadyToSwitchOn BOOL	TRUE	"ReadyToSwitchOn" device status is active
bOperationEnable BOOL	TRUE	"OperationEnabled" device status is active
bWarning BOOL	TRUE	A warning is indicated
bTrouble BOOL	TRUE	"Trouble" device state is active
bFail BOOL	TRUE	"Fault" device state is active
bCollectedFail BOOL	TRUE	Group error: A device status according to the group error configuration in C00148 has occurred, the drive is not able to follow the setpoint selection.
bSafetyIsActive BOOL	TRUE	In preparation
bImplsActive BOOL	TRUE	Pulse inhibit is active
bClnhIsActive BOOL	TRUE	Controller inhibit is active
bCwCcw BOOL	FALSE	Motor rotates in CW direction
	TRUE	Motor rotates in CCW direction
bNactCompare BOOL	TRUE	During open-loop operation: Speed setpoint < Comparison value (C00024)
		During closed-loop operation: Actual speed value < Comparison value (C00024)

Option "Lock bFail at TroubleQSP"

The [TroubleQSP](#) device status gets active as soon as a monitoring function responds that has been parameterised for the "TroubleQSP" error response. Since the *bFail* status output is not set in this case, it is not recognisable after pulse inhibit due to e.g. automatic brake operation (as well for a higher-level control), why the drive is standing und does not start when the setpoint is selected. Only after an error reset, a setpoint is accepted again.

From version 02.00.00: If the "Lock bFail at TroubleQSP" option is activated (bit 14 = "1") in [C00148](#), the *bFail* status output is also set to TRUE if the device status is [TroubleQSP](#).

4.4.1 wCANControl/wMCIControl control words

The controller is controlled by a master control (e.g. IPC) via the *wCanControl* or *wMCIControl* control word, respectively.

- *wCANControl*: Control word via system bus (CAN)
 - The process data word is provided at the *wCanControl* input via the upstream [LP_CanIn1](#) port block.
 - Display parameter: [C00136/2](#)
- *wMCIControl*: Control word via a plugged-in communication module (e.g. PROFIBUS)
 - The process data word is provided at the *wMCIControl* input via the upstream [LP_MciIn1](#) port block.
 - Display parameter: [C00136/1](#)
- The bit assignment for the *wCanControl*/*wMCIControl* control words can be seen from the table below.

**Note!**

The assignment of bits 11 ... 13 and bit 15 depends on the technology application selected in [C00005](#)!

- See description of the corresponding technology application.

Bit	Name	Function
Bit 0	SwitchOn	1 ≡ Change to the "SwitchedOn" device status <ul style="list-style-type: none"> • This bit has to be set in the CAN AND MCI control word in order that the drive changes to the "SwitchedOn" device state. In order to reach the "ReadyToSwitchOn" state, it is sufficient to set the bit to 0 in of the two control words.
Bit 1	DisableVoltage	1 ≡ Inhibit inverter control (pulse inhibit)
Bit 2	SetQuickStop	Activate quick stop (QSP) <ul style="list-style-type: none"> ▶ Activate/deactivate quick stop (108)
Bit 3	EnableOperation	1 ≡ Enable controller (RFR) <ul style="list-style-type: none"> • This bit must be set in CAN AND in the MCI control word, otherwise the controller will be inhibited.
Bit 4	ModeSpecific_1	Reserved (currently not assigned)
Bit 5	ModeSpecific_2	
Bit 6	ModeSpecific_3	
Bit 7	ResetFault	1 ≡ Reset fault (trip reset) <ul style="list-style-type: none"> • Acknowledge error message (if the error cause has been eliminated).
Bit 8	SetHalt	1 ≡ Activate stop function <ul style="list-style-type: none"> • Stop drive via stopping ramp (in preparation).
Bit 9	reserved_1	Reserved (currently not assigned)
Bit 10	reserved_2	
Bit 11	LenzeSpecific_1	Assignment depends on the selected technology application <ul style="list-style-type: none"> • See description of the corresponding technology application.
Bit 12	LenzeSpecific_2	
Bit 13	LenzeSpecific_3	
Bit 14	SetFail	1 ≡ Set error (trip set)
Bit 15	LenzeSpecific_4	Assignment depends on the selected technology application <ul style="list-style-type: none"> • See description of the corresponding technology application.

**Tip!**

If a bus control is not wanted (e.g. in case of control via terminals):

Connect both control word inputs with the *wDriveCtrl* output signal of the [LS_ParFix](#) system block. This output signal has the fixed value "9", which corresponds to the following assignment:

- Bit 0, SwitchOn = 1
- Bit 3, EnableOperation = 1
- All others: 0

4.4.2 wDeviceStatusWord status word

The *wDeviceStatusWord* status word provided by the control system contains all information relevant for controlling the controller.

- The status word is sent as a process data word to the master control via a port block:
 - The **LP_CanOut1** port block if "CAN on board" is used or
 - the **LP_MciOut1** port block if a plugged-in communication module is used (e.g. PROFIBUS).
- Display parameter: [C00150](#)
- The bit assignment of the *wDeviceStatusWord* status word can be seen from the table below.

Bit	Name	Status
Bit 0	FreeStatusBit0	Free status bit 0
Bit 1	PowerDisabled	1 ≡ Inverter control inhibited (pulse inhibit is active)
Bit 2	FreeStatusBit2	Free status bit 2 (not assigned, freely assignable)
Bit 3	FreeStatusBit3	Free status bit 3 (not assigned, freely assignable)
Bit 4	FreeStatusBit4	Free status bit 4 (not assigned, freely assignable)
Bit 5	FreeStatusBit5	Free status bit 5 (not assigned, freely assignable)
Bit 6	ActSpeedIsZero	During open-loop operation: 1 ≡ Speed setpoint < Comparison value (C00024)
		During closed-loop operation: 1 ≡ Actual speed value < Comparison value (C00024)
Bit 7	ControllerInhibit	1 ≡ Controller inhibited (controller inhibit is active)
Bit 8	StatusCodeBit0	Bit coded display of the active device status ▶ Device state machine and device states (see table [4-1])
Bit 9	StatusCodeBit1	
Bit 10	StatusCodeBit2	
Bit 11	StatusCodeBit3	
Bit 12	Warning	1 ≡ A warning is indicated
Bit 13	Trouble	1 ≡ Controller is in the " Trouble " device status • E.g. if an overvoltage has occurred.
Bit 14	FreeStatusBit14	Free status bit 14 (not assigned, freely assignable)
Bit 15	FreeStatusBit15	Free status bit 15 (not assigned, freely assignable)

*This page has been left blank intentionally,
to present the following information more clearly.*

5 Motor control (MCTRL)

This chapter provides information on the parameter setting of the controller's internal motor control. The 8400 TopLine controller both supports synchronous and asynchronous motors.

Topics:

Basic settings:

- ▶ [Motor selection/Motor data](#)
- ▶ [Selecting the control mode](#)
- ▶ [Defining current and speed limits](#)

Description of the motor control types:

- ▶ [V/f characteristic control \(VFCplus\)](#)
- ▶ [V/f characteristic control - energy-saving \(VFCplusEco\)](#)
- ▶ [V/f control \(VFCplus + encoder\)](#)
- ▶ [Sensorless vector control \(SLVC\)](#)
- ▶ [Sensorless control for synchronous motors \(SLPSM\)](#)
- ▶ [Servo control \(SC\)](#)

Parameterisable additional functions:

- ▶ [Selection of switching frequency](#)
- ▶ [Operation with increased rated power](#)
- ▶ [Current-dependent stator leakage inductance Ppp\(I\)](#)
- ▶ [Flying restart function](#)
- ▶ [DC-injection braking](#)
- ▶ [Slip compensation](#)
- ▶ [Oscillation damping](#)
- ▶ [Phase sequence reversal for correcting misconnected UVW motor phases](#)
- ▶ [Field weakening for synchronous motors](#)

Further topics:

- ▶ [Position control/additive speed specification](#)
- ▶ [Braking operation/brake energy management](#)
- ▶ [Monitoring](#)

Internal interfaces (process signals):

- ▶ [Internal interfaces | System block "LS_MotorInterface"](#)
- ▶ [Internal status signals | System block "LS_DeviceMonitor"](#)

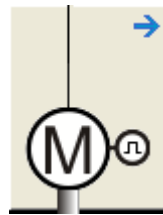
5.1 Motor selection/Motor data

The motor data term comprises all parameters that only depend on the motor and that only characterise the electrical behaviour of the machine. The motor data are independent of the application in which the controller and the motor are used.



Proceed as follows to open the dialog for parameterising the motor data:

1. »Engineer« Go to the *Project* view and select the 8400 TopLine controller.
2. Select the **Application parameters** tab from the *Workspace*.
3. Go to the *Overview* dialog level and click the following button:



Parameterisation dialog in the »Engineer«

Application Parameters

Overview -> Motor data

Motor selection

Selected motor:

Motor data

Rated motor power	<input type="text" value="0,08"/> kW	Actual speed value	<input type="text" value="0"/> rpm
Rated motor speed	<input type="text" value="2700"/> rpm	Motor voltage	<input type="text" value="0"/> V
Rated motor current	<input type="text" value="0,54"/> A	DC-bus voltage	<input type="text" value="0"/> V
Rated motor frequency	<input type="text" value="100"/> Hz	Motor current	<input type="text" value="0,00"/> A
Rated motor voltage	<input type="text" value="390"/> V	Thermal motor load (Fxt)	<input type="text" value="0,00"/> %
Motor cosine phi	<input type="text" value="0,50"/>		

- Via the **From Motor Catalogue** button, the motor catalogue can be opened to select another motor. ▶ [Selecting a motor from the motor catalogue in the »Engineer«](#) (139)
- Via the **From drive...** button, the motor data set in the controller can be copied to the »Engineer« when an online connection has been established.
- When an online connection has been established to the controller, the **Identification in progress...** button serves to automatically identify different motor data. ▶ [Automatic motor data identification](#) (141)
- The **Encoder/feedback system...** button serves to get to the settings for the encoder/feedback system, if available. ▶ [Encoder/feedback system](#) (314)

**Stop!**

Motors with electronic nameplates (ETS) must not be operated on 8400 controllers!

**Note!**

Sensorless vector control (SLVC) and sensorless control for synchronous motors (SLPSM) in particular requires the motor data parameters to be set. The motor data comprise the data of the motor nameplate and the data of the motor equivalent circuit.

If the motor has been selected via the motor catalogue of the »Engineer« or the motor data have been adapted offline using the »Engineer«, all motor data must then be copied to the controller and saved power-failure-proof to the memory module (device command: [C00002/11](#)) when an online connection has been established.

**Note!****Setting a rated motor frequency with a decimal position**

If the motor has a rated motor frequency with a decimal position (e.g. motor nameplate data "23.7 Hz"):

- [Up to and including version 02.xx.xx](#), the following motor nameplate data must be increased by a factor of 10:
 - [C00089](#): Rated motor frequency
(a value of "23.7 Hz", for instance, must be increased to 237 Hz.)
 - [C00081](#): Rated motor power
 - [C00087](#): Rated motor speed
 - [C00090](#): Rated motor voltage
- [From version 12.00.00](#), the rated motor frequency must be entered without decimal position to clearly identify the right motor type. (a value of "23.7 Hz", for instance, must be set to 23 Hz in [C00089](#))
 - [C01000](#) displays the set motor type (ASM or PSM).
 - [C00969](#) displays the set number of motor pole pairs.
- [From version 14.00.00 onwards](#), the motor type (ASM or PSM) can also be set manually in [C01001/1](#) for a clear identification.

**Note!**

If a rated motor speed is set for an asynchronous motor (ASM) in [C00087](#) which corresponds to a very high slip speed, the number of pole pairs is identified incorrectly. Moreover, a synchronous motor (PSM) is detected instead of an asynchronous motor (ASM) at certain slip speeds. Detailed information and possible remedies can be found here:

► [Application notes for asynchronous motors with high slip speed](#) (📖 148)

Motor data

In the parameterisation dialog, the data of the motor nameplate for the selected motor are displayed under "Motor data".

Parameter	Info
C00081	Rated motor power
C00087	Rated motor speed
C00088	Rated motor current
C00089	Rated motor frequency
C00090	Rated motor voltage
C00091	Motor cos φ

Actual values

When an online connection to the controller has been established, the following actual values are displayed in the parameterisation dialog under "Actual values":

Parameter	Info
C00051	Actual speed value
C00052	Motor voltage
C00053	DC-bus voltage
C00054	Motor current
C00066	Thermal motor load (I2xt)
Highlighted in grey = display parameter	

Adapting motor data manually

If a third party manufacturer's motor is used, the displayed motor data can exactly be adapted to the real motor by clicking the **From project...** button and selecting the "Own motor settings" entry from the **Motor selection** dialog box afterwards. For this purpose, the data of the motor nameplate and the equivalent circuit diagram must be available.



Tip!

For a better concentricity factor, we recommend to perform motor parameter identification of the third party manufacturer's motor first. The motor parameters can be manually adapted afterwards.

Improving the concentricity factor includes

- the adjustment of the inverter error characteristic to the drive system and
- the knowledge of the motor cable resistance.

Both factors are determined in the course of motor parameter identification.

► [Automatic motor data identification](#) (141)

Other motor data

Click the **Other motor data...** button and go to the *Other motor data* dialog box including the motor equivalent circuit (in the following for an asynchronous motor):

The dialog box titled "Other motor data" contains the following parameters and a circuit diagram:

- Motor stator resistance: 43000 mOhm
- Motor stator leakage inductance: 172.60 mH
- Motor rotor resistance: 86600 mOhm
- Motor magnetising current: 0.35 A
- Motor magnetising inductance: 879.0 mH
- VFC: V/f base frequency: 100.0 Hz
- Slip comp.: 10.00 %
- SLVC: Vp speed controller: 10.93
- SLVC: Ti speed controller: 100.0 ms
- Vp current controller: 345.20 V/A
- Ti current controller: 4.01 ms
- SC: Moment of inertia: 0.41 kg c

The circuit diagram shows a series combination of stator resistance and leakage inductance, followed by a parallel branch containing magnetising inductance and rotor resistance, all connected to a magnetising current source.

Parameter	Info	ASM	PSM
C00084	Motor stator resistance	●	●
C00085	Motor stator leakage inductance	●	●
C00082	Motor rotor resistance	●	
C00095	Motor magnetising current	●	
C00092	Motor magnetising inductance	●	
C00015	VFC: V/f base frequency	●	●
C00021	Slip compensation	●	
C00070/1	SLVC: Vp speed controller	●	
C00071/1	SLVC: Ti speed controller	●	
C00075	Vp current controller	●	●
C00076	Ti current controller	●	●
C00273	Moment of inertia	●	●
C00016	VFC: Vmin boost	●	●
C00070/2	SC: Vp speed controller	●	●
C00071/2	SC: Ti speed controller	●	●
C00070/3	SLPSM: Vp speed controller	●	●
C00071/4	SLPSM: Ti speed controller	●	●
C00072	SC: Tdn speed controller	●	●
C00011	Appl.: Reference speed	●	●
C00022	Imax in motor mode	●	●
C00966	VFC: Time const. slip comp.	●	
C00982	VFC-ECO: Voltage reduction ramp	●	
C00073/1	VFC: Vp Imax controller	●	●
C00077	SC: Vp field controller	●	
C00078	SC: Tn field controller	●	

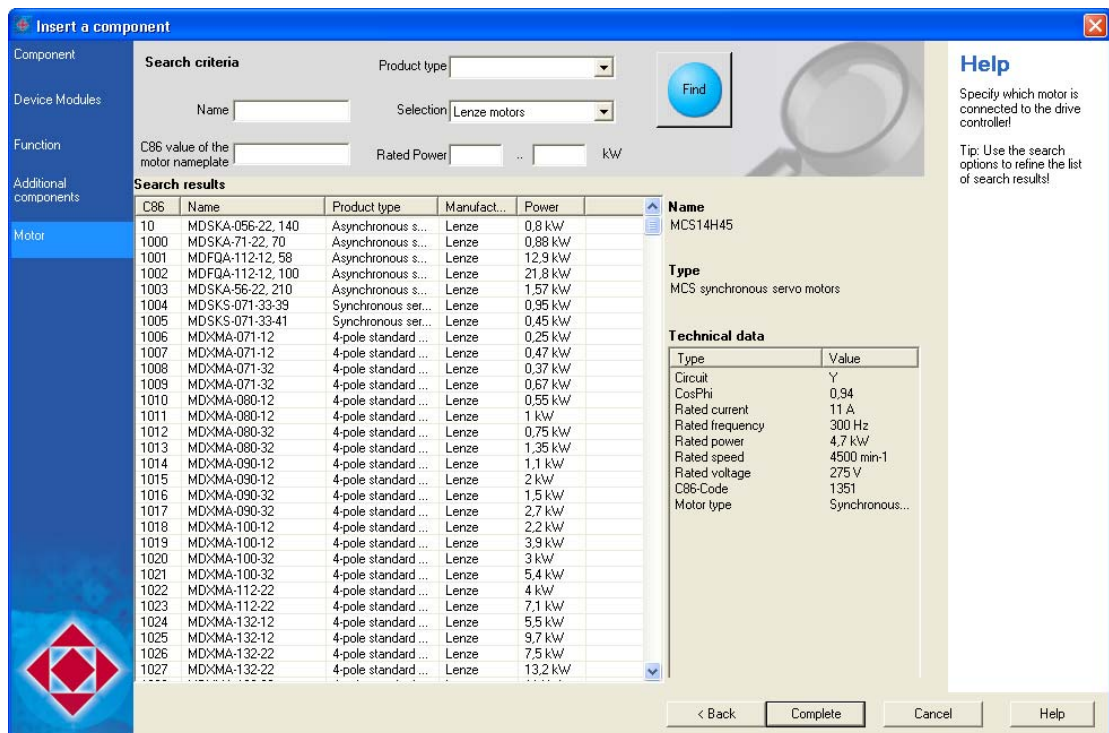
5 Motor control (MCTRL)

5.1 Motor selection/Motor data

- From version 12.00.00 onwards, [C01000](#) displays the set motor type (ASM or PSM).
- Generally, a synchronous motor without speed feedback can also be operated with the [V/f characteristic control \(VFCplus\)](#) control mode. The parameters for this control mode (e.g. V/f base frequency) thus also have an according influence on synchronous motors.

5.1.1 Selecting a motor from the motor catalogue in the »Engineer«

If you, when inserting the controller into the project in the dialog step "Other components", put a checkmark in the control field **Motor**, you can select as a further dialog step the motor for the controller from the motor catalogue:



- Alternatively, the motor can be inserted into the project at a later time via the **Insert a component** command.
- Go to the **Application parameters** tab in the *Overview* → *Motor data* dialog level and click the **From motor catalogue...** button to also reach the motor catalogue for the selection of another motor.

Accepting the default values of the motor

If a motor is selected from the motor catalogue at a later time, the *Use motor's default values* dialog box is displayed afterwards which includes all motor data of the selected motor. Please select here which of the default values are to be copied to the controller:

Use motor's default values

Controller: [8400 HighLine C V04.00.00 [8400 HighLine C V04.00.00]]

Motor: [SDSGA047-22, 100 (Y)]

Motor parameter

☐ Use selection of motor controller in C0006: [No default value available for this motor]

☒ Use following values in drive controller:

Code	Subcode	Description	Value	Unit
0015	000	VFC: V/f base frequency	100	Hz
0016	000	VFC: rpm boost	4.93	%
0021	000	Slip comp.	10	%
0073	001	VFC: Vp Imax controller	1.45	
0075	000	Vp current controller	345.2	V/A
0076	000	Ti current controller	4.01	ms
0077	000	SC: Vp field controller	1.22	
0078	000	SC: Tn field controller	24.5	ms
0081	000	Rated motor power	0.08	kW
0082	000	Motor rotor resistance	86600	mOhm

Path parameters for operation with zero load

☒ Use following values in drive controller:

Code	Subcode	Description	Value	Unit
0022	000	Imax in motor mode	0.95	A
0070	001	SLVC: Vp speed controller	10.93	
0070	002	SC: Vp speed controller	6.25	
0071	001	SLVC: Ti speed controller	100	ms
0071	002	SC: Ti speed controller	50	ms
0072	000	SC: Tdn speed controller	0	ms
0273	000	SC: Moment of inertia	0.41	kg cm ²

OK

- The listed motor parameters are already optimally preset for the selected Lenze motor. An adaptation is not required.
- The "plant parameter" term comprises all parameters that result from the combination of motor and load. These characterise the transfer behaviour of the entire controlled system.
 - The plant parameters depend on the application in which the controller and motor are used.
 - When a Lenze motor is selected in the »Engineer«, plant parameters are suggested for this motor for a load-free operation.



Tip!

If a third party manufacturer's motor is used, select a Lenze motor from the motor catalogue first which is similar in terms of current, voltage and speed rating. Adapt the preselected motor data exactly to the real motor afterwards.

5.1.2 Automatic motor data identification

The motor parameter identification serves to automatically identify the inverter characteristic, the influences of the motor cable and various motor parameters.



Note!

We strongly recommend motor parameter identification before the initial commissioning of the sensorless vector control (SLVC) and the sensorless control for synchronous motors (SLPSM).

Automatically identified motor parameters

Parameter	Info	ASM	PSM
C00015	V/f base frequency	●	●
C00016	V _{min} boost	●	●
C00021	Slip compensation	●	
C00082	Motor rotor resistance	●	
C00083	Motor rotor time constant	●	
C00084	Motor stator resistance	●	●
C00085	Motor stator leakage inductance	●	●
C00092	Motor magnetising inductance	●	
C00095	Motor magnetising current	●	

Automatic calculation of the current controller and field controller parameters

From version 12.00.00 onwards: Following successful motor parameter identification, the current controller and field controller parameters listed in the below table are calculated as well.

- If these parameters are not to be calculated, bit 4 of [C02865/1](#) must be set to "1".

Parameter	Info	ASM	PSM
C00073/1	VFC: Vp I _{max} controller	●	●
C00075	Vp current controller	●	●
C00076	Ti current controller	●	●

OPTIONAL: Automatic calculation of the speed controller parameters

From version 12.00.00 onwards: Following successful motor parameter identification, the speed controller parameters listed in the below table can also be calculated automatically.

- If these parameters are to be calculated, bit 6 of [C02865/1](#) must be set to "5".

Parameter	Info	ASM	PSM
C00070/1	SLVC: Vp speed controller	●	
C00071/1	SLVC: Ti speed controller	●	
C00070/3	SLPSM: Vp speed controller	●	●
C00071/3	SLPSM: Ti speed controller	●	●

- Care must be taken that the constant mass inertia of the drive (mass inertia of motor, gearbox, shaft and constant load) is entered as exactly as possible in [C00273](#) to calculate the speed controller parameters as dynamically as possible.
 - Mass inertias that are not constant (e.g. changing loads of reels or different loads of hoists) must be entered in [C00919/1](#).
 - If the mass inertia set in [C00273](#) is too low, the speed controller parameters are calculated less dynamically.
 - If the mass inertia set in [C00273](#) is too high, speed controller operation is unstable.
- If the mass inertia in [C00273](#) is set to "0", the setting of bit 5 in [C02865](#) has no effect on the speed controller parameter calculation. In this case, the speed controller parameters will not be calculated automatically after motor parameter identification.

OPTIONAL: Automatic calculation of other controller parameters

From version 12.00.00 onwards: Following successful motor parameter identification, the controller parameters listed in the below table can also be calculated automatically.

- If these parameters are to be calculated, bit 6 of [C02865/1](#) must be set to "6".

Parameter	Info	ASM	PSM
C00011	Appl.: Reference speed	●	●
C00022	Imax in motor mode	●	●
C00497	Nact filter time constant	●	●
C00966	VFC: Time const. slip comp.	●	
C00982	VFC-ECO: Voltage reduction ramp	●	

Automatic calculation of the field weakening controller parameters for ASM servo control

From version 15.00.00, the field weakening controller parameters are automatically calculated as well after a successful motor parameter identification. Moreover, the special functions of the internal motor control listed in the table are activated.

- If these parameters are not to be calculated/activated, bit 6 has to be set to "1" in [C02864/1](#).

Parameter	Info	ASM	PSM
C00577	SC: Vp field weakening controller	●	
C00578	SC: Tn field weakening controller	●	
Activation of special functions of the internal motor control			
C02864/1	Bit 5 is set to "1" → Field/field weakening controllers are called in a 500-μs cycle.*	●	
	Bit 7 is set to "1" → In case of servo control for asynchronous motors, the rated motor speed (C00087) is assumed for the calculation of the slip from the nameplate (C02879 /bit 1 = "0".* ▶ Slip calculation from motor equivalent circuit diagram data (□ 246)	●	
* If bit 6 is set to "1" in C02864/1 , bit 5 and bit 7 are reset to "0".			

Principal sequence of the motor parameter identification

1. The motor stator resistance ([C00084](#)) is measured.
2. The inverter error characteristic is measured.
3. The motor stator leakage inductance ([C00085](#)) is measured.
4. The V/f base frequency ([C00015](#)) is calculated.
5. The slip compensation ([C00021](#)) is calculated.
6. The V_{\min} boost ([C00016](#)) is detected.
7. Only for asynchronous motors:
The motor magnetising inductance ([C00092](#)) and the motor rotor resistance ([C00082](#)) are measured.
The motor magnetising current ([C00095](#)) is measured.

From version 12.00.00:

8. If [C02865/1](#) - bit 4 = "0" (Lenze setting):
The current controller and field controller parameters are calculated. (See [table](#).)
9. If [C02865/1](#) - bit 5 = "1":
The speed controller parameters are calculated. (See [table](#).)
10. If [C02865/1](#) - bit 6 = "1":
Other controller parameters are calculated. (See [table](#).)

From version 15.00.00:

11. If [C02864/1](#) - bit 6 = "0" (Lenze setting):
The field weakening controller parameters are calculated and certain special functions of the internal motor control are activated. (See [table](#).)

Selection of the identification mode

From version 10.00.00 onwards, two identification modes are available in [C02867/1](#):

- "1: Basic identification" (previous mode)
 - Only for asynchronous motors
 - Duration approx. 30 s
- "2: extended identification"
 - Stands out due to increased accuracy of the determined motor parameters.
 - Also supports synchronous motors and asynchronous motors with a power of more than 11 kW.
 - Duration approx. 80 s



Tip!

In the Lenze setting, a setting of "0: automatic" is selected in [C02867/1](#). This setting ensures that the controller automatically selects the optimum procedure for motor parameter identification.

Preconditions for executing the motor parameter identification

- The motor parameter identification must be carried out when the motor is cold!
- The load machine may remain connected. Holding brakes, if present, may remain in the braking position.
- In case of a synchronous motor:
 - The shaft must be able to rotate freely (must not be locked).
 - An identification is only possible with the extended motor parameter identification.
- For an asynchronous motor from a power of 11 kW:
 - An identification is only possible with the extended motor parameter identification.
- The controller has to be ready for enable (has to be in the "[SwitchedOn](#)" state).
Inhibit the controller if it is enabled, e.g. via the [C00002/16](#) device command or a LOW signal at the X4/RFR terminal.
- The motor has to be at standstill.

Required parameter settings before the motor parameter identification is executed

- For an extended motor parameter identification, a motor control suitable for the motor has to be set in [C00006](#). When the identification starts, this setting determines whether an asynchronous motor or a synchronous motor has to be identified. ▶ [Selecting the control mode](#) (149)
- The motor parameters listed in the table below are excluded from automatic identification and must therefore be adapted to the used motor before motor parameter identification is carried out (see motor nameplate).

Parameter	Info
C00081	Rated motor power
C00087	Rated motor speed
C00088	Rated motor current (according to the connection method Δ/Δ) Note The amplitude of the rated motor current (C00088) is injected to identify the stator resistance. If the rated motor current amounts to less than 60 % of the rated inverter current, at least 60 % of the rated inverter current will be injected to ensure sufficient motor parameter identification accuracy.
C00089	Rated motor frequency (according to the connection method Δ/Δ)
C00090	Rated motor voltage (according to the connection method Δ/Δ)
C00091	Motor $\cos \varphi$

- If the motor nameplate data are entered in the »Engineer« motor catalogue instead of selecting a motor, it is recommendable to use the extended motor parameter identification ([C02867/1](#) = "2: extended identification").
- Especially for third-party motors, it is also recommendable to carry out the slip calculation with the motor equivalent circuit diagram data ([C02879/1](#)). If the slip calculation is derived from the motor nameplate data, this can negatively affect the stability and accuracy of the drive behaviour because the rated speed specified on the motor nameplate often is rather inaccurate.
- The available motor cable must be specified in terms of length and cross-section:

Parameter	Info
C00915	Motor cable length
C00916	Motor cable cross-section

The motor cable resistance resulting from these settings is displayed in [C00917](#).

- For the measurement of the required variables, the motor is energised via the controller terminals U, V and W during the motor parameter identification. The corresponding current controller is preset in the Lenze setting so that an optimal controller behaviour is achieved with an asynchronous motor power-adapted to the controller.

Thanks to optimisation, the current controller can be set via the following parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C00075	Vp current controller	7.00	V/A
C00076	Ti current controller	10.61	ms

- Switching frequency for the motor parameter identification:
 - [Up to and including version 13.xx.xx](#), the motor parameter identification is executed with a switching frequency of 4 kHz.
 - [From version 14.00.00](#), the motor parameter identification can also be executed with a switching frequency of 8 kHz instead of 4 kHz. For this purpose, the option "Motor ident.: Switching frequency 8 kHz" (Bit 4 = "1") has to be set in [C02864/1](#).
Example of how to use this option: Between the output of the inverter and the motor, a sinusoidal filter is connected which may only be operated with a minimum switching frequency of 8 kHz. (See also the section "[Preventing a decrease of the switching frequency](#)".) ([□ 257](#))

Generally, a switching frequency of 4 kHz is recommended for the motor parameter identification as it serves to obtain the most accurate results.

Premature abort of the motor parameter identification



Stop!

If motor parameter identification is aborted, unstable drive behaviour may be the result!

The motor parameter identification can be aborted in the following cases:

- If a special motor (e.g. mid-frequency motor) or a servo motor is used.
- If there is a large deviation between inverter and motor power.

In case of a simple motor parameter identification, we recommend the following:

- to reduce the P component Vp of the current controller ([C00075](#)) e.g. by halving.
- to increase the time constant Ti of the current controller ([C00076](#)) e.g. by doubling.

In case of the extended motor parameter identification, the current controller parameters are determined automatically. If the identification is aborted all the same, the current controller parameters set in [C00075](#) and [C00076](#) can be used by parameterising [C02866](#) to "1".

Another cause for the abort of the motor parameter identification could be the implausibility of the entered nameplate data, e.g. the entry P = 0 kW for the motor power.

Execute automatic motor parameter identification**Danger!**

During motor parameter identification, the motor is energised via the outputs U, V and W of the controller!

- Observe the corresponding safety instructions!
- With an idling motor, a small angular offset may occur at the motor shaft.
- During the motor parameter identification, rotations occur in case of a synchronous motor.

**How to carry out automatic motor parameter identification:**

1. Activate motor parameter identification via the [C00002/23](#) = "1: On / start" device command.
2. Enable controller.
 - The controller changes to the "[Ident](#)" device status.
 - Motor parameter identification starts.
 - The progress of the identification run can be seen in [C00002/23](#).
 - The identification is completed if the "0: Off / ready" message is displayed in [C00002/23](#).
 - After successful identification, it changes back to the "[SwitchedOn](#)" device status.
3. Inhibit controller again.

5.1.3 Application notes for asynchronous motors with high slip speed



Note!

If a rated motor speed is set for an asynchronous motor (ASM) in [C00087](#) which corresponds to a very high slip speed, the number of motor pole pairs is identified incorrectly.

Moreover, a synchronous motor is (PSM) is detected instead of an asynchronous motor (ASM). In this case, the "[Id7](#)" error message can occur since motor and motor control type do not match.

Examples, possible impacts and remedies are described in the following sections.

Examples:

Number of pole pairs	Mechanical synchronous speed	Rated motor frequency (C00089)	Incorrect number of pole pairs if the rated motor speed (C00087) is lower:
1	3000 rpm	50 Hz	1986 rpm
2	1500 rpm	50 Hz	1195 rpm
3	1000 rpm	50 Hz	854 rpm
4	750 rpm	50 Hz	665 rpm

Possible impacts depending on the motor control type:

Motor control type	Possible impacts on the drive
Servo control (SC) - PSM	No impact if the motor data have been entered correctly.
Servo control (SC) - ASM	The motor can accelerate up to maximum speed of the motor.
V/f control (VFCplus + encoder)	
Sensorless vector control (SLVC)	The output speed is considerably too high.
V/f characteristic control (VFCplus)	Example: $p=2$, $f_n=50$ Hz, $n_n=1195 \text{ min}^{-1}$ → Speed is 50 % too high

Remedies:

- For version 12.xx.xx and version 13.xx.xx the following applies:
Limit the rated motor speed: $\text{C00087} = \text{C00089} * 60 / (\text{number of pole pairs} + 0.5)$
- From version 14.00.00:
Set the motor type ("ASM" or "PSM") manually in [C01001/1](#). The rated motor speed does not need to be limited since the number of pole pairs can be detected safely when the motor type has been set manually.

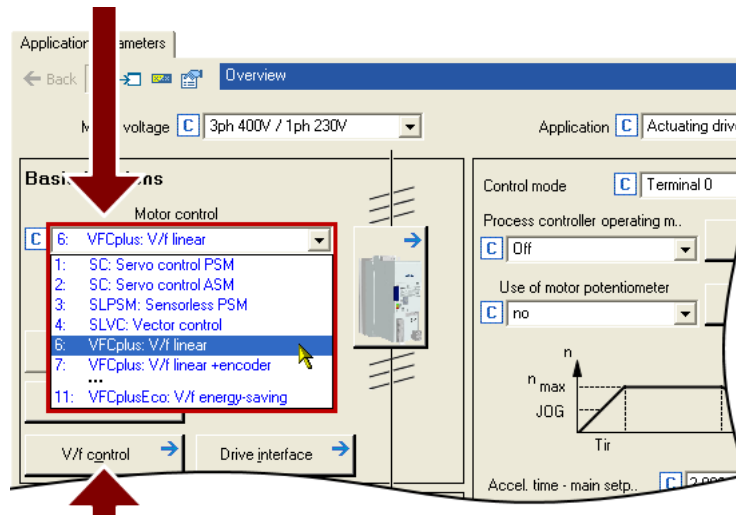
5 Motor control (MCTRL)

5.2 Selecting the control mode

5.2 Selecting the control mode

The 8400 TopLine controller supports various modes for motor control (open loop or closed loop).

- V/f characteristic control (VFCplus) with linear characteristic for asynchronous motors is preset.
- The control mode can be selected in the »Engineer« on the **Application parameter** tab via the **Motor control (C00006)** list field:



- A click on the **Motor control...** button leads you to the parameterisation dialog of the selected motor control. (The button is labelled according to the selected motor control.)



Tip!

In order to make the selection of the motor control easier, we provide a selection help with recommendations and alternatives for standard applications in the subchapter entitled "[Selection help](#)". (153)

The following section briefly describe the control modes. A reference to more details can be found at the end of each section.

V/f characteristic control (VFCplus)

The V/f characteristic control (VFCplus) is a motor control mode for standard frequency inverter applications based on a simple and robust control process which is suitable for the operation of asynchronous motors with linear or square-law load torque characteristic (e.g. fans). Furthermore, this motor control mode is also suitable for group drives and special motors. Due to the low parameterisation effort, commissioning of such applications is fast and easy.

The V_{\min} boost ([C00016](#)) and slip compensation ([C00021](#)) required for optimising the drive behaviour are dimensioned for asynchronous motors with power adaptations to the inverter in the Lenze setting.

▶ [V/f characteristic control \(VFCplus\)](#) (□ 157)

Energy-saving V/f characteristic control (VFCplusEco)

In contrast to the V/f characteristic control mode (VFCplus), this motor control mode uses a $\cos\phi$ control in partial load operational range to automatically reduce the power loss in the asynchronous motor (energy optimisation).

The motor data required for the $\cos\phi$ control and the V_{\min} boost ([C00016](#)) and slip compensation ([C00021](#)) required for optimising the drive behaviour are dimensioned for asynchronous motors with power adaptations to the inverter in the Lenze setting.

The required motor data (motor rotor resistance, motor stator resistance, motor stator leakage inductance and mutual motor inductance) only affect the extent of energy optimisation but not the stability.

In case of applications with dynamically very high sudden load variations from the unloaded operation, this motor control mode should not be used since a motor stalling cannot be excluded.

Energy optimisation for dynamic applications is not possible with this motor control mode.

▶ [V/f characteristic control - energy-saving \(VFCplusEco\)](#) (□ 176)

V/f control (VFCplus + encoder)

The V/f control can be selected for operating asynchronous motors with speed feedback. With this motor control, a slip regulator can be additionally parameterised which adjusts the actual speed value dynamically to the speed setpoint.

▶ [V/f control \(VFCplus + encoder\)](#) (□ 186)

Sensorless vector control (SLVC)

Sensorless (field-oriented) vector control for asynchronous motors is based on a decoupled, separate control for the torque-producing and the field-producing current component. In addition, the actual speed is reconstructed by means of a motor model so that a speed sensor is not required.

In comparison to the V/f characteristic control without feedback, the following can be achieved by means of sensorless vector control SLVC:

- A higher maximum torque throughout the entire speed range
- A higher speed accuracy
- A higher concentricity factor
- A higher level of efficiency
- The implementation of torque-actuated operation with speed limitation
- The limitation of the maximum torque in motor and generator mode for speed-actuated operation



Tip!

If a high torque without feedback is to be provided at small speeds, we recommend the "Sensorless vector control" motor control mode.

► [Sensorless vector control \(SLVC\)](#) (📖 193)

Sensorless control for synchronous motors (SLPSM)

This sensorless control enables an encoderless control of synchronous motors. The process is based on field-oriented control within a higher speed range (e.g. > 10 % of the rated motor speed). The actual speed value and rotor position are reconstructed via a motor model.

Standard applications for this control type are pumps and fans, horizontal materials handling and simple positioning technology.

► [Sensorless control for synchronous motors \(SLPSM\)](#) (📖 209)

Servo control (SC)

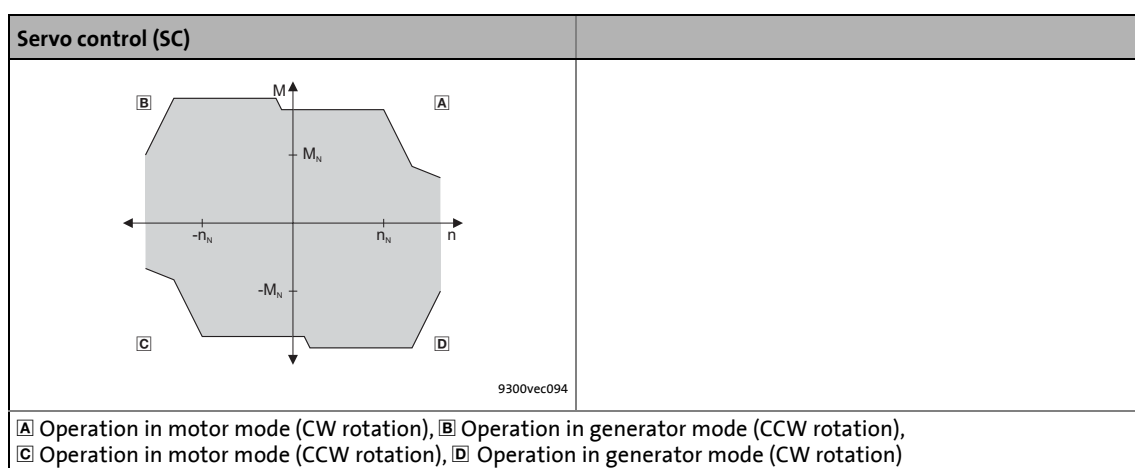
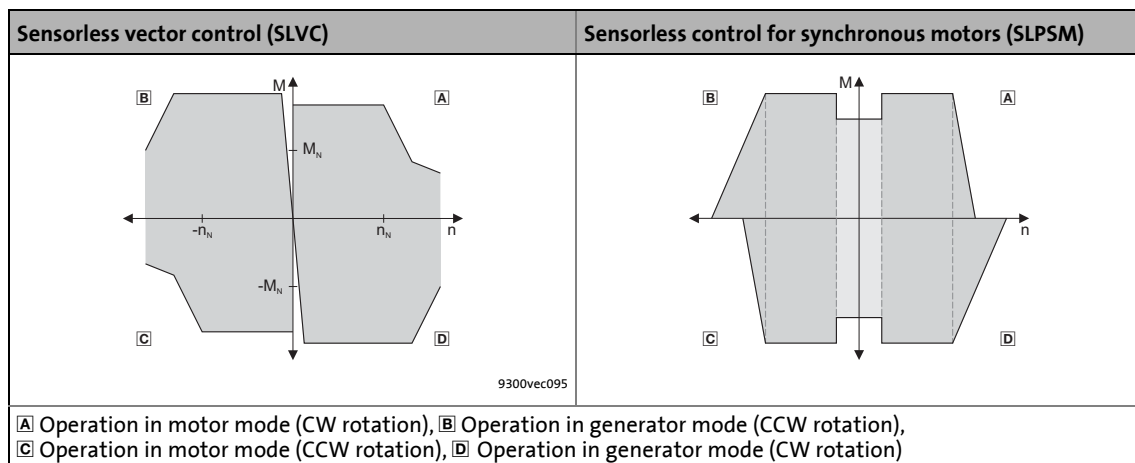
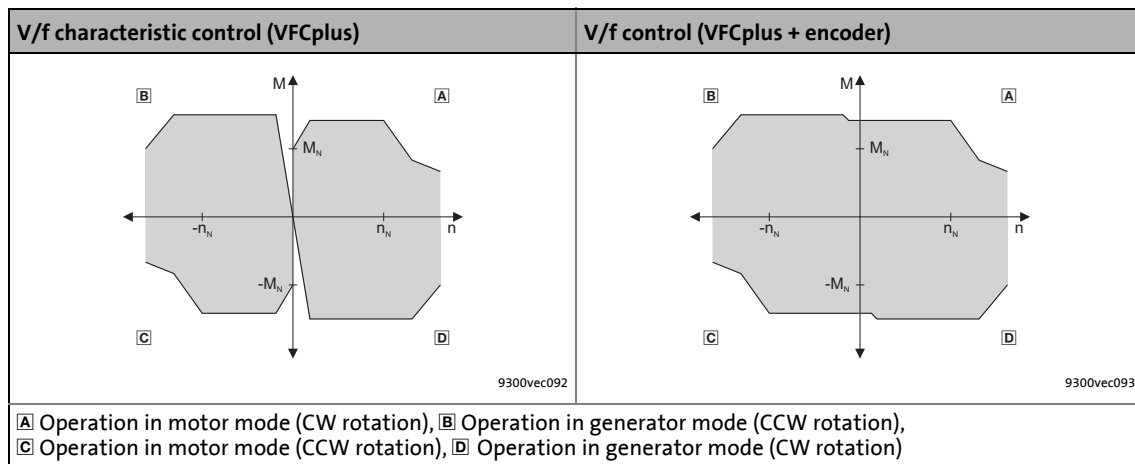
Field-oriented servo control (SC) is based on a decoupled, separate control of the torque-producing and the field-producing current component. The motor control is based on a field-oriented, cascaded controller structure with feedback function and enables dynamic and stable operation in all of the four quadrants.

The servo control can be used for synchronous motor (PSM) and asynchronous motors (ASM) and basically offers the same advantages as the sensorless vector control (SLVC).

► [Servo control \(SC\)](#) (📖 226)

Speed feedback

As shown in the following graphics, the drive systems with feedback have, independently of the motor control, more advantages than systems without feedback.



5.2.1 Selection help

To ease the selection of the motor control mode, the two following tables contain recommendations and alternatives to standard applications.

Application	recommended	Alternatively
Single drives		
With constant load	VFCplus: V/f linear	SLVC or SLPSM
With extremely alternating loads	VFCplus: V/f linear	SLVC
With high starting duty	SLVC	VFCplus: V/f linear
Torque limitation	SLVC	SLPSM
With torque limitation (power control)	VFCplus: V/f linear	SLPSM
Three-phase reluctance motor	VFCplus: V/f linear	-
Three-phase sliding rotor motor	VFCplus: V/f linear	-
Three-phase AC motors with permanently assigned frequency/voltage characteristic	VFCplus: V/f linear	-
Pump and fan drives with quadratic load characteristic	VFCplusEco	SLVC or SLPSM
Simple hoists	VFCplus: V/f linear	-
Group drives (several motors connected to controller)		
Identical motors and loads	VFCplus: V/f linear	-
Different motors and/or alternating loads	VFCplus: V/f linear	-

[5-1] Standard applications without speed feedback

Application	recommended	Alternatively
Single drives		
With constant load	SC	VFCplus / SLVC
With extremely alternating loads	SC	VFCplus / SLVC
With high starting duty	SC	VFCplus / SLVC
With speed control (speed feedback)	SC	VFCplus
With high dynamic performance e.g. for positioning and infeed drives	SC	-
Torque limitation	SC	SLVC
With torque limitation (power control)	-	-
Winder with dancer position control	SC	VFCplus
Unwinder with dancer position control	SC	VFCplus
Three-phase reluctance motor	-	-
Three-phase sliding rotor motor	-	-
Three-phase AC motors with permanently assigned frequency/voltage characteristic	-	-
Pump and fan drives with quadratic load characteristic	-	-
Simple hoists	VFCplus: V/f linear	-
Group drives (several motors connected to controller)		
Identical motors and loads	VFCplus	-
Different motors and/or alternating loads	-	VFCplus

[5-2] Standard applications with speed feedback

5.3 Defining current and speed limits

Limitation of the speed setpoint

Parameterising the reference speed in [C00011](#) means that the drive must rotate at the set speed if a speed setpoint of 100% is specified.

All speed setpoint selections are provided in % and always refer to the reference speed set in [C00011](#).



Tip!

For reasons of achievable resolution and the accuracy involved, the reference speed should be geared to the speed range required for the respective application.

Lenze recommendation: Reference speed ([C00011](#)) = 1500 ... 3000 rpm

Irrespective of the selected motor control, there are more limitation options:

Parameter	Info	Lenze setting	
		Value	Unit
C00909/1	Max. positive speed	120	%
C00909/2	Max. negative speed	120	%
C00910/1	Max. positive output frequency	1000	Hz
C00910/2	Max. negative output frequency	1000	Hz



Note!

In the torque-controlled operation (*bTorquemodeOn* = TRUE), the limitation of the speed setpoint set in [C00909/x](#) has no impact!

For the torque-controlled operation, a permissible speed range can be defined via the speed limitation (inputs *nSpeedHighLimit_a* and *nSpeedLowLimit_a* at the SB [LS MotorInterface](#)).

For a correct function of the speed limitation in both direction, the following applies:

The speed limitation operates with a internal hysteresis of 50 min⁻¹. The upper or lower speed limit resulting from the settings has to be higher than this hysteresis!

Current limitation in motor and generator mode

In the various motor control modes, the controller is provided with functions which determine the dynamic behaviour under load and counteract exceedance of the maximum current in motor or generator mode.

Parameter	Info	Lenze setting	
		Value	Unit
C00022	I _{max} in motor mode	47.00	A
C00023	I _{max} in generator mode • 100 % ≡ I _{max} in motor mode (C00022)	100	%

The current limits must be selected depending on

- the permissible maximum current of the motor → recommendation: $I(\text{Mot})_N < 1.5 \dots 2.0$
- the permissible maximum current of the inverter
- the torque in motor/generator mode required for the application



Note!

Highly dynamic applications

(that have e.g. too short acceleration/deceleration times or excessively changing loads)

The overcurrent disconnection may respond (fault message oC1 or oC11) if the setting of the maximum current in motor mode in [C00022](#) approximately corresponds to the maximum permissible value of the respective inverter.

Remedies:

- Increase of the acceleration and deceleration ramp times
- Reduction of the maximum current in motor mode ([C00022](#))
- Reduction of the maximum current in generator mode ([C00023](#))
- Adaptation of the indirect peak current limitation (procedure depends on the selected motor control mode, see below)
- Reduction of the reset time of the current limiting controller ([C00074/1](#))

Influencing the torque in motor/generator mode

The torque in motor and generator mode can be limited via the *nTorqueMotLim* and *nTorqueGenLim* process signal inputs.

- If V/f characteristic control (VFCplus) is selected, limitation is indirectly performed via a so-called I_{max} controller.
- If sensorless vector control (SLVC), sensorless control for synchronous motors (SLPSM) or servo control (SC) is selected, limitation has a direct effect on the torque-producing current component.

If keypad control is selected, the *nTorqueMotLim* and *nTorqueGenLim* process signals can be parameterised via [C00728/1...2](#).

**How to adapt the peak current limitation:**

V/f characteristic control (VFCplus):

- Reduce the slip compensation with [C00021](#).

V/f control (VFCplus + encoder):

- Reduce the slip limitation to twice the rated motor slip with [C00971](#).
- Reduce the V_{\min} boost in [C00016](#).

Sensorless vector control (SLVC):

- Reduce the slip compensation with [C00021](#).
- Reduce the limitation of the torque in motor mode via $nTorqueMotLimit_a$ ([C00728/1](#)) and the limitation of the torque in generator mode via $nTorqueGenLimit_a$ ([C00728/2](#)).

Servo control (SC):

- Reduce the jerk limitation with [C00274](#).
- Reduce the limitation of the torque in motor mode via $nTorqueMotLimit_a$ ([C00728/1](#)) and the limitation of the torque in generator mode via $nTorqueGenLimit_a$ ([C00728/2](#)).

5.4 V/f characteristic control (VFCplus)

In case of the V/f characteristic control (VFCplus), the motor voltage of the inverter is determined by means of a linear or quadratic characteristic depending on the field frequency or motor speed to be generated. The voltage follows a preselected characteristic.



Stop!

- The V/f characteristic control is only suitable for asynchronous motors.
- The following must be observed when operating drives with quadratic V/f characteristic:
 - Please always check whether the corresponding drive is suitable for operation with a quadratic V/f characteristic!
 - If you pump or fan drive is not suitable for operation with a square-law V/f characteristic, we recommend using the energy-saving V/f characteristic control (VFCplusEco). Alternatively, you can use the V/f characteristic control with linear V/f characteristic or the sensorless vector control (SLVC) or servo control (SC).
- For adjustment, observe the thermal performance of the connected asynchronous motor at low output frequencies.
 - Usually, standard asynchronous motors with insulation class B can be operated for a short time with their rated current in the frequency range 0 Hz ... 25 Hz.
 - Contact the motor manufacturer to get the exact setting values for the max. permissible motor current of self-ventilated motors in the lower speed range.
 - If you select square-law V/f characteristics, we recommend setting a lower V_{\min} or using the energy-saving V/f characteristic control (VFCplusEco).
- The nameplate data of the motor (at least rated speed and rated frequency) must be entered if, instead of a standard motor, an asynchronous motor is used with the following values:
 - rated frequency \neq 50 Hz (star) or
 - rated frequency \neq 87 Hz (delta) or
 - number of pole pairs \neq 2



Note!

When the auto DCB threshold ([C00019](#)) is set > 0 rpm, there is no torque at the motor shaft in the lower speed range!

► [Automatic DC-injection braking \(Auto-DCB\)](#) (□ 268)

5.4.1 Parameterisation dialog/signal flow

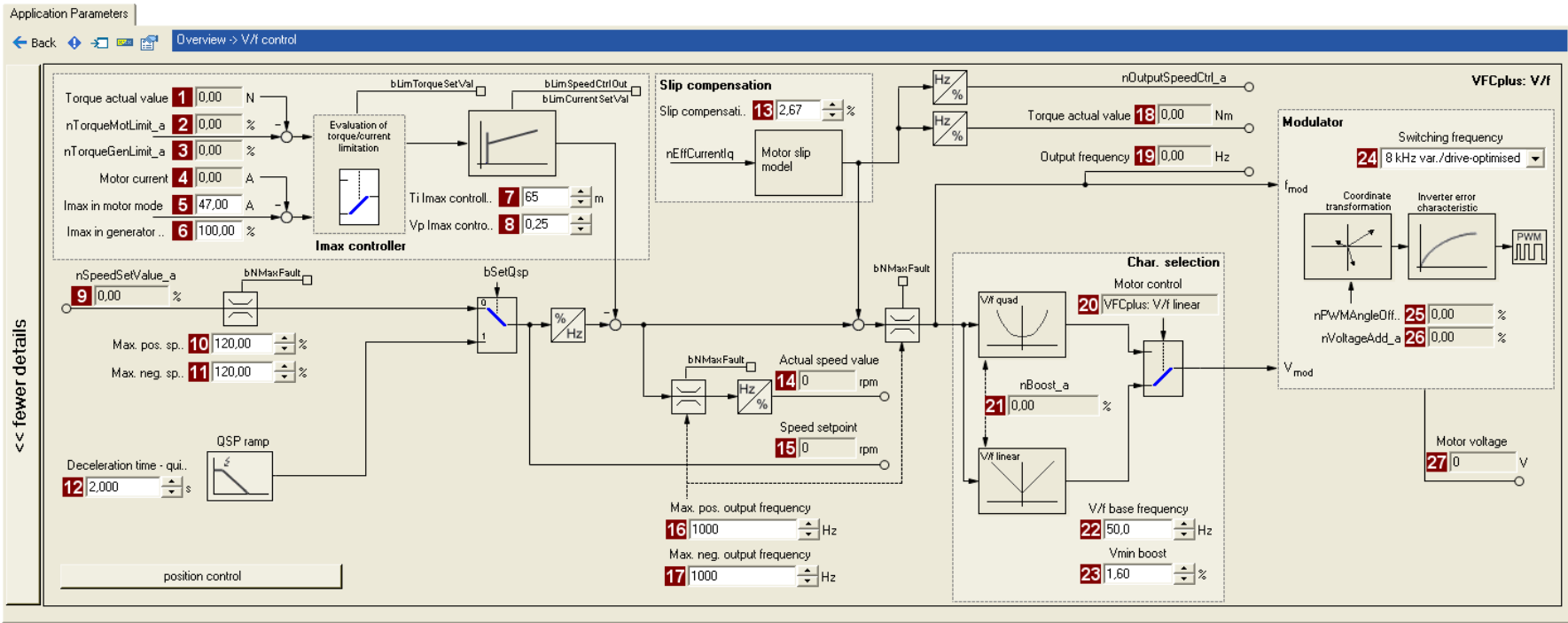


Proceed as follows to open the dialog for parameterising the motor control:

1. »Engineer« Go to the *Project view* and select the 8400 TopLine controller.
2. Select the **Application parameters** tab from the *Workspace*.
3. Select the motor control from the *Overview* dialog level in the **Motor control** list field:
 - "6: VFCplus: V/f linear" for linear characteristic or
 - "8: VFCplus: V/f quadr" for square-law characteristic

More available V/f characteristic control modes:

- "10: VFCplus: V/f definable".
With this motor control, the V/f characteristic can be freely defined. ▶ [Defining a user-defined V/f characteristic](#) (□ 172)
 - "11: VFCplusEco: V/f energy-saving".
With this motor control, the motor is always operated in an optimal efficiency range via a $\cos\phi$ control and the resulting voltage reduction (reduced copper losses in the asynchronous motor). ▶ [V/f characteristic control - energy-saving \(VFCplusEco\)](#) (□ 176)
4. Click the **Motor control V/f** button to change to the *Overview → Motor control V/f* dialog box.
 - This dialog level only shows a simplified signal flow with the most important parameters.
 - When you click the >>**More details** button in the left-most position, a signal flow with more details/parameters is displayed.



Parameter	Info	Parameter	Info	Parameter	Info
1	C00056/2 Actual torque value	13	C00021 Slip compensation	18	C00056/2 Actual torque value
2	C00830/29 Limitation of torque in motor mode	14	C00051 Actual speed value	19	C00058 Output frequency
3	C00830/28 Limitation of torque in generator mode	15	C00050 Speed setpoint	20	C00006 Motor control
4	C00054 Motor current	16	C00910/1 Max. pos. output frequency	21	C00830/26 MCTRL: nBoost_a
5	C00022 I _{max} in motor mode	17	C00910/2 Max. neg. output frequency	22	C00015 V/f base frequency
6	C00023 I _{max} in generator mode			23	C00016 V _{min} boost
7	C00074 Ti I _{max} controller			24	C00018 Switching frequency
8	C00073 Vp I _{max} controller			25	C00830/32 MCTRL: nPWMAngleOffset_a
9	C00830/22 Speed setpoint			26	C00830/31 MCTRL: nVoltageAdd_a
10	C00909/1 Max. pos. speed			27	C00052 Motor voltage
11	C00909/2 Max. neg. speed				
12	C00105 Decel. time - quick stop				

5.4.2 Basic settings

The "Initial commissioning steps" listed in the table below are sufficient for a simple characteristic control.

- Detailed information on the individual steps can be found in the following subchapters.

Initial commissioning steps	
1.	Defining the V/f characteristic shape. (📖 161)
2.	Defining current limits (I_{max} controller). (📖 162)



Tip!

Information on the optimisation of the control mode and the adaptation to the real application is provided in chapter "[Optimising the control mode](#)". (📖 163)

Parameterisable additional functions are described correspondingly in the chapter "[Parameterisable additional functions](#)". (📖 256)

5.4.2.1 Defining the V/f characteristic shape

In principle, four different characteristic shapes can be stipulated:

1. **Linear V/f characteristic:**

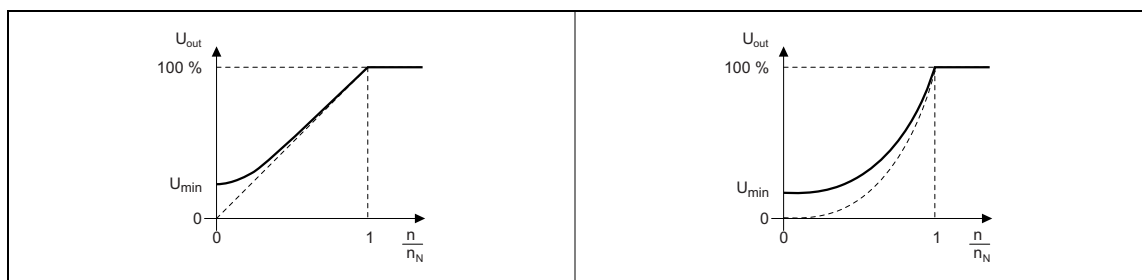
For drives for a constant, speed-independent load torque.

2. **Quadratic V/f characteristic:**

For drives with a load torque curve which is quadratic or in relation to speed. Quadratic V/f characteristics are preferred in the case of centrifugal pumps and fan drives.

3. **Freely definable V/f characteristic:**

For drives that require adaptation of the magnetising current by means of the output speed. The freely definable V/f characteristic can be used e.g. for operation in conjunction with special machines such as reluctance motors in order to suppress oscillations at the machine or to optimise energy consumption.



[5-3] Principle of a linear V/f characteristic (on the left) and a quadratic V/f characteristic (on the right)

4. **Linear V/f characteristic with voltage reduction:**

For drives which often work in partial load operation, the energy-saving V/f characteristic control (VFCplusEco) offers the opportunity to reduce the voltage at low load in order to save energy. At higher loads, the voltage reduction is cancelled and a linear characteristic is caused.

The V/f characteristic shape is defined by selecting the corresponding motor control mode in [C00006](#):

V/f characteristic shape	Motor control to be selected (C00006)
Linear V/f characteristic	6: VFCplus: V/f linear
Square-law V/f characteristic	8: VFCplus: V/f quadr
User-definable V/f characteristic	10: VFCplus: V/f definable
Linear V/f characteristic with voltage reduction	11: VFCplusEco: V/f energy-saving



Tip!

- You can find detailed information on freely definable V/f characteristics in the subchapter entitled "[Defining a user-defined V/f characteristic](#)". (172)
- You can find detailed information on the linear V/f characteristic with voltage reduction in the chapter entitled "[V/f characteristic control - energy-saving \(VFCplusEco\)](#)". (176)

5.4.2.2 Defining current limits (I_{max} controller)

The V/f characteristic control (VFCplus) and the V/f control (VFCplus + encoder) operating modes are provided with a current limitation control which is decisive for the dynamic behaviour under load and counteracts exceedance of the maximum current in motor or generator mode. This current limitation control is called I_{max} control.

- The efficiency (motor current) measured by the I_{max} control is compared with the current limit value for motor load set in [C00022](#) and the current limit value for generator load set in [C00023](#).
- If the current limit values are exceeded, the controller changes its dynamic behaviour.

Motor overload during acceleration

The controller prolongs the acceleration ramp to keep the current on or below the current limit.

Generator overload during deceleration

The controller prolongs the deceleration ramp to keep the current on or below the current limit.

Increasing load with constant speed

- If the motor current limit value is reached:
 - The controller reduces the effective speed setpoint until a stable working point is set or an effective speed setpoint of 0 rpm is reached.
 - If the load is reduced, the controller increases the effective speed setpoint until the setpoint speed is reached or the load reaches the current limit value again.
- When the generator current limit value is reached:
 - The controller increases the effective speed setpoint until a stable working point is set or the maximally permissible speed ([C00909](#)) or output frequency is reached ([C000910](#)).
 - If the load is reduced, the controller reduces the effective speed setpoint until the setpoint speed is reached or the load reaches the current limit value again.
- If a sudden load is built up at the motor shaft (e.g. drive is blocked), the overcurrent disconnection may respond (fault message oC1 or oC11).

5.4.3 Optimising the control mode

The V/f characteristic control (VFCplus) is generally ready for operation. It can be adapted subsequently by adapting the characteristic and/or the drive behaviour.



Note!

Following successful motor parameter identification, the V/f base frequency ([C00015](#)) and the V_{\min} boost ([C00016](#)) as well as the slip constant for slip compensation ([C00021](#)) are calculated automatically.

From version 12.00.00:

- Following successful motor parameter identification, the gain of the I_{\max} controller ([C00073/1](#)) is calculated automatically.
 - If these parameters are not to be calculated, bit 4 of [C02865/1](#) must be set to "1".
- Following successful motor parameter identification, other controller parameters ([C00011](#), [C00022](#), [C00966](#)) can be calculated automatically.
 - If these parameters are to be calculated, bit 6 of [C02865/1](#) must be set to "6".

Adapting characteristic

For the linear and quadratic characteristic, it is also possible to match its curve to different load profiles or motors by adapting the V/f base frequency ([C00015](#)) and the V_{\min} boost ([C00016](#)).

- ▶ [Adapting the V/f base frequency](#) (📖 164)
- ▶ [Adapting the \$V_{\min}\$ boost](#) (📖 166)

Freely defining the characteristic

The V/f characteristic can also be defined freely if the linear and quadratic characteristics are not suitable.

- ▶ [Defining a user-defined V/f characteristic](#) (📖 172)

Adapting drive behaviour

- Limitation of the maximum current by a current limitation controller (e.g. to prevent the motor from stalling or to limit to the maximally permissible motor current). ▶ [Optimising the \$I_{\max}\$ controller](#) (📖 168)
- Adaptation of the field frequency by a load-dependent slip compensation (improved speed accuracy for systems without feedback)
- Adaptation of the controller parameters of the slip regulator if V/f control (VFCplus + encoder) is selected. ▶ [Parameterising the slip regulator](#) (📖 190)

5.4.3.1 Adapting the V/f base frequency

The V/f base frequency ([C00015](#)) determines the slope of the V/f characteristic and has considerable influence on the current, torque, and power performance of the motor.

- The setting in [C00015](#) applies to all permitted mains voltages.
- Mains fluctuations or fluctuations of the DC-bus voltage (operation in generator mode) do not need to be considered when the V/f base frequency is set. They are automatically compensated for by the internal mains voltage compensation of the device.
- Depending on the setting in [C00015](#), it may be required to adapt the reference speed ([C00011](#)) to traverse the entire speed range of the motor.
- The V/f base frequency is automatically calculated from the stored motor nameplate data by the motor parameter identification:

$$C00015 \text{ [Hz]} = \frac{U_{FI} \text{ [V]}}{U_{Ratedmot} \text{ [V]}} \cdot f_{Rated} \text{ Hz}$$

U_{FI} : Mains voltage 400 V or 230 V

$U_{Ratedmot}$: Rated motor voltage depending on the connection method

f_{Rated} : Rated motor frequency

[5-4] Calculation of the V/f base frequency

Typical values of the V/f base frequency

Drive controller with 400 V mains connection			
Motor voltage [V]	Motor frequency [Hz]	Motor connection	V/f base frequency (C00015)
230 / 400	50	Y	50 Hz
220 / 380	50	Y	52.6 Hz
280 / 480	60	Y	50 Hz
400 / 690	50	Δ	50 Hz
400	50	Δ	50 Hz
230 / 400	50	Δ	87 Hz
280 / 480	60	Δ	87 Hz
400	87	Δ	87 Hz
220 / 380	50	Δ	90.9 Hz

Drive controller with 230 V mains connection			
Motor voltage [V]	Motor frequency [Hz]	Motor connection	V/f base frequency (C00015)
230	50	Δ	50 Hz
220 / 380	50	Δ	52.3 Hz

**Note!****87-Hz operation**

4-pole asynchronous motors which are designed for a rated frequency of $f = 50$ Hz in star connection can be operated in delta connection when being constantly excited up to $f = 87$ Hz.

- Advantages:
 - Higher speed-setting range
 - 73% higher power output in case of standard motors
- Motor current and motor power increase by the factor $\sqrt{3}$.
- The field weakening range starts above 87 Hz.
- Generally, this process can also be used with motors which have different numbers of pole pairs. In case of 2-pole asynchronous motors, the mechanical limit speed must be maintained.

5.4.3.2 Adapting the Vmin boost

The V_{\min} boost ([C00016](#)) of the motor voltage serves to select a load independent magnetising current which is required for asynchronous motors. The torque behaviour of the motor can be optimised by adapting the setting in [C00016](#).

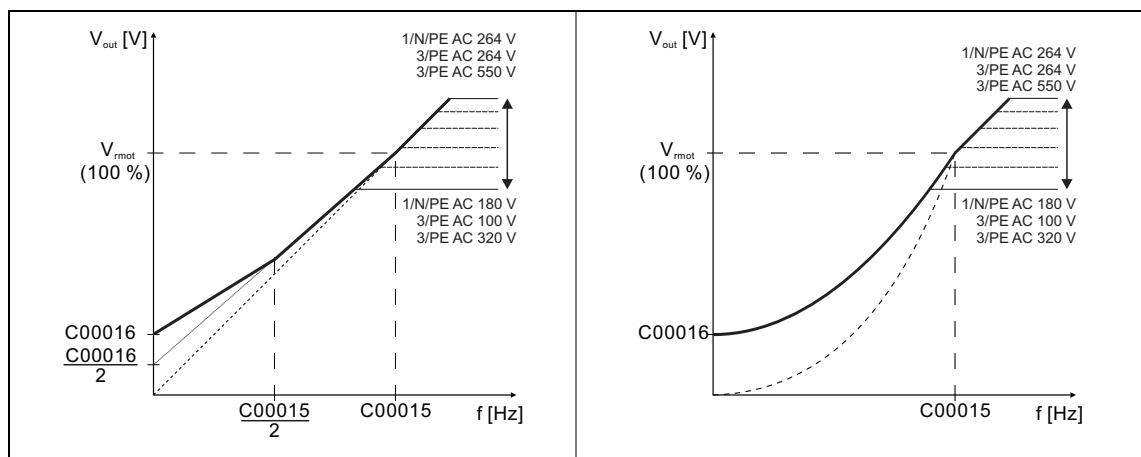
The $nBoost_a$ process signal at the SB [LS MotorInterface](#) serves to carry out a V_{\min} boost as well:

Identifier	Information/possible settings
DIS code data type	
nBoost_a C00830/26 INT	<p>Process signal for the V_{\min} boost</p> <ul style="list-style-type: none"> This signal is added to C00016 and has thus an increasing or decreasing effect. This signal serves to implement a load-dependent Vmin boost to improve the torque behaviour in different load states, as for instance in case of operation in generator or motor mode. Scaling: $16384 \equiv 100\%$ rated device voltage V_{FU} (400 V or 230 V)
	<p>STOP Stop!</p> <p>Values selected too high may cause the motor to heat up due to the resulting current!</p>

**Note!**

The V_{\min} boost has an effect on output frequencies below the V/f base frequency ([C00015](#)).

The general linear and quadratic V/f characteristics are shown in the illustrations below. The illustrations show the impacts of the parameters used to adapt the characteristic shape.



[5-5] Representation of the linear V/f characteristic (on the left) and quadratic V/f characteristic (on the right)



How to set the V_{\min} boost:

1. Operate motor in idle state at approx. 6 % of the rated motor speed.
2. Increase V_{\min} boost ([C00016](#)) until the following motor current is reached:

Motor in short-time operation up to $0.5 n_{\text{rated}}$

- for self-ventilated motors: $I_{\text{motor}} \approx I_{\text{rated motor}}$
- for forced ventilated motors: $I_{\text{motor}} \approx I_{\text{rated motor}}$

Motor in continuous operation up to $0.5 n_{\text{rated}}$

- for self-ventilated motors: $I_{\text{motor}} \approx 0.8 I_{\text{rated motor}}$
- for forced ventilated motors: $I_{\text{motor}} \approx I_{\text{rated motor}}$



Note!

V_{\min} boost is automatically calculated by the motor parameter identification using the data specified on the motor nameplate so that a no-load current of approx. $0.8 I_{\text{rated motor}}$ results at the slip frequency of the machine.

V/f control (VFCplus + encoder)

In case of operation in motor mode, we recommend a considerably lower V_{\min} boost with V/f control (VFCplus + encoder) In this cas, the V_{\min} boost should be dimensioned in such a way that in case of slip frequency in idle state, approx. 50 % of the rated motor current flows.

In case of operation in generator mode, a light increase of the speed may be caused in certain load ranges with V/f control (VFCplus + encoder) in the lower speed range. This speed increase can be reduced by a higher V_{\min} boost.

The $nBoost_a$ process signal is added to [C00016](#) and can be used to implement different V_{\min} boosts for operation in motor and generator mode. As an alternative, the $nVoltageAdd_a$ process signal can be used as well.

5.4.3.3 Optimising the I_{max} controller

Using the Lenze setting of the current limitation controller, the drive is stable:

Parameter	Info	Lenze setting	
		Value	Unit
C00073/1	VFC: Vp I _{max} controller	0.25	
C00074/1	VFC: Ti I _{max} controller	65	ms

Most applications do not require optimisation.

The setting of the current limitation controller must be adapted if

- power control including great moments of inertia is performed.
 - Recommendation: Increase of the reset time Ti ([C00074/1](#)) of the I_{max} controller.
- vibrations occur in the V/f control (VFCplus + encoder) mode during the intervention of the current limitation controller.
 - Recommendation: Increase of the reset time Ti ([C00074/1](#)) of the I_{max} controller.
- overcurrent errors (e.g. OC3) occur due to load impulses or too high acceleration ramps.
 - Recommendation: Reduction of the gain Vp ([C00073/1](#)) and reset time Ti ([C00074/1](#)) of the I_{max} controller.

5.4.3.4 Optimising the stalling behaviour

Motor stalling due to a torque overload in the field weakening range is prevented in all characteristic-based motor control types (VFCplus) by means of an inverter-internal stalling current monitoring. In the field weakening range, hence at frequencies above the base frequency, it reduces the maximum current to prevent the motor from stalling. The reduction depends on the current field frequency, the base frequency, the DC-bus voltage and the maximum current ([C00022](#)). Generally it applies that a higher field frequency causes a stronger limitation of the maximum current.

The behaviour in the field weakening range can be adapted via the override point of field weakening ([C00080](#)). This parameter serves to shift the frequency-dependent maximum current characteristic:

- [C00080](#) > 0 Hz:
 - The maximum current characteristic is shifted by the entered frequency to higher field frequencies.
 - The maximally permissible current and the maximum torque increase in the field weakening range.
 - The risk of motor stalling increases.
- [C00080](#) < 0 Hz:
 - The maximum current characteristic is shifted by the entered frequency to lower field frequencies.
 - The maximally permissible current and the maximum torque are reduced in the field weakening range.
 - The risk of motor stalling is reduced.



Note!

We recommend to keep the Lenze setting (0 Hz).

5.4.3.5 Torque limitation

The previous chapter, "[Optimising the I_{max} controller](#)", describes how the drive can be protected from overload. During commissioning, these settings are carried out once and remain unchanged afterwards. However, it is often necessary to limit the torque to a lower value for plant or process reasons.

- To avoid overload in the drive train, the torque in motor mode can be limited via the *nTorqueMotLimit_a* process input signal, and the torque in generator mode can be limited via the *nTorqueGenLimit_a* process input signal:

Identifier DIS code data type	Information/possible settings
nTorqueMotLimit_a C00830/29 INT	Torque limitation in motor mode <ul style="list-style-type: none"> • Scaling: 16384 \equiv 100 % M_{max} (C00057) • Setting range: 0 ... +199.99 % • If keypad control is performed: Parameterisable via C00728/1.
nTorqueGenLimit_a C00830/28 INT	Torque limitation in generator mode <ul style="list-style-type: none"> • Scaling: 16384 \equiv 100 % M_{max} (C00057) • Setting range: -199.99 ... 0 % • If keypad control is performed: Parameterisable via C00728/2.

**Note!**

- The actual torque ([C00056/2](#)) is directly calculated from the current slip speed of the machine. This requires correct entry of the motor data. ▶ [Motor selection/Motor data](#) ([135](#))
- To avoid instabilities during operation with active slip compensation, the torque limit values are internally processed as absolute values.
- If slip compensation is deactivated ([C00021](#) = 0), indirect torque limitation (differential signal between apparent motor current and *nTorqueMotLimit_a* or *nTorqueGenLimit_a*) occurs. Above the no-load current of the motor, the accuracy of the indirect torque limitation is limited.

5 Motor control (MCTRL)

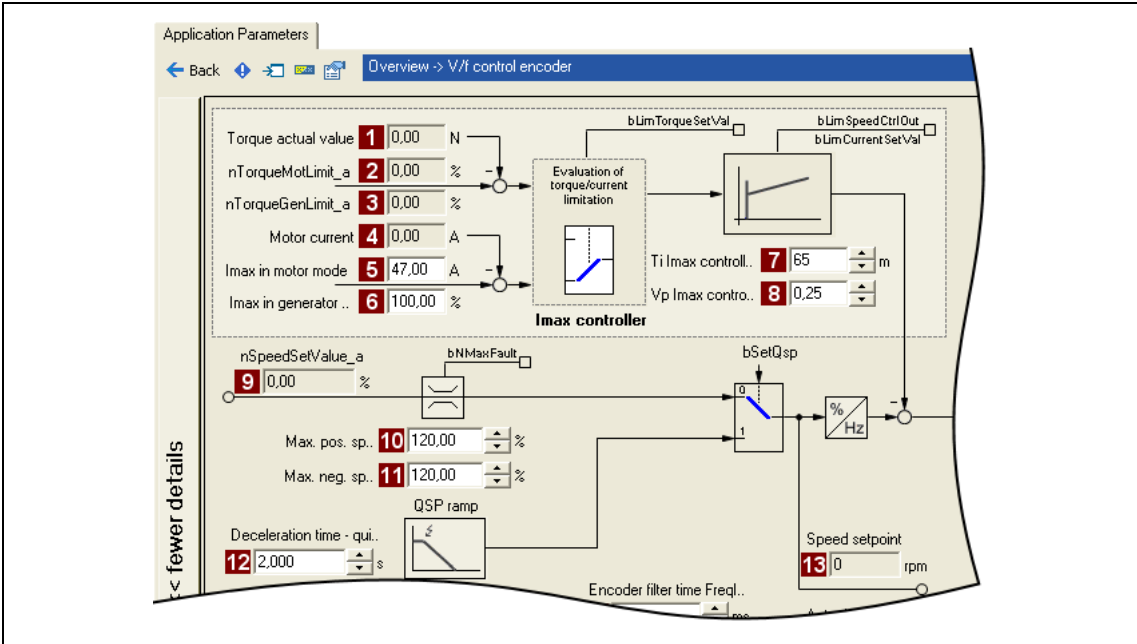
5.4 V/f characteristic control (VFCplus)

V/f characteristic control (VFC)

The accuracy of the torque limitation is limited because the actual torque ([C00056/2](#)) is only calculated from the slip speed measured indirectly via the motor current.

V/f control (VFC + encoder)

The slip speed of the motor is available at the slip controller output. This leads to a high accuracy for the actual torque ([C00056/2](#)) and the torque limitation.



[5-6] Extract from the signal flow of the V/f control (VFC + encoder)

Parameter	Info	Parameter	Info
1	C00056/2 Actual torque value	9	C00830/22 MCTRL: nSpeedSetValue_a
2	C00830/29 Limitation of torque in motor mode	10	C00909/1 Max. pos. speed
3	C00830/28 Limitation of torque in generator mode	11	C00909/2 Max. neg. speed
4	C00054 Motor current	12	C00105 Decel. time - quick stop
5	C00022 I _{max} in motor mode	13	C00050 Speed setpoint
6	C00023 I _{max} in generator mode		
7	C00074 Ti I _{max} controller		
8	C00073 Vp I _{max} controller		

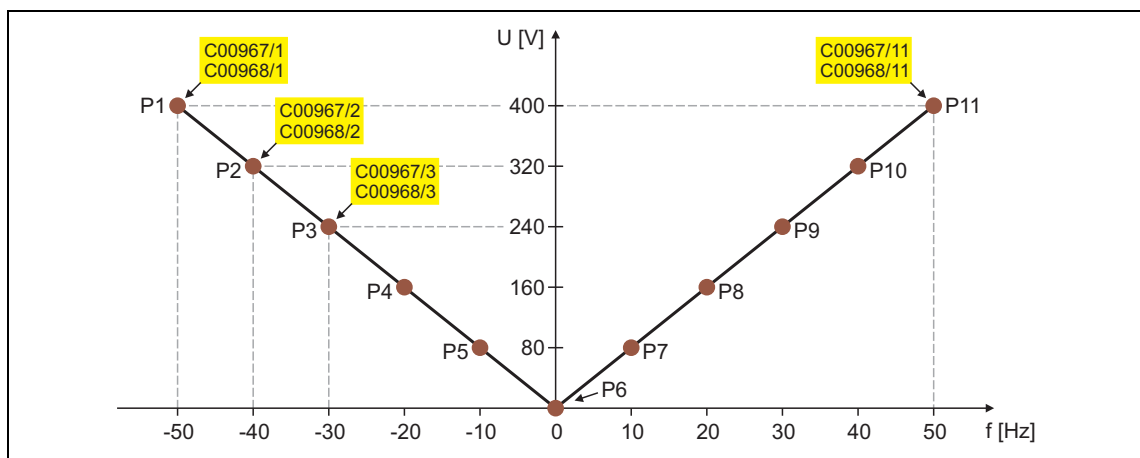
5.4.3.6 Defining a user-defined V/f characteristic

For individual adaptation of the motor magnetisation to the actual application, the motor control "10: VFCplus: V/f definable" with a freely definable characteristic can be selected in [C00006](#) as an alternative if the linear and quadratic characteristics are not suitable.

**Note!**

The V/f base frequency ([C00015](#)) and the V_{\min} boost ([C00016](#)) no longer exert an influence if this motor control is chosen.

- The 11 grid points (voltage/frequency values) of the characteristic are selected via the 11 subcodes of [C00967](#) and [C00968](#).
 - It is necessary to set all 11 grid points by means of corresponding subcodes.
 - If fewer grid points (voltage/frequency values) are needed, this can be achieved indirectly by ascribing the same voltage and frequency values to consecutive grid points.
Example: $C00967/3 = C00967/4$ and $C00968/3 = C00968/4$
 - The grid points can be specified in any sequence. Internally, they are automatically ordered from the minimum to the maximum frequency value.
 - Above the maximum and below the minimum frequency, the previous rise is continued until the maximum output voltage.
- In the Lenze setting, the 11 grid points represent a linear characteristic.
 - 3-phase devices: Output voltage 400 V at $f = 50$ Hz
 - 1-phase devices: Output voltage 230 V at $f = 50$ Hz



	P1	P2	P3	P4	P5	P6	P7	P8	P9	P10	P11
V	400 V	320 V	240 V	160 V	80 V	0 V	80 V	160 V	240 V	320 V	400 V
f	-50 Hz	-40 Hz	-30 Hz	-20 Hz	-10 Hz	0 Hz	10 Hz	20 Hz	30 Hz	40 Hz	50 Hz

[5-7] Freely definable characteristic (Lenze setting for 3-phase devices)

**Tip!**

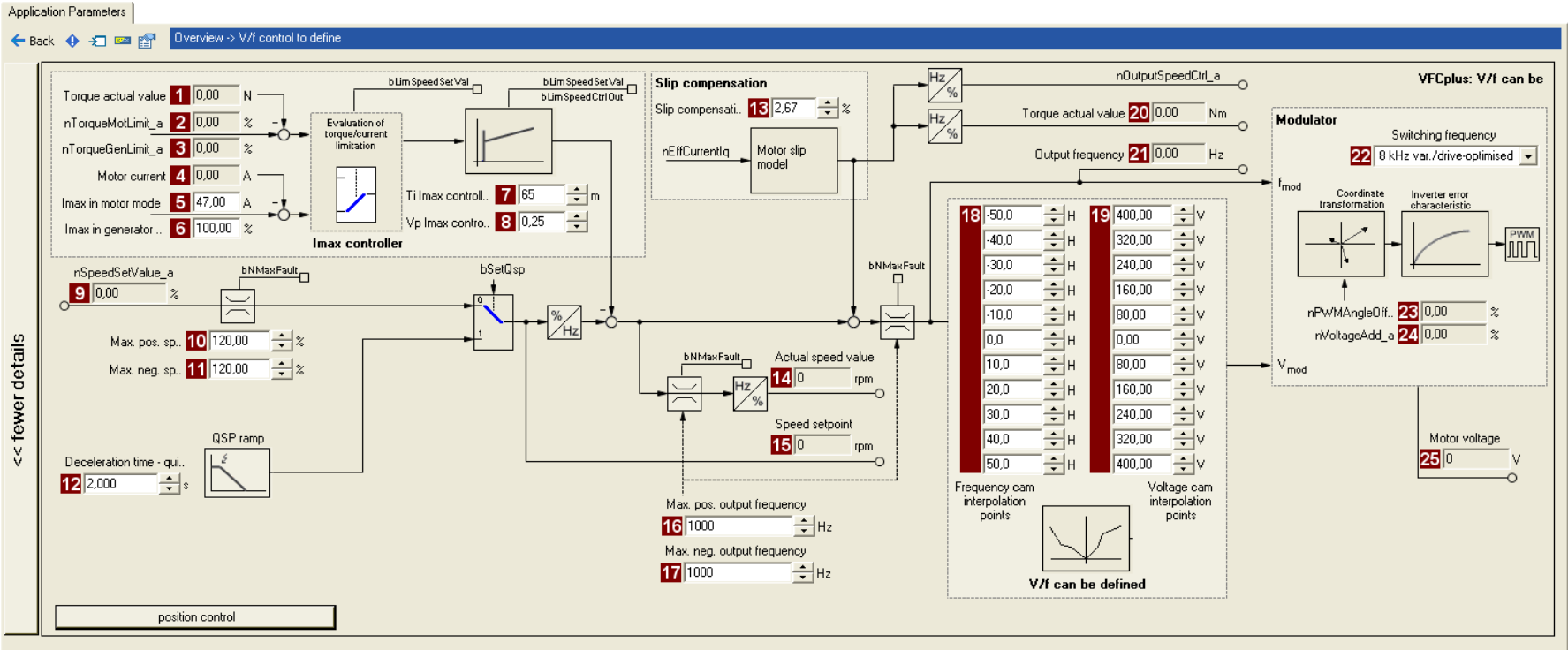
Cases of application for this function:

- Operation of reluctance motors or synchronous motors during controlled acceleration (reduction of natural frequencies caused by wrong excitation).
- Adaptation of the voltage requirement for the motor, depending on specific load conditions.



Proceed as follows to open the dialog for parameterising the motor control:

1. »Engineer« Go to the *Project view* and select the 8400 TopLine controller.
2. Select the **Application parameters** tab from the *Workspace*.
3. Select the motor control "10: VFCplus: V/f definable" from the *Overview* dialog box in the **Motor control** list field:
4. Click the **Motor control V/f definable** button to change to the *Overview → Motor control V/f* dialog box.
 - This dialog level only shows a simplified signal flow with the most important parameters.
 - When you click the **>>More details** button in the left-most position, a signal flow with more details/parameters is displayed.



Parameter	Info	Parameter	Info	Parameter	Info
1	C00056/2 Actual torque value	13	C00021 Slip compensation	18	C00967/x Frequency interpol. points
2	C00830/29 Limitation of torque in motor mode	14	C00051 Actual speed value	19	C00968/x Voltage interpol. points
3	C00830/28 Limitation of torque in generator mode	15	C00050 Speed setpoint	20	C00056/2 Actual torque value
4	C00054 Motor current	16	C00910/1 Max. pos. output frequency	21	C00058 Output frequency
5	C00022 I _{max} in motor mode	17	C00910/2 Max. neg. output frequency	22	C00018 Switching frequency
6	C00023 I _{max} in generator mode			23	C00830/32 MCTRL: nPWMAngleOffset_a
7	C00074 Ti I _{max} controller			24	C00830/31 MCTRL: nVoltageAdd_a
8	C00073 Vp I _{max} controller			25	C00052 Motor voltage
9	C00830/22 Speed setpoint				
10	C00909/1 Max. pos. speed				
11	C00909/2 Max. neg. speed				
12	C00105 Decel. time - quick stop				

5.4.4 Remedies for undesired drive behaviour

Drive behaviour	Remedy
Inadequate smooth running at low speeds, especially in the case of operation with a long motor cable	▶ Automatic motor data identification (📖 141)
Problems in case of high starting duty (great mass inertia)	▶ Adapting the Vmin boost (📖 166)
Drive does not follow the speed setpoint.	<p>The current controller intervenes in the set field frequency to limit the controller output current to the maximum current (C0022, C0023). Therefore:</p> <ul style="list-style-type: none"> • Prolong acceleration/deceleration times: C00012: Accel. time - main setpoint C00013: Decel. time - main setpoint • Consider a sufficient magnetising time of the motor. Depending on the motor power, the magnetising time amounts to 0.1 ... 0.2 s. • Increase the maximally permissible current: C00022: I_{max} in motor mode C00023: I_{max} in generator mode)
For operation without speed feedback (C00006 = 6): Insufficient speed constancy at high load (setpoint and motor speed are not proportional anymore)	<ul style="list-style-type: none"> • Increase slip compensation (C00021). Important: Unstable drive due to overcompensation! • With cyclic load impulses (e. g. centrifugal pump), a smooth motor characteristic is achieved by smaller values in C00021 (possibly negative values). <p>Note: The slip compensation is only active for operation without speed feedback.</p>
"Clamp operation active" error message (oC11): Controller cannot follow dynamic processes, i.e. too short acceleration/deceleration times in terms of load ratios.	<ul style="list-style-type: none"> • Increase the gain of the I_{max} controller (C00073/1) • Reduce the reset time of the I_{max} controller (C00074/1) • Prolong the acceleration time (C00012) • Prolong the deceleration time (C00013)
Motor stalling in the field weakening range (adaptation especially required for small machines)	<ul style="list-style-type: none"> • Reduce the override point of field weakening (C00080) • If motor power < inverter power: Set C00022 to I_{max} = 2 I_{rated motor} • Reduce dynamic performance of setpoint generation

5.5

V/f characteristic control - energy-saving (VFCplusEco)

With the energy-saving V/f characteristic control mode (VFCplusEco), the motor voltage of the inverter is detected by means of a linear characteristic depending on the field frequency to be created or the motor speed. Moreover, a $\cos\phi$ control and the resulting voltage reduction causes the motor to be always operated in the optimum efficiency range (reduction of copper losses in the asynchronous motor).

- Hence, these are the advantages of this motor control mode:
 - Good robustness
 - Easy parameter setting
 - High energy efficiency (lower heating of the motor in partial load operational range)
 - Same speed accuracy and maximum torques as with VFCplus
 - Less noise generation of the motor with active voltage reduction
- Predetermined application areas of this motor control mode are materials handling technology and pump and fan systems.
- This motor control mode serves to improve efficiency of standard asynchronous motors with efficiency class IE1 (standard IEC 60034-30 2008) in the range 0 ... $M_{\text{efficiency_max}}$ between 0 ... 20 % (\emptyset 5 ... 10 %).
 - For asynchronous motors with energy efficiency class IE2 the potential for efficiency improvement is reduced to approx. 0 ... 15 %.
 - Description of $M_{\text{efficiency_max}}$: Indicates the torque [%] of $M_{\text{rated_motor}}$, where the motor has the max. efficiency.)
- In case of asynchronous motors with a higher energy efficiency class (IE2 and IE3), the absolute energy saving of the motor control mode is lower due to improved efficiency of the machine. However, energy saving is still achieved in a higher load range.
- $M_{\text{efficiency_max}}$ is performance-related and listed in the following table for some power values of the energy efficiency class IE1 and IE2:

Power	$M_{\text{efficiency_max}}$ (related to $M_{\text{rated_motor}}$)	
	IE1	IE2
0.25 kW	75 %	
0.75 kW	65 %	75 %
2.2 kW	55 %	85 %
7.5 kW	30 %	45 %
22 kW	23 %	
45 kW	21 %	



Stop!

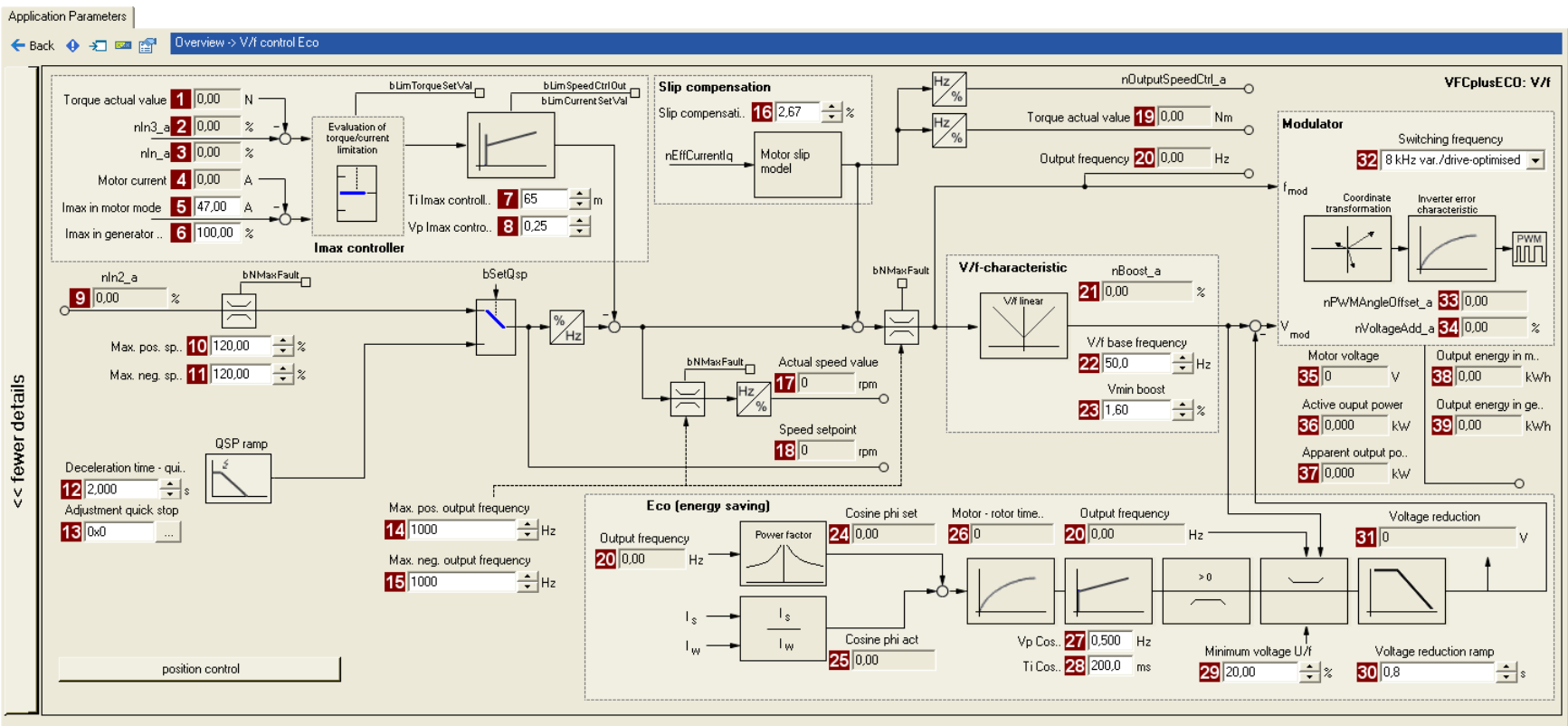
- For adjustment, observe the thermal performance of the connected asynchronous motor at low output frequencies.
 - Usually, standard asynchronous motors with insulation class B can be operated for a short time with their rated current in the frequency range 0 Hz ... 25 Hz.
 - Contact the motor manufacturer to get the exact setting values for the max. permissible motor current of self-ventilated motors in the lower speed range.
- The nameplate data of the motor (at least rated speed and rated frequency) must be entered if, instead of a standard motor, an asynchronous motor is used with the following values:
 - rated frequency \neq 50 Hz (star) or
 - rated frequency \neq 87 Hz (delta) or
 - number of pole pairs \neq 2

5.5.1 Parameterisation dialog/signal flow



Proceed as follows to open the dialog for parameterising the motor control:

1. »Engineer« Go to the *Project view* and select the 8400 TopLine controller.
2. Select the **Application parameters** tab from the *Workspace*.
3. Select the motor control "11: VFCplusEco: V/f energy-saving" from the *Overview* dialog box in the **Motor control** 11list field:
4. Click the **Motor control V/f Eco** button to change to the *Overview* → *Motor control V/f* dialog box.
 - This dialog level only shows a simplified signal flow with the most important parameters.
 - When you click the >>**More details** button in the left-most position, a signal flow with more details/parameters is displayed.

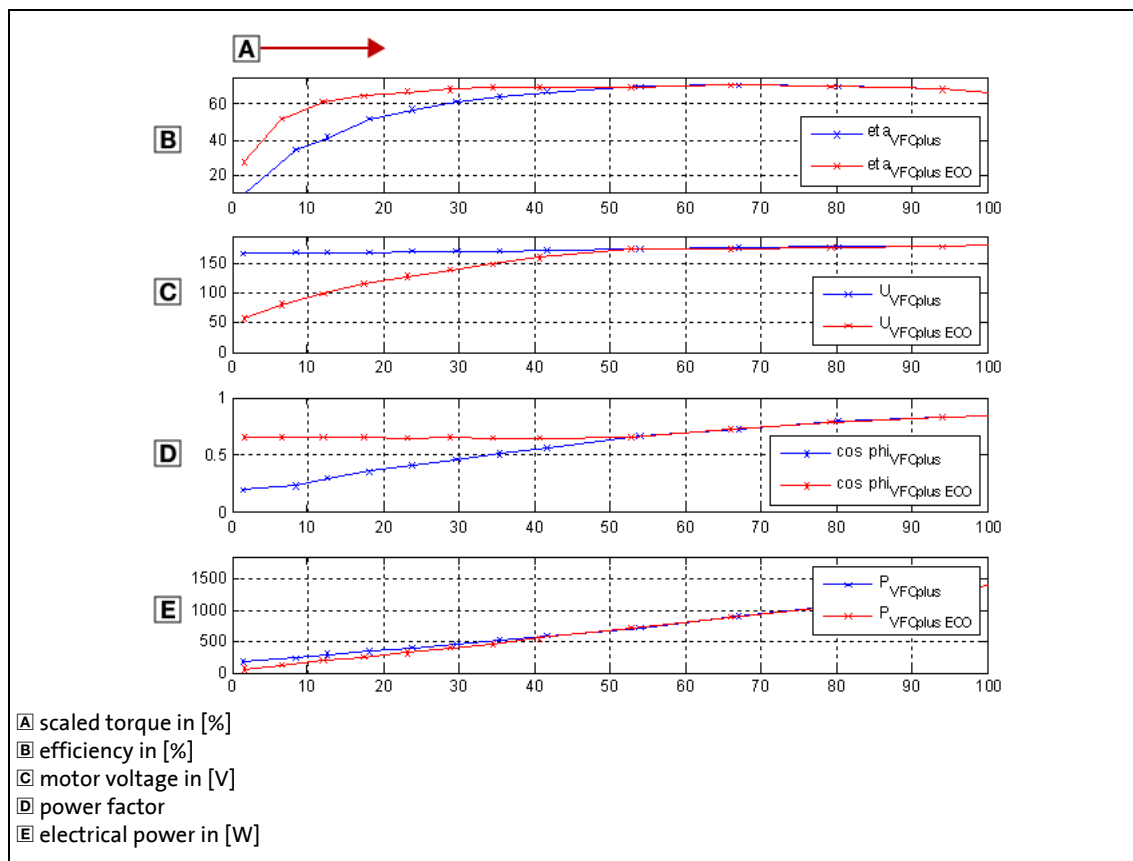


Parameter	Info	Parameter	Info	Parameter	Info
1	C00056/2 Actual torque value	14	C00910/1 Max. pos. output frequency	27	C00975 VFC-ECO: Vp
2	C00830/4 Limitation of torque in motor mode	15	C00910/2 Max. neg. output frequency	28	C00976 VFC-ECO: Ti
3	C00830/5 Limitation of torque in generator mode	16	C00021 Slip compensation	29	C00977 VFC-ECO: Minimum voltage V/f
4	C00054 Motor current	17	C00051 Actual speed value	30	C00982 VFC-ECO: Voltage reduction ramp
5	C00022 I _{max} in motor mode	18	C00050 Speed setpoint	31	C00978 VFC-ECO: Voltage reduction
6	C00023 I _{max} in generator mode	19	C00056/2 Actual torque value	32	C00018 Switching frequency
7	C00074 Ti I _{max} controller	20	C00058 Output frequency	33	C00830/32 MCTRL: nPWMAngleOffset_a
8	C00073 Vp I _{max} controller	21	C00830/26 MCTRL: nBoost_a	34	C00830/31 MCTRL: nVoltageAdd_a
9	C00830/3 Speed setpoint	22	C00015 V/f base frequency	35	C00052 Motor voltage
10	C00909/1 Max. pos. speed	23	C00016 Vmin boost	36	C00980/1 Active output power
11	C00909/2 Max. neg. speed	24	C00979/2 Cosine phi set	37	C00980/2 Apparent output power
12	C00105 Decel. time - quick stop	25	C00979/1 Cosine phi act	38	C00981/1 Output energy in motor mode
13	C00104/1 Quick stop setting	26	C00083 Motor rotor time constant	39	C00981/2 Output energy in generator mode

5.5.2 Comparison of VFCplusEco - VFCplus

The following characteristics show the impact of the energy-saving V/f characteristic control (VFCplusEco) compared to the standard V/f characteristic control (VFCplus).

- The characteristics were recorded with a standard asynchronous motor 2.2 kW with energy efficiency class IE1 at speed = 600 rpm.



[5-8] Comparison of VFCplusEco - VFCplus

5.5.3 Basic settings

The "Initial commissioning steps" listed in the table below are sufficient for the V/f characteristic control - energy-saving (VFCplusEco).

- Detailed information on the individual steps can be found in the following subchapters.

Initial commissioning steps			
1.	Determine the motor control: C00006 = "11: VFCplusEco: V/f energy-saving"		
2.	<p>The required motor data are pre-initialised depending on the device and thus, they do not need to be entered directly. In order to achieve a high energy optimisation, these motor data can be entered (see the following section).</p> <p>Set the motor selection/motor data</p> <ul style="list-style-type: none"> • When selecting and parameterising the motor, the motor nameplate data and the equivalent circuit diagram data are relevant. Detailed information can be found in the "Motor selection/Motor data" chapter. (135) <p>Depending on the motor manufacturer, proceed as follows:</p> <table border="1"> <tr> <td> Lenze motor: Selecting a motor from the motor catalogue in the »Engineer« - or - 1. Set the motor nameplate data 2. Automatic motor data identification </td><td> Third party manufacturer's motor: 1. Set the motor nameplate data 2. Automatic motor data identification or set known equivalent circuit diagram manually: C00084: Motor stator resistance C00085: Motor stator leakage inductance C00092: Motor magnetising inductance </td></tr> </table>	Lenze motor: Selecting a motor from the motor catalogue in the »Engineer« - or - 1. Set the motor nameplate data 2. Automatic motor data identification	Third party manufacturer's motor: 1. Set the motor nameplate data 2. Automatic motor data identification or set known equivalent circuit diagram manually: C00084 : Motor stator resistance C00085 : Motor stator leakage inductance C00092 : Motor magnetising inductance
Lenze motor: Selecting a motor from the motor catalogue in the »Engineer« - or - 1. Set the motor nameplate data 2. Automatic motor data identification	Third party manufacturer's motor: 1. Set the motor nameplate data 2. Automatic motor data identification or set known equivalent circuit diagram manually: C00084 : Motor stator resistance C00085 : Motor stator leakage inductance C00092 : Motor magnetising inductance		
3.	Defining current limits (I_{max} controller) . (162)		



Tip!

Information on the optimisation of the control mode and the adaptation to the real application is provided in chapter "[Optimising the control mode](#)". ([181](#))

Parameterisable additional functions are described correspondingly in the chapter "[Parameterisable additional functions](#)". ([256](#))

5.5.4 Optimising the control mode

The V/f characteristic control - energy-saving (VFCplus) is generally ready for operation. It can be adapted subsequently by adapting the characteristic and/or the drive behaviour.



Note!

Following successful motor parameter identification, the V/f base frequency ([C00015](#)) and the V_{\min} boost ([C00016](#)) as well as the slip constant for slip compensation ([C00021](#)) are calculated automatically.

From version 12.00.00 onwards:

- Following successful motor parameter identification, the gain of the I_{\max} controller ([C00073/1](#)) is calculated automatically.
 - If these parameters are not to be calculated, bit 4 of [C02865/1](#) must be set to "1".
- Following successful motor parameter identification, other controller parameters ([C00011](#), [C00022](#), [C00966](#), [C00982](#)) can be calculated automatically.
 - If these parameters are to be calculated, bit 6 of [C02865/1](#) must be set to "6".

Adapting characteristic

For the linear characteristic as part of the V/f characteristic control - energy-saving (VFCplusEco), it is also possible (like in case of the standard V/f characteristic control) to match its curve to different load profiles or motors by adapting the V/f base frequency ([C00015](#)) and the V_{\min} boost ([C00016](#)).

► [Adapting the V/f base frequency](#) ([164](#))

► [Adapting the \$V_{\min}\$ boost](#) ([166](#))

Adapting drive behaviour

- Limitation of the maximum current by a current limitation controller (e.g. to prevent the motor from stalling or to limit to the maximally permissible motor current). ► [Optimising the \$I_{\max}\$ controller](#) ([168](#))
- Adaptation of the field frequency by a load-dependent slip compensation (improved speed accuracy for systems without feedback).
- [Improving the behaviour at high dynamic load changes](#). ([182](#))
- [Adapting the slope limitation for lowering the Eco function](#). ([183](#))
- [Optimising the cos/phi controller](#). ([183](#))

Torque limitation

Limit the torque to a lower value. ► [Torque limitation](#) ([170](#))

5.5.4.1 Improving the behaviour at high dynamic load changes

Due to the voltage reduction executed via the $\cos\phi$ control, the motor may stall in the Lenze setting at high dynamic load torque changes. This is caused by the flux reduction and the connected reduction of the stalling torque of the motor current:

$$M_{\text{Max}(t)} = M_{\text{Stalling}} \cdot \frac{U_{\text{Motor}(t)}^2}{(U_{\text{Motor}(t)} - U_{\text{Reduction}})^2} \quad \text{with } M_{\text{Stalling}} = 1.6 \dots 2.5 \cdot M_{\text{Rated_motor}}$$

V_{Motor} = display in [C00052](#)
 $V_{\text{Reduction}}$ = display in [C00978](#)

It generally applies that when the output voltage is divided in halves, the maximum torque is approx. reduced by the factor 4. A reduction by the factor 3 reduces the torque to approx. 15 %.

The minimum voltage and thus the maximum influence access of the Eco function on the output voltage can be defined in [C00977](#). With full influence of the Eco function, the following stalling torque can be ensured depending on the setting in [C00977](#):

Minimum voltage V/f (C00977)	Maximum torque
100 %	160 % ... 250 % M_{rated}
70 %	80 % ... 130 % M_{rated}
50 %	40 % ... 70 % M_{rated}
20 %	15 % ... 50 % M_{rated}

An adaptation of the minimum voltage V/f ([C00977](#)) improves the stability in case of load impulses.

- In the Lenze setting, the minimum voltage V/f is set to 20 % for the highest energy optimisation. This setting serves to respond to load torques if these amount to approx. 25 % of the rated torque or occur with low dynamics.
- An increase of the minimum voltage V/f to 70 % permits to apply a dynamic load impulse from 0 to 100 % rated motor torque without the motor stalling. This reduces the energy optimisation to be achieved by approx. 75 %.
- A further increase of the stability at still higher dynamic load impulses can be achieved by a further increase of the minimum voltage V/f, but means a further loss in energy optimisation.



Note!

In case of applications with very high dynamic sudden load variations from the unloaded operation, this motor control mode should not be used or the energy optimisation should be switched off, since a motor stalling cannot be excluded.

- The energy optimisation can be switched off by setting the minimum voltage V/f ([C00977](#)) to 100 %. Then, the behaviour corresponds to the V/f characteristic control (VFCplus) with linear characteristic.
- From version 13.00.00, the energy optimisation can be switched off via the *bVfcEcoDisable* process signal if a dynamic load change is known to take place.

5.5.4.2 Adapting the slope limitation for lowering the Eco function

The ramp set in [C00982](#) for voltage reduction serves as slope limitation in order to prevent that voltage is suddenly applied to the motor when the Eco function is deactivated. Otherwise, the overvoltage limitation (Imax, Clamp) would be activated.

- This ramp is, depending on the device, pre-initialised to approx. the triple rotor time constant. An adaptation of this parameter is not required.

When the Eco function is switched off, a quick reaction (high dynamic performance) is required, but with a low current overshoot and a small torque jump. Thus, the Lenze setting of [C00982](#) is a compromise regarding the switch-off of the Eco function (voltage reduction = 0).

- To increase the dynamics when switching off the Eco function:
Reduce → setting in [C00982](#).
(Current compensation actions increase when the Eco function is switched off.)
- In order to reduce current compensation actions when switching off the Eco function:
Increase → setting in [C00982](#).
(The dynamics when switching off the eco function is reduced)

5.5.4.3 Optimising the cos/phi controller

With the Lenze setting, the cosφ controller is set such that usually no adaptation is required for all power ratings and application cases.

Behaviour	Remedy/recommendation
The cosφ actual value (C00979/1) varies greatly.	Reduce gain Vp (C00975) and reset time Ti (C00976).
The cosφ actual value (C00979/1) is permanently lower than the cosφ setpoint (C00979/2).	Increase gain Vp (C00975) and reset time Ti (C00976).

5.5.5 Remedies for undesired drive behaviour

Drive behaviour	Remedy
Inadequate smooth running at low speeds, especially in the case of operation with a long motor cable	<p>► Automatic motor data identification (□ 141)</p> <p>Reduce the influence of the Eco function by increasing the minimum voltage V/f (C00977) if necessary.</p>
Problems in case of high starting duty (great mass inertia)	<ol style="list-style-type: none"> 1. Set motor control VFCplus with linear characteristic (C00006 = 6). 2. Adapting the Vmin boost. (□ 166) 3. Again set motor control VFCplusEco (C00006 = 11).
Drive does not follow the speed setpoint	<p>The current controller intervenes in the set field frequency to limit the controller output current to the maximum current (C0022, C0023). Therefore:</p> <ul style="list-style-type: none"> • Prolong acceleration/deceleration times: <ul style="list-style-type: none"> C00012: Accel. time - main setpoint C00013: Decel. time - main setpoint • Consider a sufficient magnetising time of the motor. Depending on the motor power, the magnetising time amounts to 0.1 ... 0.2 s. • Increase the maximally permissible current: <ul style="list-style-type: none"> C00022: I_{max} in motor mode C00023: I_{max} in generator mode • Make adaptations for the Eco function: <ul style="list-style-type: none"> • Improving the behaviour at high dynamic load changes. (□ 182) • Adapting the slope limitation for lowering the Eco function. (□ 183) • Optimising the cos/phi controller. (□ 183)
Insufficient speed constancy at high load (setpoint and motor speed are not proportional anymore)	<ul style="list-style-type: none"> • Increase slip compensation (C00021). <p>Important: Unstable drive due to overcompensation!</p> <ul style="list-style-type: none"> • With cyclic load impulses (e. g. centrifugal pump), a smooth motor characteristic is achieved by smaller values in C00021 (possibly negative values). <p>Note: The slip compensation is only active for operation without speed feedback.</p>
"Clamp operation active" error message (oC11): Controller cannot follow dynamic processes, i.e. too short acceleration/deceleration times in terms of load ratios.	<ul style="list-style-type: none"> • Increase the gain of the I_{max} controller (C00073) • Reduce the reset time of the I_{max} controller (C00074) • Prolong the acceleration time (C00012) • Prolong the deceleration time (C00013) • Make adaptations for the Eco function: <ul style="list-style-type: none"> • Improving the behaviour at high dynamic load changes. (□ 182) • Adapting the slope limitation for lowering the Eco function. (□ 183)
Motor stalling in the field weakening range (adaptation especially required for small machines)	<ul style="list-style-type: none"> • If motor power < inverter power: Set C00022 to I_{max} = 2 I_{rated motor} • Reduce dynamic performance of setpoint generation • Make adaptations for the Eco function: <ul style="list-style-type: none"> • Improving the behaviour at high dynamic load changes. (□ 182) • Adapting the slope limitation for lowering the Eco function. (□ 183)
Speed variations in no-load operation for speeds > 1/3 rated speed.	Minimise speed oscillations with oscillation damping (C00234).

Drive behaviour	Remedy
Speed variations in no-load operation and with load for speeds > rated speed.	Minimise speed oscillations with increasing the oscillation damping field weakening (C00236). Caution: If C00236 is increased, the maximum output voltage of the device is reduced!
Output voltage is too low. There is a too low maximum torque in the high field weakening range.	Reduction of the oscillation damping field weakening (C00236). Caution: When C00236 = 0, oscillation damping field weakening is inactive. Thus, a maximum output voltage is available but the tendency to speed oscillations in the field weakening range at no-load operation and with load increases.

5.6 V/f control (VFCplus + encoder)

The V/f characteristic control (VFCplus) described above can be operated with a speed feedback. This has the following advantages:

- Steady-state accuracy of the speed
- Less parameterisation effort compared to the sensorless vector control (SLVC)
- Improved dynamics compared to V/f characteristic control without feedback or to sensorless vector control (SLVC).
- Suitability for group drives



Stop!

The V/f control requires a speed feedback!

- The speed sensor used has to be set in [C00495](#). This setting is not made automatically with the selection of the motor from the »Engineer« motor catalogue!
- If no speed sensor is set in [C00495](#) and the controller is enabled, an impermissibly high motor current occurs which may destroy the motor thermally!
- From version 14.00.00, the error response set in [C00571/2](#) (Lenze setting: "Fault") takes place if in case of controller enable it is detected that a motor control type with feedback is set in [C00006](#) but no speed encoder is set in [C00495](#).



Stop!

V/f emergency operation

From version 15.00.00, it is internally switched to the encoderless V/f characteristic control in case of an encoder open circuit in order to avoid impermissible motor movements.

- In order that this "V/f emergency operation" works properly, the parameters relevant for the V/f characteristic control (base frequency, Vmin boost, slip compensation, etc.) have to be set correctly. As an alternative, a motor parameter identification can be executed as well.
- The change-over to "V/f emergency operation" is reported via bit 4 in [C01000](#) and via the *bWirebreakUfLinearActive* status signal at the SB [LS DeviceMonitor](#).
- The change-over to "V/f emergency operation" can be suppressed by setting bit 8 to "1" in [C02864/1](#).



Note!

As the slip is calculated in the feedback V/f operation and injected through the slip regulator, the slip compensation ([C00021](#)) is deactivated with V/f control.



The descriptions in chapter "[V/f characteristic control \(VFCplus\)](#)" also apply to the V/f control. ([157](#))

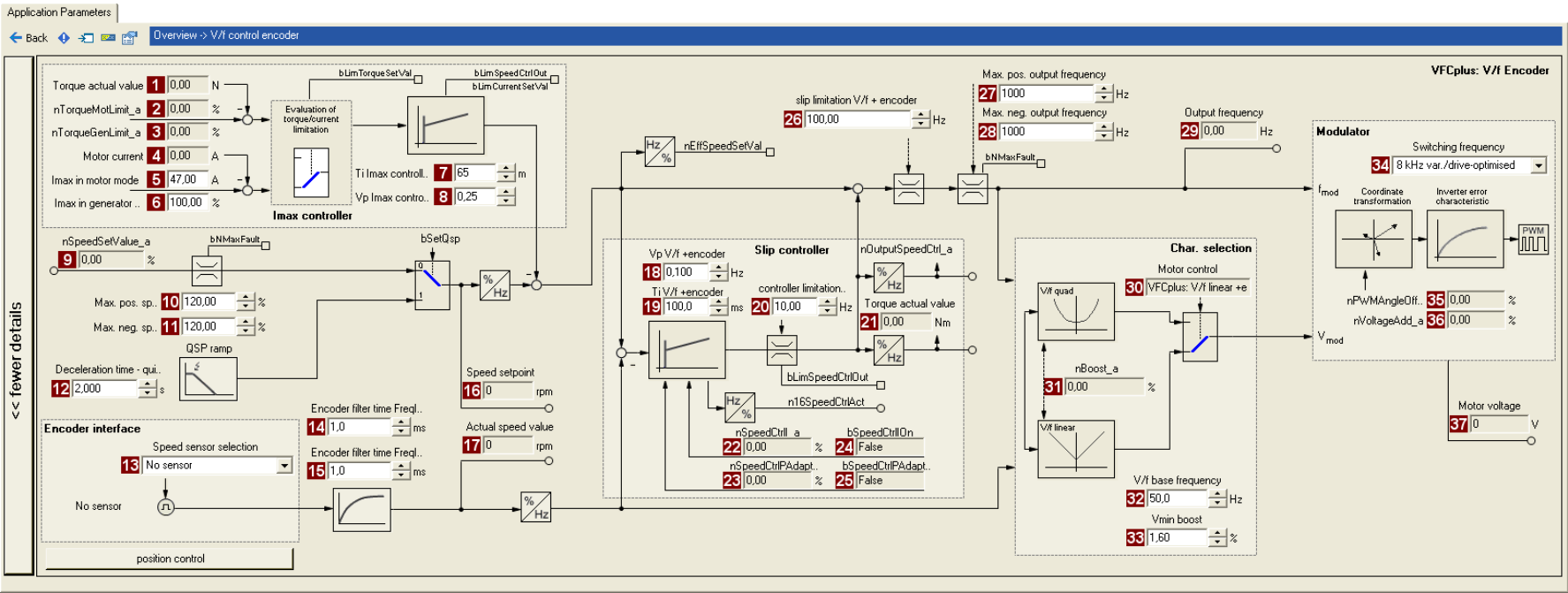
Detailed information on the speed feedback can be found in the chapter "[Encoder/feedback system](#)". ([314](#))

5.6.1 Parameterisation dialog/signal flow



Proceed as follows to open the dialog for parameterising the motor control:

1. »Engineer« Go to the *Project view* and select the 8400 TopLine controller.
2. Select the **Application parameters** tab from the *Workspace*.
3. Select the motor control from the *Overview* dialog level in the **Motor control** ([C00006](#)) list field:
 - "7: VFCplus: V/f linear +encoder" for linear characteristic or
 - "9: VFCplus: V/f quadr +encoder" for quadratic characteristic
4. Click the **Motor control V/f encoder** button to change to the *Overview* → *Motor control V/f* dialog box.
 - This dialog level only shows a simplified signal flow with the most important parameters.
 - When you click the >>**More details** button in the left-most position, a signal flow with more details/parameters is displayed, as shown in the following subchapter.



Parameter	Info	Parameter	Info	Parameter	Info
1	C00056/2 Actual torque value	16	C00050 Speed setpoint	29	C00058 Output frequency
2	C00830/29 Limitation of torque in motor mode	17	C00051 Actual speed value	30	C00006 Motor control
3	C00830/28 Limitation of torque in generator mode	18	C00972 Vp Vf+encoder	31	C00830/26 MCTRL: nBoost_a
4	C00054 Motor current	19	C00973 Ti Vf+encoder	32	C00015 V/f base frequency
5	C00022 Imax in motor mode	20	C00971/1 Controller limitation Vf+encoder	33	C00016 Vmin boost
6	C00023 Imax in generator mode	21	C00056/2 Actual torque value	34	C00018 Switching frequency
7	C00074 Ti Imax controller	22	C00830/24 MCTRL: nSpeedCtrl_a	35	C00830/32 MCTRL: nPWMAngleOffset_a
8	C00073 Vp Imax controller	23	C00830/25 MCTRL: nSpeedCtrlAdapt_a	36	C00830/31 MCTRL: nVoltageAdd_a
9	C00830/22 Speed setpoint	24	C00833/31 MCTRL: bSpeedCtrlOn	37	C00052 Motor voltage
10	C00909/1 Max. pos. speed	25	C00833/69 MCTRL: bSpeedCtrlAdaptOn		
11	C00909/2 Max. neg. speed	26	C00971/2 Slip limitation Vf+encoder		
12	C00105 Decel. time - quick stop	27	C00910/1 Max. pos. output frequency		
13	C00495 Speed sensor selection	28	C00910/2 Max. neg. output frequency		
14	C00497/2 Encoder filter time FreqIn67				
15	C00497/1 Encoder filter time FreqIn12				

5.6.2 Basic settings

In order to protect the drive system, carry out the commissioning of the V/f control and the slip regulator in several steps.

- Detailed information on the single steps can be found in the following subchapters or in the corresponding subchapters for V/f characteristic control.

Initial commissioning steps	
1.	Define the V/f characteristic: <ul style="list-style-type: none"> • C00006 = 7: Linear characteristic • C00006 = 9: Quadratic characteristic
2.	Defining current limits (I_{max} controller) . (162)
3.	Parameterise encoder/feedback system. <ul style="list-style-type: none"> ▶ Encoder/feedback system (314)
4.	If special motors with a rated frequency other than 50 Hz or with a number of pole pairs $\neq 2$ are used, set the motor parameters according to the motor nameplate. <ul style="list-style-type: none"> ▶ Motor selection/Motor data (135)
5.	Define speed setpoint (e.g. 20 % of the rated speed) and enable controller.
6.	Check whether the actual speed value (C00051) \approx speed setpoint (C00050) and then inhibit the controller again. <ul style="list-style-type: none"> • In case of a sign reversal between actual value and setpoint, check the connection or setting of the encoder. • In case the actual value differs considerably from the setpoint (factor 2), set the motor parameters according to motor nameplate. Then repeat step 5.
7.	To protect the drive, reduce the slip regulator limitation in C00971/1 . <ul style="list-style-type: none"> • e.g. reduction to half the slip frequency (≈ 2 Hz)
8.	Define speed setpoint (e.g. 20 % of the rated speed) and enable controller.
9.	In case of a semi-stable operational performance, reduce the reset time (C00972) or the proportional gain (C00973) of the slip regulator until a stable operation has been achieved. <ul style="list-style-type: none"> ▶ Parameterising the slip regulator (190)
10.	In a final step, increase the slip regulator limitation again in C00971/1 . <ul style="list-style-type: none"> • e.g. increase to twice the slip frequency



Tip!

Information on the further optimisation of the control mode and the adaptation to the real application is provided in the "[Optimising the control mode](#)" chapter for the V/f characteristic control (VFCplus). (163)

Parameterisable additional functions are described correspondingly in the chapter "[Parameterisable additional functions](#)". (256)

5.6.2.1 Parameterising the slip regulator

The slip regulator is designed as a PI controller. In order to improve the response to setpoint changes, the setpoint speed or setpoint frequency is added to the output (correcting variable) of the slip regulator as feedforward control value.

- Unlike traditional speed controllers, the slip regulator only controls the slip.
- In the Lenze setting, the configuration of the slip regulator provides robustness and moderate dynamics.

Parameter	Info	Lenze setting	
		Value	Unit
C00971/1	VFC: Controller limitation V/f +encoder	10.00	Hz
C00971/2	VFC: Slip limitation V/f +encoder	100.00	Hz
C00972	VFC: Vp V/f +encoder	0.100	Hz/Hz
C00973	VFC: Ti V/f +encoder	100.0	ms

Slip regulator gain Vp

The setting range of the slip regulator gain Vp ([C00972](#)) which leads to a stable operational performance, mainly depends on the resolution of the speed sensor. There is a direct relationship between encoder resolution and gain:

- The higher the encoder resolution, the higher the gain can be set.

The following table provides maximum and recommended slip regulator gains for encoder with standard encoder increments:

Encoder increment [Increments/revolution]	Slip regulator gain Vp	
	maximum	recommended
8	0.09	0.06
64	0.52	0.31
100	0.79	0.47
120	0.94	0.57
128	1.00	0.60
256	1.29	0.77
386	1.63	0.98
512	1.97	1.18
640	2.31	1.38
768	2.65	1.59
896	2.99	1.79
1014	3.33	2.00
1536	4.69	2.81
2048	6.05	3.63
3072	8.77	5.26
4096	11.49	6.90

[5-1] Slip regulator gain Vp based on the encoder increment



How to adapt the slip regulator gain to the operating conditions:

1. Adapt the slip regulator gain ([C00972](#)) to the encoder increment according to table [\[5-1\]](#).
2. Set controller limitation ([C00971/1](#)) to half the slip frequency (≈ 2 Hz).
3. Select speed setpoint (e.g. 20 % of the rated speed).
4. Enable controller.
5. Increase the slip regulator gain ([C00972](#)) until the drive is semi-stable.
 - This can be recognised by motor noises or "humming" of the motor or by a noise on the actual speed signal.
6. Reduce slip regulator gain ([C00972](#)) until the drive runs stable again (no motor "humming").
7. Reduce slip regulator gain ([C00972](#)) to approx. half the value.
 - With low encoder resolutions, another reduction of the the slip regulator gain for low speeds may be necessary (speed setpoint ≈ 0).
 - We recommend to finally check the behaviour at setpoint speed = 0 and to further reduce the slip regulator gain if irregular running occurs.
8. Increase controller limitation ([C00971/1](#)) again (e.g. to twice the slip frequency).

Slip regulator time constant T_i



How to set the slip regulator time constant:

1. Set controller limitation ([C00971/1](#)) to half the slip frequency (≈ 2 Hz).
2. Select speed setpoint (e.g. 20 % of the rated speed).
3. Enable controller.
4. Reduce the slip regulator time constant ([C00973](#)) until the drive is semi-stable.
 - This can be recognised by motor noise, "motor vibrations" or resonance on the actual speed value signal.
5. Increase slip regulator time constant ([C00973](#)) until the drive runs stable again (no motor "oscillation").
6. Increase the slip regulator time constant ([C00973](#)) to approx. twice the value.
7. Increase controller limitation ([C00971/1](#)) again (e.g. to twice the slip frequency).

Controller limitation

Max. intervention of the controller is limited by the controller limitation ([C00971/1](#)).

- The controller can be limited depending on the application.
- We recommend to limit the max. intervention to twice the rated slip of the motor.
- The rated slip is calculated as follows:

$$f_{\text{Slip}_{\text{Rated}}} [\text{Hz}] = f_{\text{Rated}} [\text{Hz}] - \left(\frac{n_{\text{Motor}_{\text{Rated}}} [\text{rpm}]}{60} \cdot p_{\text{Number of pole pairs}} \right)$$

[5-9] Calculation of the rated slip

**Note!**

A setting of [C00971/1](#) = 0 Hz deactivates the slip regulator. In this case, the structure of the V/f control corresponds to the structure of a V/f characteristic control without feedback.

Slip limitation

In addition to limiting the slip regulator, the field frequency to be injected can also be limited by another limiting element, the slip limitation ([C00971/2](#)).

- If the slip is e.g. limited to twice the rated slip of the motor, a stalling of the motor during very dynamic processes can be avoided.
- Motor stalling is caused by:
 - a high overcurrent at very steep speed ramps
 - very fast speed changes due to load, e.g. abrupt stopping of the drive due to an encounter with a stop or a load that is not moving.

5.7 Sensorless vector control (SLVC)

Sensorless vector control (SLVC) is based on a better motor current control according to a field-oriented control mode by Lenze.



Stop!

- The sensorless vector control (SLVC) is only suitable for asynchronous motors.
- The connected motor may be maximally two power classes lower than the motor assigned to the controller.
- Operation of the sensorless vector control (SLVC) is only permissible for one single drive!
- Operation of the sensorless vector control (SLVC) is not permissible for hoists!
- The Lenze setting permits the operation of a power-adapted motor. Optimal operation is only possible if either:
 - the motor is selected via the »Engineer« motor catalogue,
 - the motor nameplate data are entered and motor parameter identification is carried out afterwards
 - or -
 - the nameplate data and equivalent circuit data of the motor (motor leakage inductance and mutual motor inductance, slip compensation and motor stator resistance) are entered manually.
- When you enter the motor nameplate data, take into account the phase connection implemented for the motor (star or delta connection). Only enter the data applying to the selected connection type.
 - In this context, also observe the instructions in chapter "[Adapting the V/f base frequency](#)" relating to V/f characteristic control. ([164](#))



Note!

Optimal operation of the sensorless vector control (SLVC) can be achieved from a minimum speed of approx. 0.5-fold slip speed. At lower speed values below the 0.5-fold slip speed, the maximum torque is reduced.

The maximum field frequency with this motor control mode is 650 Hz.

In comparison to the V/f characteristic control without feedback, the following can be achieved by means of sensorless vector control SLVC:

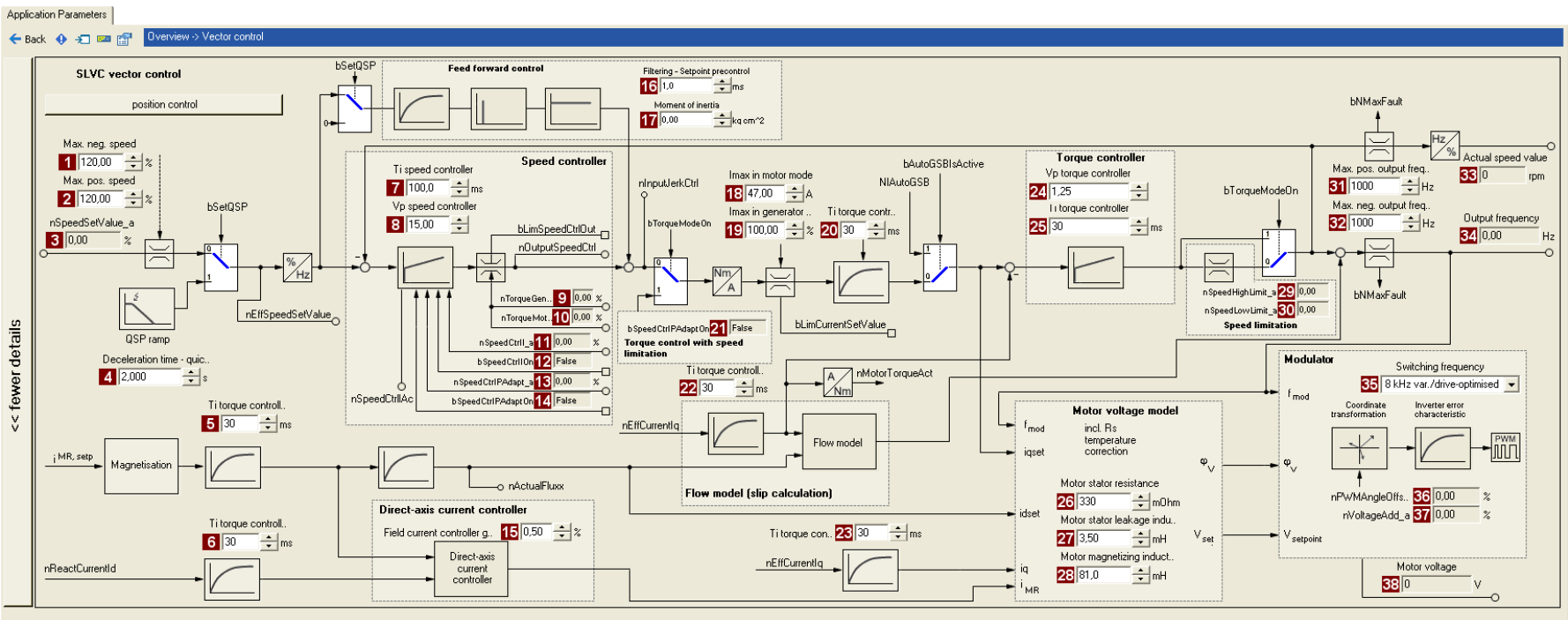
- A higher maximum torque throughout the entire speed range
- A higher speed accuracy
- A higher concentricity factor
- A higher level of efficiency
- The implementation of torque-controlled operation with speed limitation
- The limitation of the maximum torque in motor and generator mode for speed-controlled operation

5.7.1 Parameterisation dialog/signal flow



Proceed as follows to open the dialog for parameterising the motor control:

1. »Engineer« Go to the *Project view* and select the 8400 TopLine controller.
2. Select the **Application parameters** tab from the *Workspace*.
3. Select the motor control "4: SLVC: Vector control" from the *Overview* dialog level in the **Motor control** list field ([C00006](#)):
4. Click the **Motor control vector** button to change to the *Overview → Motor control vector* dialog box.
 - This dialog level only shows a simplified signal flow with the most important parameters.
 - When you click the >>**More details** button in the left-most position, a signal flow with more details/parameters is displayed, as shown in the following subchapter.



Parameter	Info	Parameter	Info	Parameter	Info
1	C00909/2 Max. neg. speed	16	C00275 Setpoint feedforward control filtering	24	C00073/2 SLVC: Vp torque controller
2	C00909/1 Max. pos. speed	17	C00273 Moment of inertia	25	C00074/2 SLVC: Ti torque controller
3	C00830/22 Speed setpoint	18	C00022 Imax in motor mode	26	C00084 Motor stator resistance
4	C00105 Decel. time - quick stop	19	C00023 Imax in generator mode	27	C00085 Motor stator leakage inductance
5	C00074/2 SLVC: Ti torque controller	20	C00074/2 SLVC: Ti torque controller	28	C00092 Motor magnetising inductance
6	C00074/2 SLVC: Ti torque controller	21	C00833/69 MCTRL: bSpeedCtrlIPAdaptOn	29	C00830/88 MCTRL: nSpeedHighLimit_a
7	C00071/1 SLVC: Ti speed controller	22	C00074/2 SLVC: Ti torque controller	30	C00830/23 MCTRL: nSpeedLowLimit_a
8	C00070/1 SLVC: Vp speed controller	23	C00074/2 SLVC: Ti torque controller	31	C00910/1 Max. pos. output frequency
9	C00830/28 Limitation of torque in generator mode			32	C00910/2 Max. neg. output frequency
10	C00830/29 Limitation of torque in motor mode			33	C00051 Actual speed value
11	C00830/24 MCTRL: nSpeedCtrlI_a			34	C00058 Output frequency
12	C00833/31 MCTRL: bSpeedCtrlIOn			35	C00018 Switching frequency
13	C00830/25 MCTRL: nSpeedCtrlIPAdapt_a			36	C00830/32 MCTRL: nPWMAngleOffset_a
14	C00833/69 MCTRL: bSpeedCtrlIPAdaptOn			37	C00830/31 MCTRL: nVoltageAdd_a
15	C00985 SLVC: Field current controller gain			38	C00052 Motor voltage

5.7.2 Types of control

The sensorless vector control can be operated in two different modes:

- [Speed control with torque limitation](#) (*bTorquemodeOn* = FALSE)
- [Torque control with speed limitation](#) (*bTorquemodeOn* = TRUE)

5.7.2.1 Speed control with torque limitation

When *bTorquemodeOn* = FALSE, the drive system is operated with a selected speed setpoint in a speed-controlled manner.



Note!

From version 13.00.00, the torque setpoint *nSpeedSetValue_a* is set to 0 by quick stop (QSP) device-internally and the torque limit values *nTorqueMotLimit_a* and *nTorqueGenLimit_a* are set to 100 % to stop the drive quickly and safely anytime. The previous behaviour can be set in [C2865/1](#) via bit 12 and bit 13.

The operational performance can be adapted in the following ways:

- Overload limitation in the drive train
- Motor current limitation
- Slip compensation

Overload limitation in the drive train

The torque is limited via the torque setpoint.

- The torque setpoint is identical to the value at the output of the speed controller, *nOutputSpeedCtrl*.
- To avoid overload in the drive train, the torque in motor mode can be limited via the *nTorqueMotLimit_a* process input signal, and the torque in generator mode can be limited via the *nTorqueGenLimit_a* process input signal:

Identifier <small>DIS code data type</small>	Information/possible settings
<i>nTorqueMotLimit_a</i> C00830/29 INT	Torque limitation in motor mode <ul style="list-style-type: none"> • Scaling: 16384 \equiv 100 % M_{\max} (C00057) • Setting range: 0 ... +199.99 % • If keypad control is performed: Parameterisable via C00728/1.
<i>nTorqueGenLimit_a</i> C00830/28 INT	Torque limitation in generator mode <ul style="list-style-type: none"> • Scaling: 16384 \equiv 100 % M_{\max} (C00057) • Setting range: -199.99 ... 0 % • If keypad control is performed: Parameterisable via C00728/2.



Note!

To avoid instabilities during operation, the torque limit values are internally processed as absolute values.

Motor current limitation

A cross current setpoint is calculated from the torque setpoint which is limited depending on the magnetising current, the max. current in motor mode ([C00022](#)) and the max. current in generator mode ([C00023](#)). The total current injected into the motor does not exceed the max. currents in motor mode and in generator mode.

Slip compensation

The slip of the machine is reconstructed using the slip model. An influencing parameter is the slip constant ([C00021](#)). ▶ [Slip compensation](#) (p. 271)

5.7.2.2 Torque control with speed limitation

When *bTorquemodeOn* = TRUE, a torque-controlled operation is activated. The setpoint torque directly follows the default value *nTorqueSetValue_a*.

Due to its speed limitation, the torque-controlled drive can only rotate within a speed range whose positive speed is limited by *nSpeedHighLimit_a* and whose negative speed is limited by *nSpeedLowLimit_a*.

**Note!**

- Absolute speed limitation to speed 0 min⁻¹ (*nSpeedLowLimit_a* or *nSpeedHighLimit_a* = 0) is only possible [from version 12.00.00](#).
- Quick stop (QSP) is used to switch over to [Speed control with torque limitation](#).
 - [From version 13.00.00](#), the torque setpoint *nSpeedSetValue_a* is set to 0 by quick stop (QSP) device-internally and the two torque limit values *nTorqueMotLimit_a* and *nTorqueGenLimit_a* are set to 100 % to stop the drive quickly and safely anytime. The previous behaviour can be set in [C2865/1](#) via bit 12 and bit 13.
- [From version 13.00.00](#), the *bLimSpeedTorquemodeOn* status signal is used to show that the speed limitation is active.
- The speed is defined by the process.
- The torque setpoint is calculated directly from *nTorqueSetValue_a*.
 - [From version 12.00.00 onwards](#), the torque limitation is active via *nTorqueMotLimit_a* and *nTorqueGenLimit_a* in this control mode, too, for the torque setpoint to be limited. The torque limitation can be deactivated in [C2865/1](#) via bit 0 to obtain the previous function.

Identifier DIS code data type	Information/possible settings
<i>nTorqueSetValue_a</i> C00830/27 INT	Torque setpoint / additive torque <ul style="list-style-type: none"> • Scaling: 16384 ≡ 100 % M_{max} (C00057)
<i>nSpeedHighLimit_a</i> C00830/88 INT	Upper speed limit for the speed limitation <ul style="list-style-type: none"> • During torque-controlled operation only (<i>bTorquemodeOn</i> = TRUE) • Scaling: 16384 ≡ 100 % rated speed (C00011)
<i>nSpeedLowLimit_a</i> C00830/23 INT	Lower speed limit for speed limitation <ul style="list-style-type: none"> • During torque-controlled operation only (<i>bTorquemodeOn</i> = TRUE) • Scaling: 16384 ≡ 100 % rated speed (C00011)

Identifier DIS code data type	Information/possible settings
nTorqueMotLimit_a C00830/29 INT	Torque limitation in motor mode <ul style="list-style-type: none"> • Scaling: $16384 \equiv 100\% M_{\max}$ (C00057) • Setting range: 0 ... +199.99 % • If keypad control is performed: Parameterisable via C00728/1.
nTorqueGenLimit_a C00830/28 INT	Torque limitation in generator mode <ul style="list-style-type: none"> • Scaling: $16384 \equiv 100\% M_{\max}$ (C00057) • Setting range: -199.99 ... 0 % • If keypad control is performed: Parameterisable via C00728/2.

5.7.3

Basic settings

The following "Initial commissioning steps" must be performed to commission the sensorless vector control:

Initial commissioning steps			
1.	Determine the motor control: C00006 = "4: SLVC: Vector control"		
2.	Set the motor selection/motor data <ul style="list-style-type: none"> • When selecting and parameterising the motor, the motor nameplate data and the equivalent circuit diagram data are relevant. Detailed information can be found in the "Motor selection/Motor data" chapter. (□ 135) Depending on the motor manufacturer, proceed as follows: <table border="1" data-bbox="379 1032 1442 1279"> <tr> <td> Lenze motor: Selecting a motor from the motor catalogue in the »Engineer« - or - 1. Set the motor nameplate data 2. Automatic motor data identification </td><td> Third party manufacturer's motor: 1. Set the motor nameplate data 2. Automatic motor data identification or set known equivalent circuit diagram data manually: C00082: Motor rotor resistance C00084: Motor stator resistance C00085: Motor stator leakage inductance C00092: Motor magnetising inductance C00095: Motor magnetising current </td></tr> </table>	Lenze motor: Selecting a motor from the motor catalogue in the »Engineer« - or - 1. Set the motor nameplate data 2. Automatic motor data identification	Third party manufacturer's motor: 1. Set the motor nameplate data 2. Automatic motor data identification or set known equivalent circuit diagram data manually: C00082 : Motor rotor resistance C00084 : Motor stator resistance C00085 : Motor stator leakage inductance C00092 : Motor magnetising inductance C00095 : Motor magnetising current
Lenze motor: Selecting a motor from the motor catalogue in the »Engineer« - or - 1. Set the motor nameplate data 2. Automatic motor data identification	Third party manufacturer's motor: 1. Set the motor nameplate data 2. Automatic motor data identification or set known equivalent circuit diagram data manually: C00082 : Motor rotor resistance C00084 : Motor stator resistance C00085 : Motor stator leakage inductance C00092 : Motor magnetising inductance C00095 : Motor magnetising current		
3.	Define the type of control: <i>bTorquemodeOn</i> = FALSE: Speed control with torque limitation <i>bTorquemodeOn</i> = TRUE: Torque control with speed limitation		
4.	Set the slip compensation (C00021). ▶ Slip compensation (□ 271)		

**Tip!**

Information on the optimisation of the control mode and the adaptation to the real application is provided in chapter "[Optimising the control mode](#)". ([□ 199](#))

We recommend to use the flying restart function for connecting/synchronising the inverter to an already rotating drive system. ▶ [Flying restart function](#) ([□ 264](#))

Parameterisable additional functions are described correspondingly in the chapter "[Parameterisable additional functions](#)". ([□ 256](#))

5.7.4 Optimising the control mode



Note!

From version 12.00.00:

- Following successful motor parameter identification, the current controller parameters ([C00075](#), [C00076](#)) are calculated automatically.
 - If these parameters are not to be calculated, bit 4 of [C02865/1](#) must be set to "1".
- Following successful motor parameter identification, the speed controller parameters ([C00070/1](#), [C00071/1](#)) can be calculated automatically.
 - If these parameters are to be calculated, bit 6 of [C02865/1](#) must be set to "5".
- Following successful motor parameter identification, other controller parameters ([C00011](#), [C00022](#)) can be calculated automatically.
 - If these parameters are to be calculated, bit 6 of [C02865/1](#) must be set to "6".

5.7.4.1 Optimising the starting performance after a controller enable

After the controller has been enabled, the starting action of the motor is delayed due to the magnetisation of the motor. Under consideration of the motor rotor time constant ([C00083](#)), the time delay is calculated as follows:

$$\text{Magnetisation} = 1.5 * \text{motor rotor time constant}$$

If this delay cannot be tolerated for specific applications, the motor must always be operated in an energised condition. For this, select one of the following options:

Procedure without setting a controller inhibit

1. Deactivate the auto DCB function with [C00019](#) = 0.
2. Do not activate the controller inhibit. Instead, stop the drive by selecting a setpoint of 0 or by activating the quick stop function.

Procedure with setting a controller inhibit due to application requirements

1. Deactivate the auto DCB function with [C00019](#) = 0.
2. Enter a greater value for the motor rotor resistance (max. factor 2!) to reduce the magnetisation time in [C00082](#).



Note!

During the starting action, a jerk may occur in the machine due to the temporarily increased motor current!

5.7.4.2 Optimise speed controller

The speed controller is designed as a PI controller.

- In the Lenze setting, the configuration of the speed controller provides robustness and moderate dynamics.

Parameter	Info	Lenze setting	
		Value	Unit
C00070/1	SLVC: Vp speed controller	15.00	
C00071/1	SLVC: Ti speed controller	100.0	ms

Speed controller gain Vp

The gain Vp ([C00070/1](#)) of the speed controller is defined in a scaled representation which enables a comparable parameterisation almost independent of the power of the motor or inverter. Here, the speed input difference of the controller is scaled to the rated motor speed whereas the output torque refers to the rated motor torque. A gain of 10 means that a speed difference of 1 % is gained through the P component with 10 % torque.

If the rated data of the motor and the mass inertia of the drive system are known, we recommend the following setting:

$$V_p \approx 1.5 \dots 3 \cdot \frac{T_M[s]}{0.01[s]}$$

$$T_M[s] = \frac{2 \cdot \pi \cdot n_N[\text{rpm}]}{M_N[\text{Nm}] \cdot 60} \cdot J_{\text{Drive, total}}[\text{kgm}^2]$$

$$M_N[\text{Nm}] = \frac{P_N[\text{W}] \cdot 60}{2 \cdot \pi \cdot n_N[\text{rpm}]}$$

V_p = Gain of the speed controller ([C00070/1](#))
 T_M = Time constant for the acceleration of the motor
 M_N = Rated motor torque
 n_N = Rated motor speed
 $J_{\text{drive, total}}$ = Total moment of inertia of the drive

[5-10] Recommendation for the setting of the gain of the speed controller



Tip!

Values recommended by Lenze for the setting of the (proportional) gain:

- For drive systems without feedback: $V_p = 6 \dots 25$
- For drive systems with a good disturbance behaviour: $V_p > 15$
In this case, we recommend the optimisation of the dynamic performance of the torque controller.

Speed controller reset time T_i

Apart from setting the P component, [C00071/1](#) provides the possibility to take influence on the I component of the PI controller.

**Tip!**

Value range recommended by Lenze for the setting of the reset time:

$T_i = 20 \text{ ms} \dots 150 \text{ ms}$

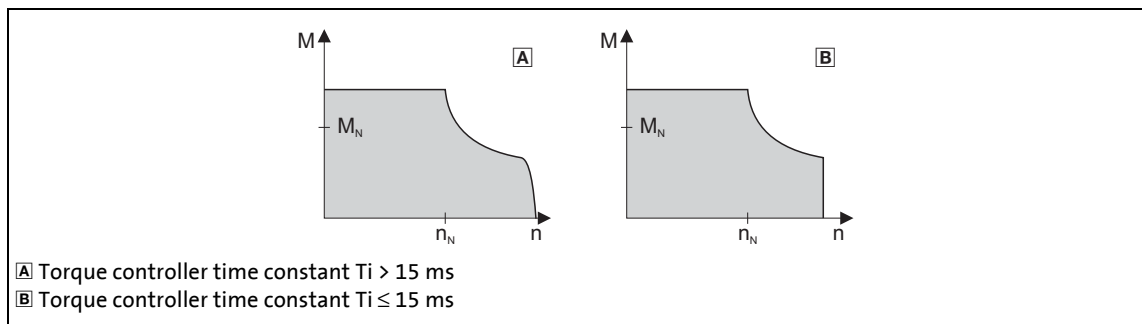
5.7.4.3 Optimising dynamic performance and field weakening behaviour

In the Lenze setting, the torque controller has been preset in such a way that robust and stable operation with a moderate dynamic response is enabled over the entire speed range. Retrospective optimisation of the controller parameters is not necessary.

Parameter	Info	Lenze setting	
		Value	Unit
C00073/2	SLVC: V_p torque controller	1.25	
C00074/2	SLVC: T_i torque controller	30	ms

A greater dynamic performance of the sensorless vector control can be achieved by reducing time constant T_i of the speed controller ([C00074/2](#)).

A greater dynamic performance of the field weakening function can be achieved by setting a time constant $\leq 15 \text{ ms}$. This means for actual speeds above rated speed a better torque-speed-characteristic in the field weakening range:



[5-11] Speed / torque characteristic diagram in the field weakening range

- For $T_i > 15 \text{ ms}$ (see **A**), the actual speed value slightly drops in the field weakening range if the load torque increases in the motor mode.
- For $T_i \leq 15 \text{ ms}$ (see **B**), the speed remains stable in the field weakening range if the torque is within the M/n characteristic field highlighted in grey.

**Tip!**

For applications with high dynamic performance and speed/torque accuracy requirements in the field weakening range, we recommend a time constant $T_i \leq 15 \text{ ms}$.

In this case, the maximum torque should be limited via the $nTorqueMotLimit_a$ and $nTorqueGenLimit_a$ process input signals to $1.5 \times M_N$ to ensure stable operation in the field weakening range.

5.7.4.4 Optimising the stalling behaviour

Motor stalling due to a torque overload in the field weakening range is prevented in sensorless vector control by means of an inverter-internal stalling current monitoring. In the field weakening range, hence at frequencies above the base frequency, it reduces the maximum current to prevent the motor from stalling. The reduction depends on the current field frequency, the base frequency, the DC-bus voltage and the maximum current ([C00022](#)). Generally it applies that a higher field frequency causes a stronger limitation of the maximum current.

The field weakening behaviour of the sensorless vector control depends on the setting of the reset time T_i of the torque controller ([C00074/2](#)).

The following applies to the reset time T_i ([C00074/2](#)) > 15 ms:

The behaviour in the field weakening range can be adapted via the override point of field weakening ([C00080](#)). This parameter serves to shift the frequency-dependent maximum current characteristic:

- [C00080](#) > 0 Hz:
 - The maximum current characteristic is shifted by the entered frequency to higher field frequencies.
 - The maximally permissible current and the maximum torque increase in the field weakening range.
 - The risk of motor stalling increases.
- [C00080](#) < 0 Hz:
 - The maximum current characteristic is shifted by the entered frequency to lower field frequencies.
 - The maximally permissible current and the maximum torque are reduced in the field weakening range.
 - The risk of motor stalling is reduced.



Note!

We recommend to keep the Lenze setting (0 Hz).

The following applies to the reset time T_i ([C00074/2](#)) ≤ 15 ms:

The reduction of the magnetising current in the field weakening range can be adapted via the override point of field weakening ([C00080](#)):

- [C00080](#) > 0 Hz:

The reduction of the magnetising current is shifted to higher field frequencies. Here, there is a risk of the motor being magnetised too much and having too little voltage reserve for the torque-creating current.
- [C00080](#) < 0 Hz:

The reduction of the magnetising current is shifted to lower field frequencies.



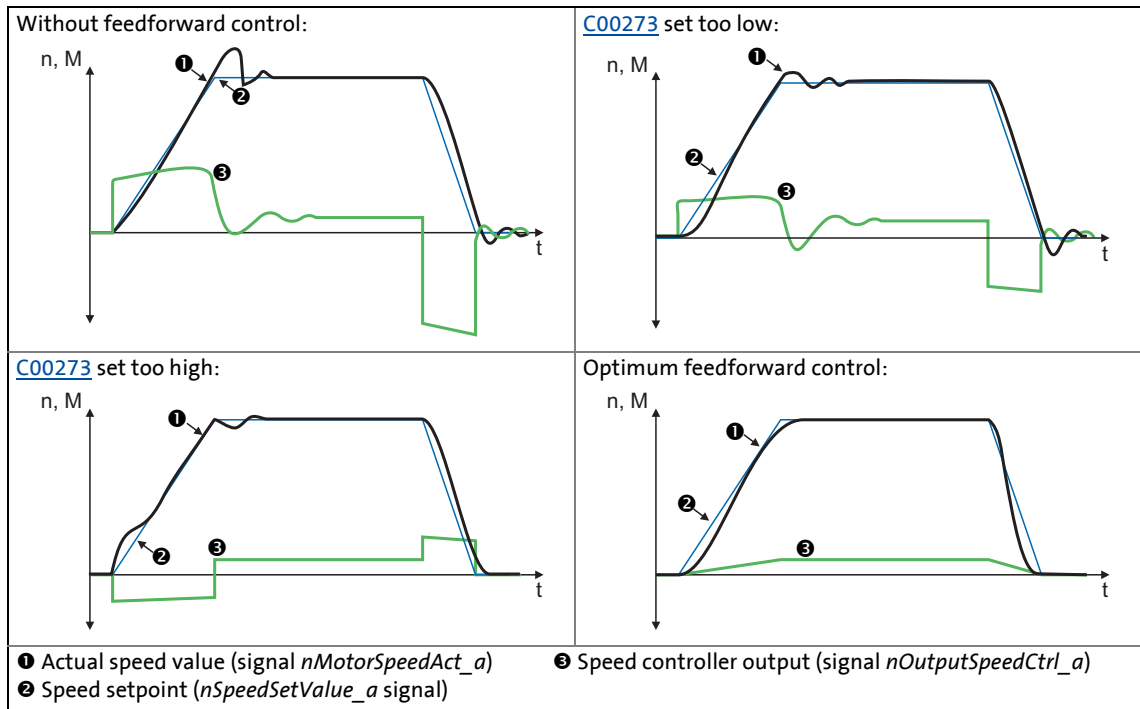
Note!

A function for enabling a stable operation can only be implemented to a limited extent with a reset time T_i ≤ 15 ms. For applications with speeds above the 2-fold rated speed, we recommend a reset time T_i ([C00074/2](#)) > 15 ms.

5.7.4.5 Optimise response to setpoint changes and determine mass inertia

Optimisation at constant mass inertia

Setting the total moment of inertia under [C00273](#) provides the optimum torque feedforward control. Depending on the application, an adjustment of the setting under [C00273](#) may be necessary to optimise the response to position/speed setpoint changes by means of the torque feedforward control.



[5-12] Typical signal characteristics for different settings of the load moment of inertia



How to optimise the torque feedforward control:

- Run a typical speed profile and record the inputs and outputs of the speed controller with the data logger.
 - Motor control variables to be recorded:
 - nSpeedSetValue_a* (speed setpoint)
 - nMotorSpeedAct_a* (actual speed value)
 - nOutputSpeedCtrl_a* (speed controller output)
- Estimate the moment of inertia and set it in [C00273](#) in relation to the motor end (i.e. with account being taken of the gearbox factors).
- Repeat the data logger recording (see step 1).

Now the data logger should show that part of the required torque is generated by the feedforward control and the speed controller output signal (*nOutputSpeedCtrl_a*) is correspondingly smaller. The resulting following error decreases.
- Change the setting in [C00273](#) and repeat the data logger recording until the intended response to setpoint changes is reached.
 - The optimisation could aim at the speed controller being completely relieved (see signal characteristics in Fig. [\[5-12\]](#)).
- Save the parameter set (device command: [C00002/11](#)).

Optimisation at variable mass inertia

From version V12.00.00, mass inertia that changes during the process (e.g. a reel) can be taken into account when optimising the response to setpoint changes.

How to proceed:

1. In [C00273](#) the known constant total moment of inertia (motor, gearbox, shaft, etc.) must be set or determined according to previous instructions ("[How to optimise ...](#)").
 - The determination requires travelling the typical speed profile without variable mass inertia (e.g. reels).
2. At the [LS_MotorInterface](#) SB, the *nInertiaAdapt_a* process signal must be interconnected in a way which ensures that a value of "100 %" is applied at this input.
3. In [C00919/1](#) set the known maximum value of the variable moment of inertia or determine the value according to previous instructions ("[How to optimise ...](#)").
 - The determination requires travelling the typical speed profile including variable mass inertia (e.g. maximum reels).
4. The *nInertiaAdapt_a* process signal can be used during the process to dynamically control the percentage of the variable moment of inertia set in [C00919/1](#) which is to be considered for setpoint feedforward control.

Example:

- If there is no variable moment of inertia (e.g. no reel), the *nInertiaAdapt_a* process signal must be set to "0 %".
- If the maximally variable moment of inertia is available (e.g. maximum reels), the *nInertiaAdapt_a* process signal must be set to "100 %".



Tip!

Via the *nTorqueSetValue_a* process signal at the [LS_MotorInterface](#) SB, any differential signal can be defined for torque feedforward control. First the speed controller, then this additive torque is connected which is hence not derived from the differential change in speed setpoint.

Other functions for differential setpoint feedforward control

From version V12.00.00 onwards, the following additional functions are available for differential setpoint feedforward control (torque feedforward control):

- In [C00653/1](#), the sensitivity of setpoint feedforward control can be adapted.
- In [C00654/1](#), alternatively to the *nSpeedSetValue_a* process signal, the new *nSpeedSetValueInertia_a* process signal for the setpoint feedforward control can be selected at the [LS_MotorInterface](#) SB. Via the *nSpeedSetValueInertia_a* process signal, an optional input value (e.g. setpoint of the position or process controller) for the torque feedforward control can be specified.
- For *bTorqueModeOn* = TRUE, the setpoint feedforward control is added to the torque setpoint *nTorqueSetValue_a*. In this way, feedforward control of torque is also possible for torque-controlled operation (e.g. for winder applications).



Stop!

In the Lenze setting of [C00654/1](#), the speed setpoint of the speed controller (*nSpeedSetValue_a*) is used for the torque feedforward control which is why it is also called "differential setpoint feedforward control". A very sharp change of the speed setpoint at the speed controller thus causes a strong torque impulse at the machine!

A very sharp change of the speed setpoint of the speed controller occurs if a control creates the setpoint ramp itself and the speed setpoint is only written every 20 ms to the drive. (In this case, the speed setpoint is changed every 20 ms.)

Deactivate the speed feedforward control for the speed setpoint in [C00654/1](#) if the speed setpoint changes very sharply or the mass inertia is unknown (e.g. in case of hoists)!

5.7.4.6 Slip calculation from motor equivalent circuit diagram data

This function extension is available from version 02.00.00!

In order to achieve a better speed stability and torque accuracy, the slip calculation can be either derived from the motor nameplate data (e.g. rated motor speed) or the motor equivalent circuit diagram data (stator resistance, rotor resistance etc.).

The data to be used for sensorless vector control is selected via bit 0 in [C02879/1](#):

Setting		Info
Bit 0	SLVC	In case of sensorless vector control: <ul style="list-style-type: none"> • "0" ≡ Slip calculation from motor nameplate data (Lenze setting) • "1" ≡ Slip calculation from motor equivalent circuit diagram data
Bit 1	SC_ASM	In case of servo control for asynchronous motors: <ul style="list-style-type: none"> • "0" ≡ Slip calculation from motor nameplate data • "1" ≡ Slip calculation from motor equivalent circuit diagram data (Lenze setting)
Bit 2 ... 7	Reserved	



Note!

In order that the slip can be calculated from the motor equivalent circuit diagram data, the equivalent circuit data (stator resistance, rotor resistance etc.) must be known as exactly as possible.

- Selecting a motor in the »Engineer« motor catalogue loads the exact motor equivalent circuit diagram data.
- When the motor nameplate data is entered manually and the motor equivalent circuit diagram data is then detected via the motor parameter identification, the "extended identification" ([C02867/1](#) = 2) must be used. ▶ [Automatic motor data identification](#) (141)

In the slip calculation from the motor equivalent circuit diagram data, the slip compensation ([C00021](#)) has no influence anymore.

5.7.4.7 Optimising field feedforward control and torque feedforward control

At the start of an acceleration process and at the end of a deceleration process, the field current (*nReaktCurrentId_a*) may oscillate.

- Especially when accelerating via small acceleration ramps, these oscillations become obvious by the speed being unable to follow the setpoint or speed drops during acceleration.
- Oscillating can be reduced by increasing the gain of the field current controller in [C00985](#). A small increase of the cross current controller gain in [C00986](#) can further improve the starting performance for small acceleration ramps.

In the field weakening range, the cross current (*nEffCurrentIq_a*) may oscillate when an acceleration process starts or a deceleration process ends.

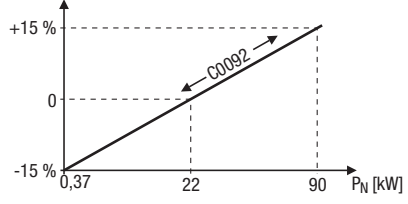
- In case of some motors, this cross current oscillation (*nEffCurrentIq_a*) can also occur in the motor setting range/field weakening range transitions which may also cause an overcurrent interruption.
- These oscillations can be reduced by again increasing the cross current controller gain slightly in [C00986](#).



Note!

The setting of [C00985](#) and [C00986](#) reduces the torque setting range.

5.7.5 Remedies for undesired drive behaviour

Drive behaviour	Remedy
Deviation between no-load current and magnetising current or bad speed or torque accuracy.	<p>Adapt the motor magnetising inductance (C00092) for no-load operation.</p> <ul style="list-style-type: none"> If the no-load current is greater than the magnetising current (C00095) at 0.5-fold rated motor speed, the magnetising inductance must be reduced until the no-load current and the magnetising current have the same values. Otherwise, the magnetising inductance must be increased. <p>Tendency of the correction of C00092:</p>  <p>PN: Rated motor power</p>
Insufficient speed constancy at high load: Setpoint and motor speed are not proportional anymore. Caution: Overcompensation of the settings mentioned under "Remedy" may result in unstable behaviour!	<p>Via the slip compensation (C00021), the speed stability under high loads can be affected:</p> <ul style="list-style-type: none"> If $n_{act} > n_{slip}$, reduce the value in C00021 If $n_{act} < n_{slip}$, increase the value in C00021
Unstable control with higher speeds.	<ul style="list-style-type: none"> Check the setting of the magnetising inductance (C00092) by comparing the current consumption in no-load operation with the rated magnetising current (C00095). Optimise oscillation damping (C00234).
"Short circuit" (oC1) or "Clamp operation active" (oC11) error messages at short acceleration time (C00012) in proportion to the load (controller cannot follow the dynamic processes).	<ul style="list-style-type: none"> Increase the gain of the torque controller (C00073/2). Reduce the reset time of the torque controller (C00074/2). Increase the acceleration (C00012)/deceleration (C00013) time.
Mechanical resonance at certain speeds.	The L_NSet_1 function block masks out those speed ranges that include resonance.
Speed variations in no-load operation for speeds > 1/3 rated speed.	Minimise speed oscillations with oscillation damping (C00234).
Drive runs unstable.	<p>Check set motor data (nameplate data and equivalent circuit diagram data).</p> <p>► Motor selection/Motor data (135)</p> <p>Increase motor magnetising current (C00095).</p>
Setpoint speed and actual speed differ strongly.	
The torque required is not generated at standstill.	
Current overshoots occur when heavy loads are accelerated from standstill (OC1 or OC11 error).	
The machine runs uneven.	

5.8 Sensorless control for synchronous motors (SLPSM)

The sensorless control for synchronous motors is based on a decoupled and separated control of the torque-creating and field-creating current share of synchronous motors. In contrast to the servo control, the actual speed value and the rotor position are reconstructed via a motor model.



Stop!

- The sensorless control for synchronous motors is only possible up to a maximum output frequency of 650 Hz (from version 14.00.00: 1000 Hz)!
 - Depending on the number of motor pole pairs, the reference speed ([C00011](#)) may only be selected that high that the output frequency displayed in [C00059](#) is less than or equal to 650 Hz (from version 14.00.00: 1000 Hz).
- We recommend to select a power-adapted combination of inverter and motor.
- The Lenze setting permits the operation of a power-adapted motor. Optimal operation is only possible if either:
 - the motor is selected via the »Engineer« motor catalogue,
 - the motor nameplate data are entered and motor parameter identification is carried out afterwards
 - or -
 - the nameplate data and equivalent circuit data of the motor (motor leakage inductance and motor stator resistance) are entered manually.
- When you enter the motor nameplate data, take into account the phase connection implemented for the motor (star or delta connection). Only enter the data applying to the selected connection type.
- In order to protect the motor (e.g. from demagnetisation), we recommend setting the ultimate motor current in [C00939](#). This ensures motor protection even with an unstable operation. ▶ [Maximum current monitoring](#) (□ 303)
- Controller enable is only possible if the motor is at standstill.
 - When the controller is enabled, a jerk may occur due to an angle jump since the rotor displacement angle is not known after controller enable. For some applications, this jerk in the machine is not acceptable.
 - From version 02.00.00, the rotor displacement angle is identified with every controller enable in the Lenze setting, and thus a jerk in the machine after controller enable can be avoided. ▶ [Pole position identification without motion](#) (□ 364)
 - A flying restart circuit for synchronising to rotating motors is in preparation.
- The injection of a constant current may cause an unwanted heating of the motor at controlled operation.
 - We recommend the use of a temperature feedback via KTY, PTC or thermal contact.
 - ▶ [Motor temperature monitoring \(KTY\)](#) (□ 373)
 - ▶ [Motor temperature monitoring \(PTC\)](#) (□ 297)

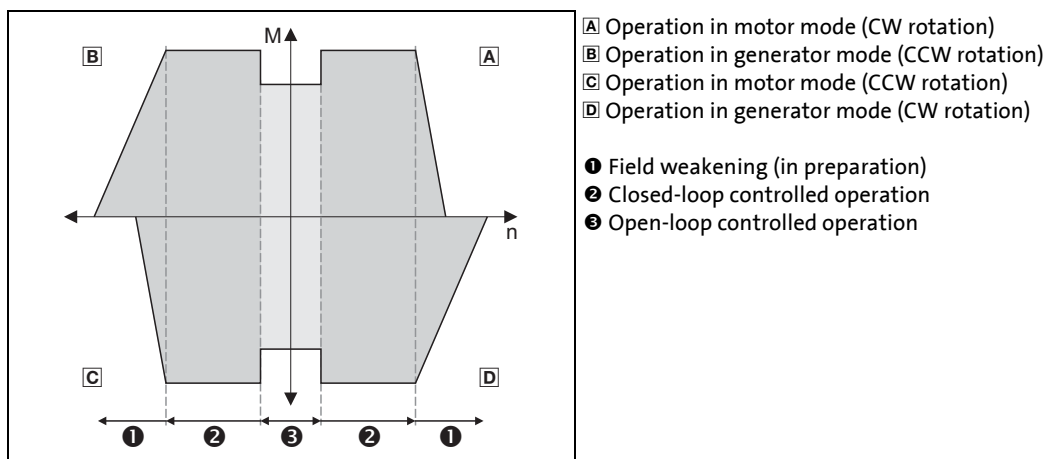
**Note!**

Currently, the sensorless control does not contain a flying restart function that enables a synchronisation of the controller to a rotating machine.

- Thus, we recommend taking measures for preventing overvoltages at operation in generator mode (e.g. brake resistor).
- By any means, the delay time for the "DC-bus overvoltage" error trigger in [C00601/1](#) must be set to 0 s.

The motor model-based speed monitoring requires a rotating machine. Thus, the operational performance of the sensorless control for synchronous motors is divided into two categories:

1. Open-loop controlled operation ($|n_{\text{setpoint}}| < n_{C00996}$)
 - In the range of low speeds, the speed of a synchronous motor is not possible. Thus, only an adjustable and constant current is injected that enables an acceleration.
2. Closed-loop controlled operation ($|n_{\text{setpoint}}| > n_{C00996}$)
 - In this range, the rotor flux position and the speed are reconstructed via an observer. The control is carried out field-oriented. Only the current is injected that is needed for the required torque.



[5-13] Operating ranges of the sensorless control for synchronous motors

The sensorless control for synchronous motors has similar advantages for the closed-loop controlled operating range and the servo control (SC) for synchronous motors. Compared to asynchronous motors, there are the following advantages:

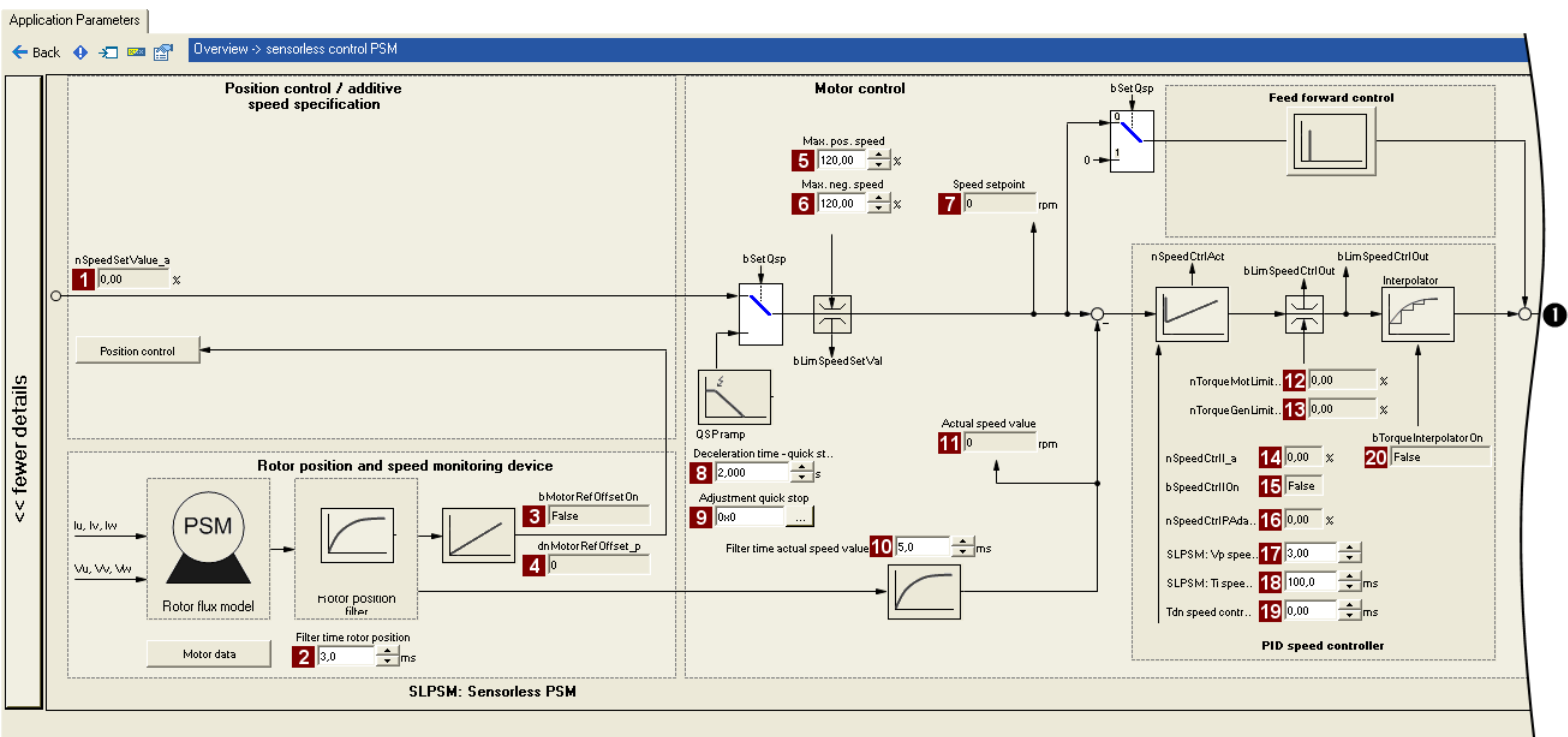
- Higher power density of the motor
- Higher efficiency
- Limitation of the maximum torque in motor mode and generator mode in closed-loop operating range
- Implementation of simple positioning

5.8.1 Parameterisation dialog/signal flow



Proceed as follows to open the dialog for parameterising the motor control:

1. »Engineer« Go to the *Project view* and select the 8400 TopLine controller.
2. Select the **Application parameters** tab from the *Workspace*.
3. Select the motor control "3: SLPSM: Sensorless PSM" from the *Overview* dialog level in the **Motor control** list field:
4. Click the **Motor control servo SLPSM** button to change to the *Overview → Motor control vector* dialog box.
 - This dialog level only shows a simplified signal flow with the most important parameters.
 - When you click the **>>More details** button in the left-most position, a signal flow with more details/parameters is displayed.



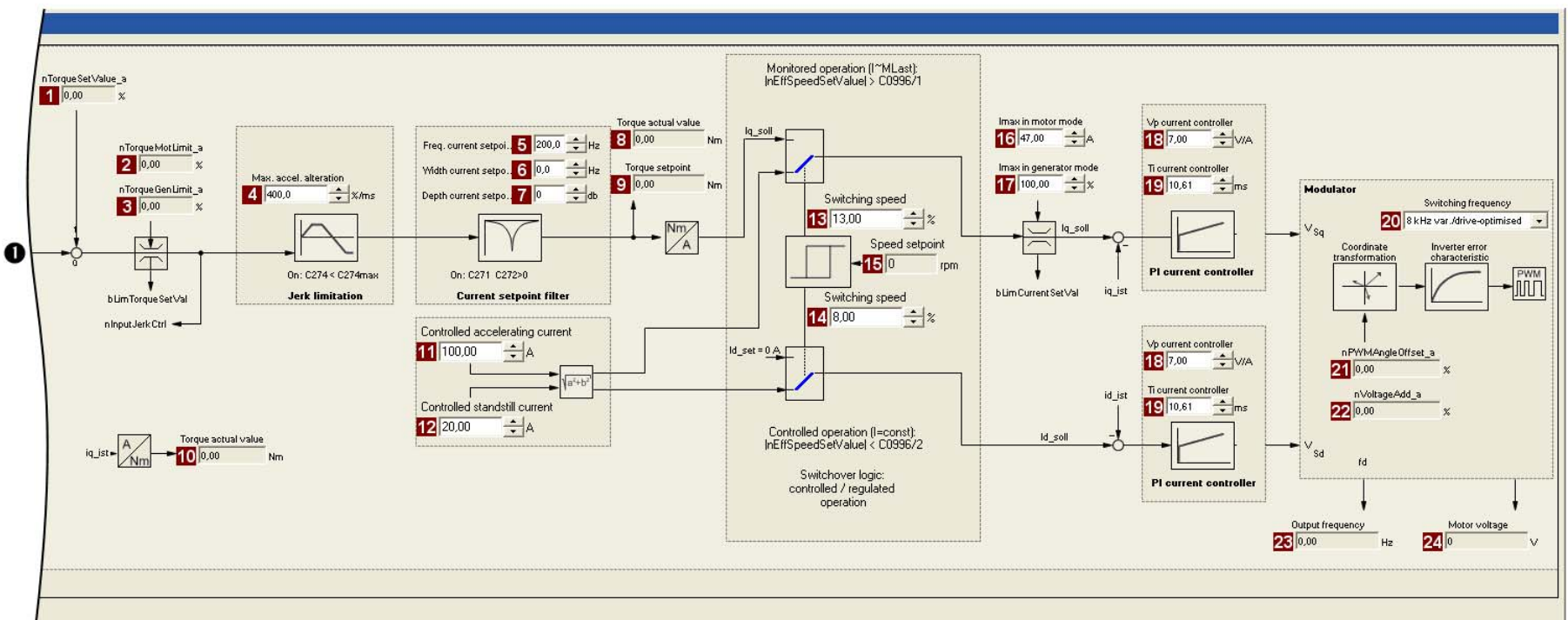
Parameter	Info	Parameter	Info	Parameter	Info
1	C00830/22 Speed setpoint	5	C00909/1 Max. pos. speed	12	C00830/29 Limitation of torque in motor mode
2	C00998/1 SLPSM: Filter time rotor position	6	C00909/2 Max. neg. speed	13	C00830/28 Limitation of torque in generator mode
3	C00833/68 MCTRL: bMotorRefOffsetOn	7	C00050 Speed setpoint	14	C00830/24 MCTRL: nSpeedCtrlI_a
4	C00834/6 MCTRL: dnMotorRefOffset_p	8	C00105 Decel. time - quick stop	15	C00833/31 MCTRL: bSpeedCtrlIOn
		9	C00104/1 Quick stop setting	16	C00830/25 MCTRL: nSpeedCtrlPAdapt_a
		10	C00998/2 SLPSM: Filter time actual speed value	17	C00070/3 SLPSM: Vp speed controller
		11	C00051 Actual speed value	18	C00071/3 SLPSM: Ti speed controller
				19	C00072 SC: Tdn speed controller
				20	C00833/29 MCTRL: bTorqueInterpolatorOn

5

Motor control (MCTRL)

5.8

Sensorless control for synchronous motors (SLPSPM)



Parameter	Info	Parameter	Info	Parameter	Info
1	C00830/27	MCTRL: nTorqueSetValue_a	11	C00995/1	SLPSM: Open-loop controlled accelerating current
2	C00830/29	Limitation of torque in motor mode	12	C00995/2	SLPSM: Open-loop controlled standstill current
3	C00830/28	Limitation of torque in generator mode	13	C00996/1	SLPSM: Closed-loop controlled switching speed
4	C00274	SC: Max. change in acceleration	14	C00996/2	SLPSM: Open-loop controlled switching speed
5	C00270	SC: Freq. current setpoint filter	15	C00050	Speed setpoint
6	C00271	SC: Current setpoint filter width	16	C00022	I _{max} in motor mode
7	C00272	SC: Current setpoint filter depth	17	C00023	I _{max} in generator mode
8	C00056/2	Actual torque value			
9	C00056/1	Torque demand			
10	C00056/2	Actual torque value			
18	C00075	V _p current controller	21	C00830/32	MCTRL: nPWMAngleOffset_a
19	C00076	T _i current controller	22	C00830/31	MCTRL: nVoltageAdd_a
20	C00018	Switching frequency	23	C00058	Output frequency
24	C00052	Motor voltage			

5.8.2 Types of control

Sensorless control for synchronous motors can only be executed in the "Speed control with torque limitation" (*bTorquemodeOn* = FALSE) mode.

Speed control with torque limitation

A speed setpoint is selected and the drive system is operated in a speed-controlled manner. For adapting the operational performance, the overload in the drive train can be limited:

- The torque is limited via the torque setpoint.
- The torque setpoint is identical to the value at the output of the speed controller, *nOutputSpeedCtrl*.
- To avoid overload in the drive train, the torque in motor mode can be limited via the *nTorqueMotLimit_a* process input signal, and the torque in generator mode can be limited via the *nTorqueGenLimit_a* process input signal:

Identifier <small>DIS code data type</small>	Information/possible settings
<i>nTorqueMotLimit_a</i> C00830/29 INT	Torque limitation in motor mode <ul style="list-style-type: none"> • Scaling: $16384 \equiv 100\% M_{\max}$ (C00057) • Setting range: 0 ... +199.99 % • If keypad control is performed: Parameterisable via C00728/1.
<i>nTorqueGenLimit_a</i> C00830/28 INT	Torque limitation in generator mode <ul style="list-style-type: none"> • Scaling: $16384 \equiv 100\% M_{\max}$ (C00057) • Setting range: -199.99 ... 0 % • If keypad control is performed: Parameterisable via C00728/2.



Stop!

Torque limitation is only active in the closed-loop controlled operation ($|n_{\text{Setpoint}}| > n_{\text{C00996}}!$)

- It must be prevented that the actual speed value is braked into the non-observable area due to the torque limitation!



Note!

To avoid instabilities during operation, the torque limit values are internally processed as absolute values.

5.8.3 Basic settings

The following "Initial commissioning steps" must be performed to commission the sensorless control for synchronous motors:

Initial commissioning steps	
1.	Select motor control: C00006 = "3: SLPSM: Sensorless PSM"
2.	<div> Set the motor selection/motor data <ul style="list-style-type: none"> When selecting and parameterising the motor, the motor nameplate data and the equivalent circuit diagram data are relevant. Detailed information can be found in the "Motor selection/Motor data" chapter. (135) Depending on the motor manufacturer, proceed as follows: <div> <div> Lenze motor: Selecting a motor from the motor catalogue in the »Engineer« - or - 1. Set the motor nameplate data 2. Automatic motor data identification </div> <div> Third party manufacturer's motor: 1. Set the motor nameplate data 2. Automatic motor data identification or set known equivalent circuit diagram manually: C00084: Motor stator resistance C00085: Motor stator leakage inductance </div> </div> </div>
3.	Set speed switching thresholds between open-loop and closed-loop controlled operation: <ul style="list-style-type: none"> Set transition speed from closed-loop to open-loop operation in C00996/1 in [%] with regard to the rated motor speed (C00087). Set transition speed from closed-loop to open-loop operation in C00996/2 in [%] with regard to the rated motor speed (C00087). Tip! <ul style="list-style-type: none"> With voltage-adjusted motors, a speed switching threshold of 10 % is recommended. As a rule of thumb, the speed switching threshold should be selected as follows: $C00996/1...2 [\%] = \frac{U_{Rated, motor} [V]}{U_{Rated, FI} [V]} \cdot 10$
4.	Set open-loop accelerating current in C00995/1 in [%] with regard to the rated motor current (C00088). <ul style="list-style-type: none"> This value defines the height of the current that is injected during the acceleration process. The accelerating current must be dimensioned so that the required torque in the lower speed range can always be reached (acceleration torque + load torque): $C00995/1 [\%] = \frac{M_{Meax} [Nm]}{M_{Rated} [Nm]} \cdot I_{Rated, motor} [A] \cdot 1.3$
5.	Set open-loop steady-state current in C00995/2 in [%] with regard to the rated motor current (C00088). <ul style="list-style-type: none"> This value defines the height of the current for processes without acceleration (e.g. standstill or constant setpoint speed).
6.	For improving the operating characteristics: If required, adapt the filter time for reconstructing the rotor position and the actual speed value through the motor model in C00998/1 and C00998/2 . <ul style="list-style-type: none"> We recommend using the Lenze setting: <ul style="list-style-type: none"> Filter time rotor position (C00998/1) = 3 ms Filter time actual speed value (C00998/2) = 5 ms Deviant from this, the following value range can be used: <ul style="list-style-type: none"> Filter time rotor position (C00998/1) = 2 ... 5 ms Filter time actual speed value (C00998/2) = 3 ... 8 ms
7.	For protecting the motor from demagnetisation: Set the ultimate current in C00939 .



Note!

The Lenze settings of the current controller are predefined for a power-adapted motor. For an optimal drive behaviour of a synchronous motor, we recommend to adapt the controller settings.

**Tip!**

Information on the optimisation of the control mode and the adaptation to the real application is provided in the "[Optimising the control mode](#)" chapter.

Parameterisable additional functions are described correspondingly in the chapter "[Parameterisable additional functions](#)". ([book icon](#) 256)

5.8.4 Optimising the control mode

**Note!**

From version 12.00.00:

- Following successful motor parameter identification, the current controller parameters ([C00075](#), [C00076](#)) are calculated automatically.
 - If these parameters are not to be calculated, bit 4 of [C02865/1](#) must be set to "1".
- Following successful motor parameter identification, the speed controller parameters ([C00070/3](#), [C00071/3](#)) can be calculated automatically.
 - If these parameters are to be calculated, bit 6 of [C02865/1](#) must be set to "5".
- Following successful motor parameter identification, other controller parameters ([C00011](#), [C00022](#)) can be calculated automatically.
 - If these parameters are to be calculated, bit 6 of [C02865/1](#) must be set to "6".

The "optimisation steps" given in the table below serve to further optimise the control behaviour of the sensorless control for synchronous motors and adjust it to the concrete application.

- Detailed information on the individual steps can be found in the following subchapters.

Generally, the following optimisation steps are recommended:

Optimisation steps	
1.	Optimise current controller. (📖 218) <ul style="list-style-type: none"> • The current controller should always be optimised if a motor of a third-party manufacturer with unknown motor data is used!
2.	Optimise speed controller. (📖 219) <ul style="list-style-type: none"> • The setting of the speed controller must be adapted depending on the mechanical path.
3.	Optimise response to setpoint changes and determine mass inertia. (📖 222) <ul style="list-style-type: none"> • For an optimal reference behaviour, the total moment of inertia can be used to make a feedforward control of the speed setpoint.

**Note!****Current setpoint filter (band-stop filter) / jerk limitation**

The use of the functions is only recommended in exceptional cases.

The functions are described in chapter "[Servo control \(SC\)](#)":

- ▶ [Setting the current setpoint filter \(band-stop filter\)](#) ([📖 244](#))
- ▶ [Adapting the max. acceleration change \(jerk limitation\)](#) ([📖 245](#))

5.8.4.1 Optimise current controller

**Note!**

An optimisation of the current controller should generally be carried out unless a power-adapted standard motor is used or the motor has been selected from the motor catalogue of the »Engineer«!

An optimisation of the current controller is sensible since the two control parameters gain ([C00075](#)) and reset time ([C00076](#)) depend on the required maximum current and the set switching frequency.

Parameter	Info	Lenze setting	
		Value	Unit
C00075	Vp current controller	7.00	V/A
C00076	Ti current controller	10.61	ms

- Gain and reset time can be calculated as per the following formulae:

$$V_p = \frac{L_{ss}[H]}{T_E[s]}$$

$$T_i = \frac{L_{ss}[H]}{R_s[\Omega]}$$

V_p = Current controller gain ([C00075](#))

T_i = Current controller reset time ([C00076](#))

L_{ss} = Motor stator leakage inductance ([C00085](#))

R_s = Motor stator resistance ([C00084](#))

T_E = Equivalent time constant (= 500 µs)

5.8.4.2 Optimise speed controller

The speed controller is in the form of a PID controller with an additional differential speed-setpoint gain. For optimum behaviour, the PID speed controller has to be optimised and the overall mass inertia of the drive train has to be determined.

- In the Lenze setting, the configuration of the speed controller provides robustness and moderate dynamics.

Parameter	Info	Lenze setting	
		Value	Unit
C00070/3	SLPSM: Vp speed controller	3.00	
C00071/3	SLPSM: Ti speed controller	100.0	ms
C00072	SC: Tdn speed controller	0.00	ms

Speed controller gain Vp

The gain Vp ([C00070/3](#)) of the speed controller is defined in a scaled representation which enables a comparable parameterisation almost independent of the power of the motor or inverter. Here, the speed input difference of the controller is scaled to the rated motor speed whereas the output torque refers to the rated motor torque. A gain of 10 means that a speed difference of 1 % is gained through the P component with 10 % torque.

If the rated data of the motor and the mass inertia of the drive system are known, we recommend the following setting:

$$V_p \approx 0.2 \dots 0.5 \cdot \frac{T_M[s]}{0.01[s]}$$

$$T_M[s] = \frac{2 \cdot \pi \cdot n_N[\text{rpm}]}{M_N[\text{Nm}] \cdot 60} \cdot J_{\text{Drive, total}}[\text{kgm}^2]$$

$$M_N[\text{Nm}] = \frac{P_N[\text{W}] \cdot 60}{2 \cdot \pi \cdot n_N[\text{rpm}]}$$

V_p = Gain of the speed controller ([C00070/3](#))

T_M = Time constant for the acceleration of the motor

M_N = Rated motor torque

n_N = Rated motor speed

$J_{\text{drive, total}}$ = Total moment of inertia of the drive

[5-14] Recommendation for the setting of the gain of the speed controller

If the mass inertia of the drive is unknown, the optimisation can be achieved as follows:

1. Specify speed setpoint.
 - A small speed just above the switching threshold is recommended in the closed-loop controlled operation.
2. Increase V_p ([C00070/3](#)) until the drive starts to oscillate (observe engine noise).
3. Reduce V_p ([C00070/3](#)) until the drive runs stable again.
4. Reduce V_p ([C00070/3](#)) to approx. half the value.
5. Afterwards check results of the optimisation in the entire speed range (one-time passing through of the speed range).



Tip!

Values recommended by Lenze for the setting of the (proportional) gain:

- For drive systems without feedback: $V_p = 2 \dots 8$
- For drive systems with a good disturbance behaviour: $V_p > 6$

Speed controller reset time T_i

Apart from setting the P component, [C00071/3](#) provides the possibility to take influence on the I component of the PI controller.

If the mass inertia of the drive is unknown, the optimisation can be achieved as follows:

1. Specify speed setpoint.
2. Reduce T_i ([C00071/3](#)) until the drive starts to oscillate (observe engine noise).
3. Increase T_i ([C00071/3](#)) until the drive runs stable again.
4. Increase T_i ([C00071/3](#)) to approx. twice the value.



Tip!

Value range recommended by Lenze for the setting of the reset time:

$T_i = 20 \text{ ms} \dots 150 \text{ ms}$

Using the ramp response for setting the speed controller

If the mechanical components cannot be operated at the stability limit, the ramp response can also be used for setting the speed controller.



Stop!

If the controller parameters are preset unfavourably, the control can tend to heavy overshoots up to instability!

- Following and speed errors can adopt very high values.
- If the mechanics are sensitive, the corresponding monitoring functions are to be activated.

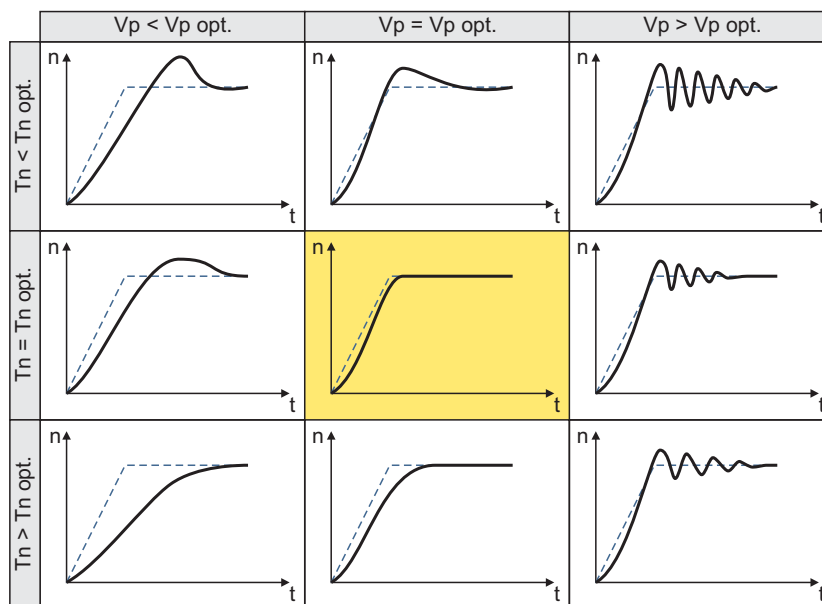
**Note!**

For an optimal setting, we recommend to determine the mass inertia (optimal response to setpoint changes) first.

► [Optimise response to setpoint changes and determine mass inertia](#) (222)

**How to optimise the speed controller setting by means of the ramp response:**

- Run a typical speed profile and record the ramp response of the speed using the data logger.
 - Motor control variables to be recorded:
nSpeedSetValue_a (speed setpoint)
nMotorSpeedAct_a (actual speed value)
- Evaluate the ramp response:



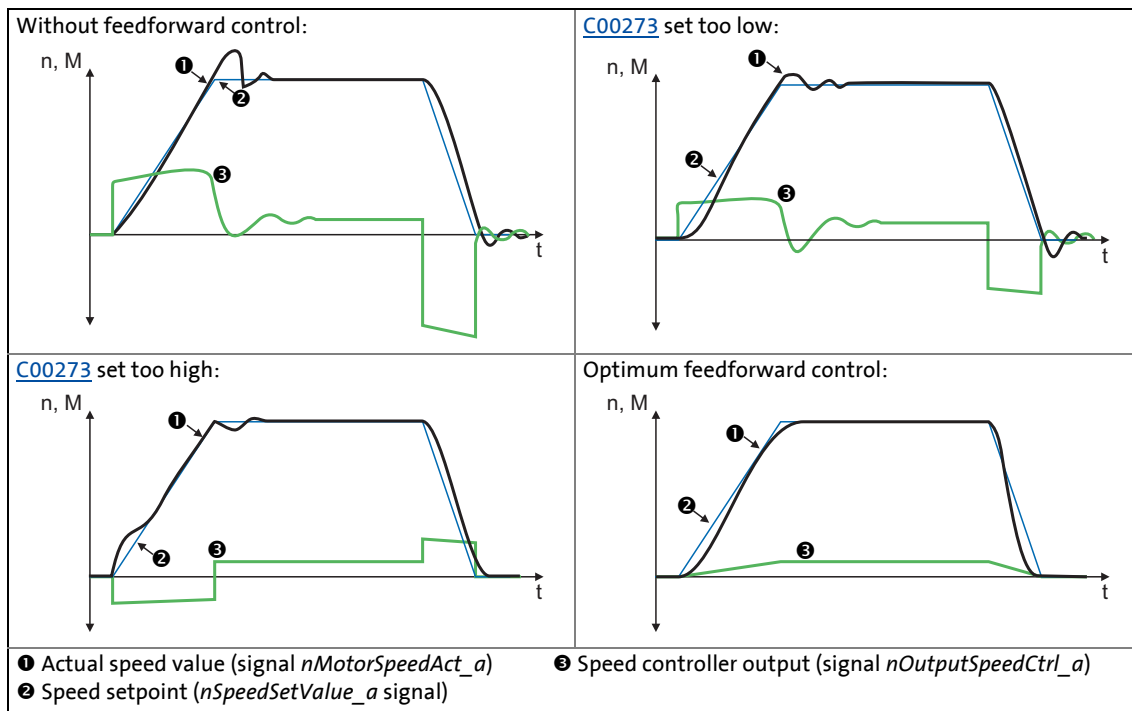
- Solid line = ramp response (actual speed value)
- Dash line = speed setpoint

- Change gain V_p in [C00070/3](#) and reset time T_n in [C00071/3](#).
- Repeat steps 1 ... 3 until the optimum ramp response is reached.

5.8.4.3 Optimise response to setpoint changes and determine mass inertia

Optimisation at constant mass inertia

Setting the total moment of inertia under [C00273](#) provides the optimum torque feedforward control. Depending on the application, an adjustment of the setting under [C00273](#) may be necessary to optimise the response to position/speed setpoint changes by means of the torque feedforward control.



[5-15] Typical signal characteristics for different settings of the load moment of inertia



How to optimise the torque feedforward control:

- Run a typical speed profile and record the inputs and outputs of the speed controller with the data logger.
 - Motor control variables to be recorded:
 - nSpeedSetValue_a* (speed setpoint)
 - nMotorSpeedAct_a* (actual speed value)
 - nOutputSpeedCtrl_a* (speed controller output)
 - Estimate the moment of inertia and set it in [C00273](#) in relation to the motor end (i.e. with account being taken of the gearbox factors).
 - Repeat the data logger recording (see step 1).
- Now the data logger should show that part of the required torque is generated by the feedforward control and the speed controller output signal (*nOutputSpeedCtrl_a*) is correspondingly smaller. The resulting following error decreases.
- Change the setting in [C00273](#) and repeat the data logger recording until the intended response to setpoint changes is reached.
 - The optimisation could aim at the speed controller being completely relieved (see signal characteristics in Fig. [5-15]).
 - Save the parameter set (device command: [C00002/11](#)).

Optimisation at variable mass inertia

From version V12.00.00, mass inertia that changes during the process (e.g. a reel) can be taken into account when optimising the response to setpoint changes.

How to proceed:

1. In [C00273](#) the known constant total moment of inertia (motor, gearbox, shaft, etc.) must be set or determined according to previous instructions ("[How to optimise ...](#)").
 - The determination requires travelling the typical speed profile without variable mass inertia (e.g. reels).
2. At the [LS_MotorInterface](#) SB, the *nInertiaAdapt_a* process signal must be interconnected in a way which ensures that a value of "100 %" is applied at this input.
3. In [C00919/1](#) set the known maximum value of the variable moment of inertia or determine the value according to previous instructions ("[How to optimise ...](#)").
 - The determination requires travelling the typical speed profile including variable mass inertia (e.g. maximum reels).
4. The *nInertiaAdapt_a* process signal can be used during the process to dynamically control the percentage of the variable moment of inertia set in [C00919/1](#) which is to be considered for setpoint feedforward control.

Example:

- If there is no variable moment of inertia (e.g. no reel), the *nInertiaAdapt_a* process signal must be set to "0 %".
- If the maximally variable moment of inertia is available (e.g. maximum reels), the *nInertiaAdapt_a* process signal must be set to "100 %".



Tip!

Via the *nTorqueSetValue_a* process signal at the [LS_MotorInterface](#) SB, any differential signal can be defined for torque feedforward control. First the speed controller, then this additive torque is connected which is hence not derived from the differential change in speed setpoint.

Other functions for differential setpoint feedforward control

From version V12.00.00 onwards, the following additional functions are available for differential setpoint feedforward control (torque feedforward control):

- In [C00653/1](#), the sensitivity of setpoint feedforward control can be adapted.
- In [C00654/1](#), alternatively to the *nSpeedSetValue_a* process signal, the new *nSpeedSetValueInertia_a* process signal for the setpoint feedforward control can be selected at the [LS_MotorInterface](#) SB. Via the *nSpeedSetValueInertia_a* process signal, an optional input value (e.g. setpoint of the position or process controller) for the torque feedforward control can be specified.
- For *bTorqueModeOn* = TRUE, the setpoint feedforward control is added to the torque setpoint *nTorqueSetValue_a*. In this way, feedforward control of torque is also possible for torque-controlled operation (e.g. for winder applications).



Stop!

In the Lenze setting of [C00654/1](#), the speed setpoint of the speed controller (*nSpeedSetValue_a*) is used for the torque feedforward control which is why it is also called "differential setpoint feedforward control". A very sharp change of the speed setpoint at the speed controller thus causes a strong torque impulse at the machine!

A very sharp change of the speed setpoint of the speed controller occurs if a control creates the setpoint ramp itself and the speed setpoint is only written every 20 ms to the drive. (In this case, the speed setpoint is changed every 20 ms.)

Deactivate the speed feedforward control for the speed setpoint in [C00654/1](#) if the speed setpoint changes very sharply or the mass inertia is unknown (e.g. in case of hoists)!

*This page has been left blank intentionally,
to present the following information more clearly.*

5.9

Servo control (SC)

Field-oriented servo control (SC) is based on a decoupled, separate control of the torque-producing and the field-producing current component. The motor control is based on a field-oriented, cascaded controller structure with feedback function and enables dynamic and stable operation in all of the four quadrants. It can be used for synchronous motors (PSM) and asynchronous motors (ASM).

**Stop!**

- Servo control requires a speed feedback!
 - The speed sensor used has to be set in [C00495](#). This setting is not made automatically with the selection of the motor from the »Engineer« motor catalogue!
 - If no speed sensor is set in [C00495](#) and the controller is enabled, an impermissibly high motor current occurs which may destroy the motor thermally!
 - **From version 14.00.00**, the error response set in [C00571/2](#) (Lenze setting: "Fault") takes place if in case of controller enable it is detected that a motor control type with feedback is set in [C00006](#) but no speed encoder is set in [C00495](#).
- We recommend to select a power-adapted combination of inverter and motor.
- The Lenze setting permits the operation of a power-adapted motor. Optimal operation is only possible if either:
 - the motor is selected via the »Engineer« motor catalogue,
 - the motor nameplate data are entered and motor parameter identification is carried out afterwards
 - or -
 - the nameplate data and equivalent circuit data of the motor are entered manually.
- When you enter the motor nameplate data, take into account the phase connection implemented for the motor (star or delta connection). Only enter the data applying to the selected connection type.

**Stop!****V/f emergency operation**

From version 15.00.00, it is internally switched to the encoderless V/f characteristic control in case of an encoder open circuit in order to avoid impermissible motor movements.

- In order that this "V/f emergency operation" works properly, the parameters relevant for the V/f characteristic control (base frequency, Vmin boost, slip compensation, etc.) have to be set correctly. As an alternative, a motor parameter identification can be executed as well.
- The change-over to "V/f emergency operation" is reported via bit 4 in [C01000](#) and via the *bWirebreakUfLinearActive* status signal at the SB [LS_DeviceMonitor](#).
- The change-over to "V/f emergency operation" can be suppressed by setting bit 8 to "1" in [C02864/1](#).
- In case of servo control for synchronous motors (PSM), no change-over to "F/f emergency operation" takes place.

**Note!**

- For closed-loop control of a synchronous motor (PSM), the pole position of the motor must be known! ▶ [Pole position identification \(PPI\)](#) (📖 358)
- For closed-loop control of an asynchronous motor (ASM), the maximum current ([C00022](#)) should be higher than the magnetising current as otherwise the motor does not generate a torque.



Detailed information on the speed feedback can be found in the chapter "[Encoder/feedback system](#)". (📖 314)

Generally, the servo control offers the same advantages as the sensorless vector control (SLVC), i.e. compared to the V/f characteristic control, the servo control (SC) can be used to achieve

- A higher maximum torque throughout the entire speed range
- A higher speed accuracy
- A higher concentricity factor
- A higher level of efficiency
- The implementation of torque-controlled operation with speed limitation
- The limitation of the maximum torque in motor and generator mode for speed-controlled operation

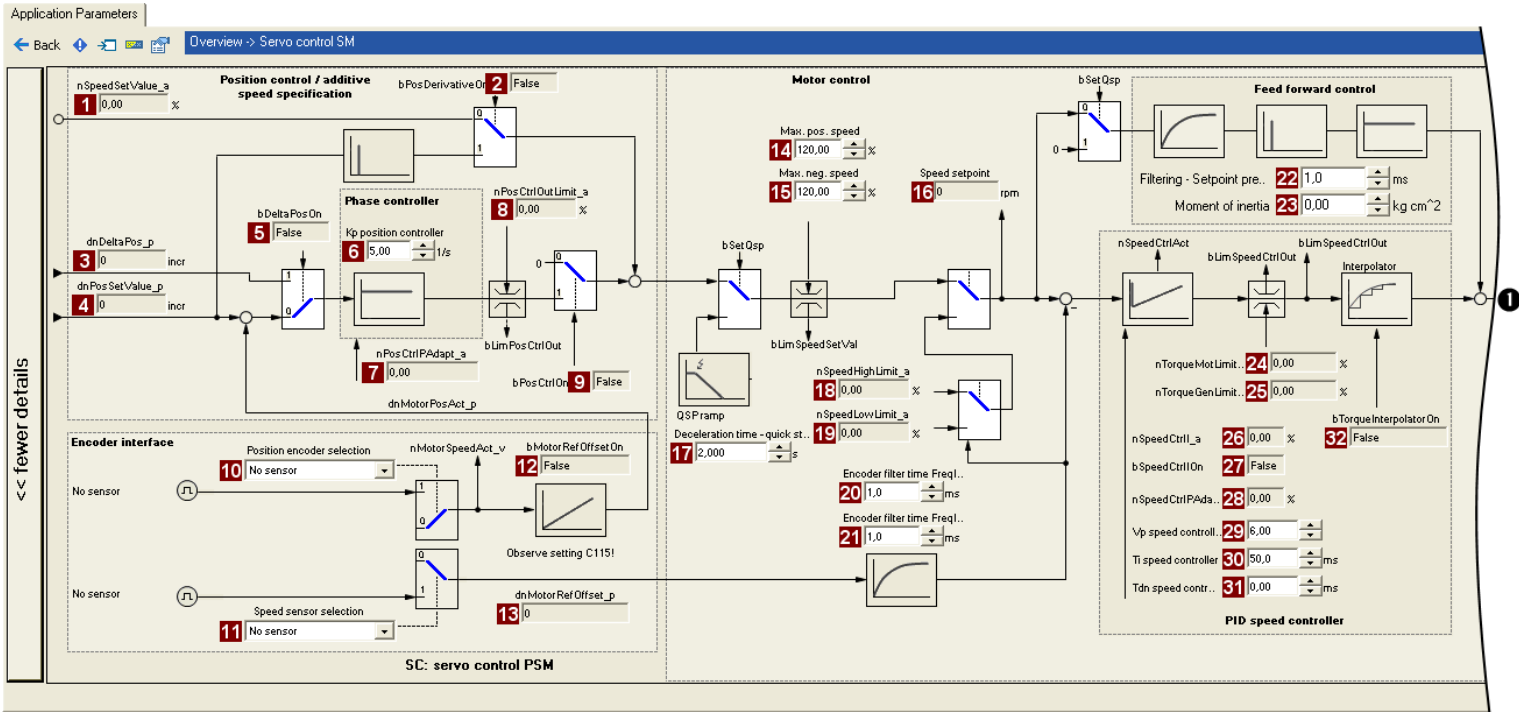
5.9.1 Parameterisation dialog/signal flow



Proceed as follows to open the dialog for parameterising the motor control:

1. »Engineer« Go to the *Project view* and select the 8400 TopLine controller.
2. Select the **Application parameters** tab from the *Workspace*.
3. Select the motor control from the *Overview* dialog level in the **Motor control** ([C00006](#)) list field:
 - "1: SC: Servo control PSM" for synchronous motor
 - or -
 - "2: SC: Servo control ASM" for asynchronous motor
4. Click the **Motor control servo** button to change to the *Overview* → *Motor control vector* dialog box.
 - This dialog level only shows a simplified signal flow with the most important parameters.
 - When you click the >>**More details** button in the left-most position, a signal flow with more details/parameters is displayed, as shown in the following subchapter.

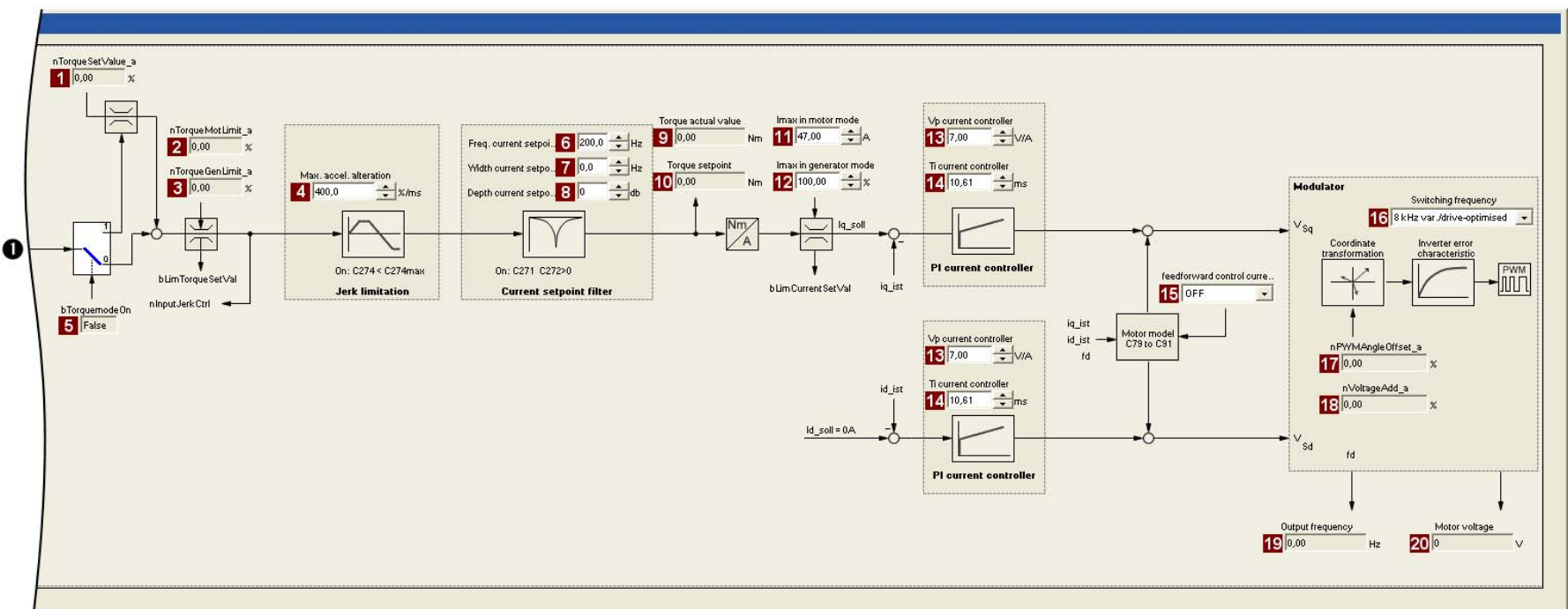
Signal flow for servo control for synchronous motor (PSM):



Parameter	Info	Parameter	Info	Parameter	Info
1	C00830/22 Speed setpoint	14	C00909/1 Max. pos. speed	22	C00275 Setpoint feedforward control filtering
2	C00833/67 MCTRL: bPosDerivativeOn	15	C00909/2 Max. neg. speed	23	C00273 Moment of inertia
3	C00834/4 MCTRL: dnDeltaPos_p	16	C00050 Speed setpoint	24	C00830/29 Limitation of torque in motor mode
4	C00834/5 MCTRL: dnPosSetValue_p	17	C00105 Decel. time - quick stop	25	C00830/28 Limitation of torque in generator mode
5	C00833/35 MCTRL: bDeltaPosOn	18	C00830/88 MCTRL: nSpeedHighLimit_a	26	C00830/24 MCTRL: nSpeedCtrlI_a
6	C00254 Kp position controller	19	C00830/23 MCTRL: nSpeedLowLimit_a	27	C00833/31 MCTRL: bSpeedCtrlIOn
7	C00830/20 MCTRL: nPosCtrlIPAdapt_a	20	C00497/1 Encoder filter time FreqIn12	28	C00830/25 MCTRL: nSpeedCtrlIPAdapt_a
8	C00830/21 MCTRL: nPosCtrlOutLimit_a	21	C00497/2 Encoder filter time FreqIn67	29	C00070/2 SC: Vp speed controller
9	C00833/27 MCTRL: bPosCtrlOn			30	C00071/2 SC: Ti speed controller
10	C00490 Position encoder selection			31	C00072 SC: Tdn speed controller
11	C00495 Speed sensor selection			32	C00833/29 MCTRL: bTorqueInterpolatorOn
12	C00833/68 MCTRL: bMotorRefOffsetOn				
13	C00834/6 MCTRL: dnMotorRefOffset_p				

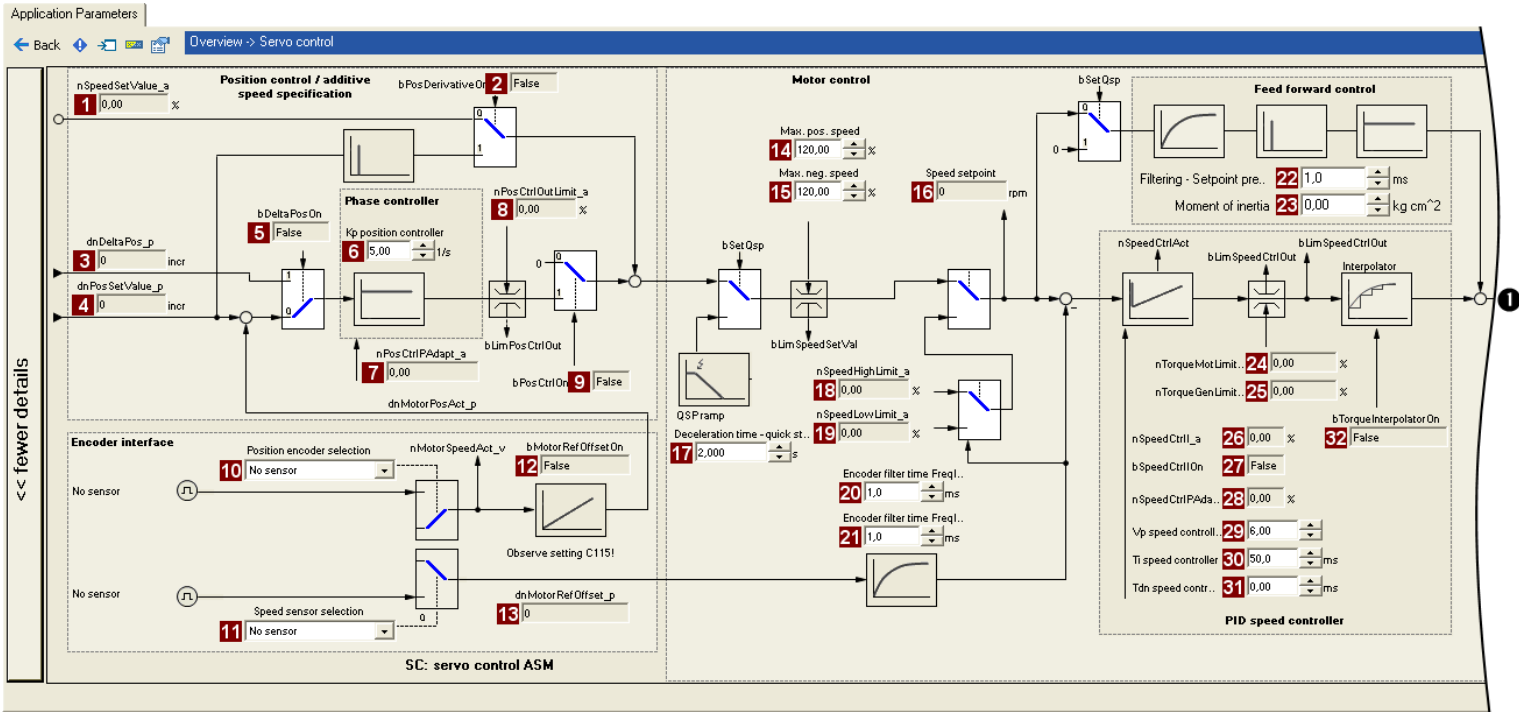
5 Motor control (MCTRL)

5.9 Servo control (SC)

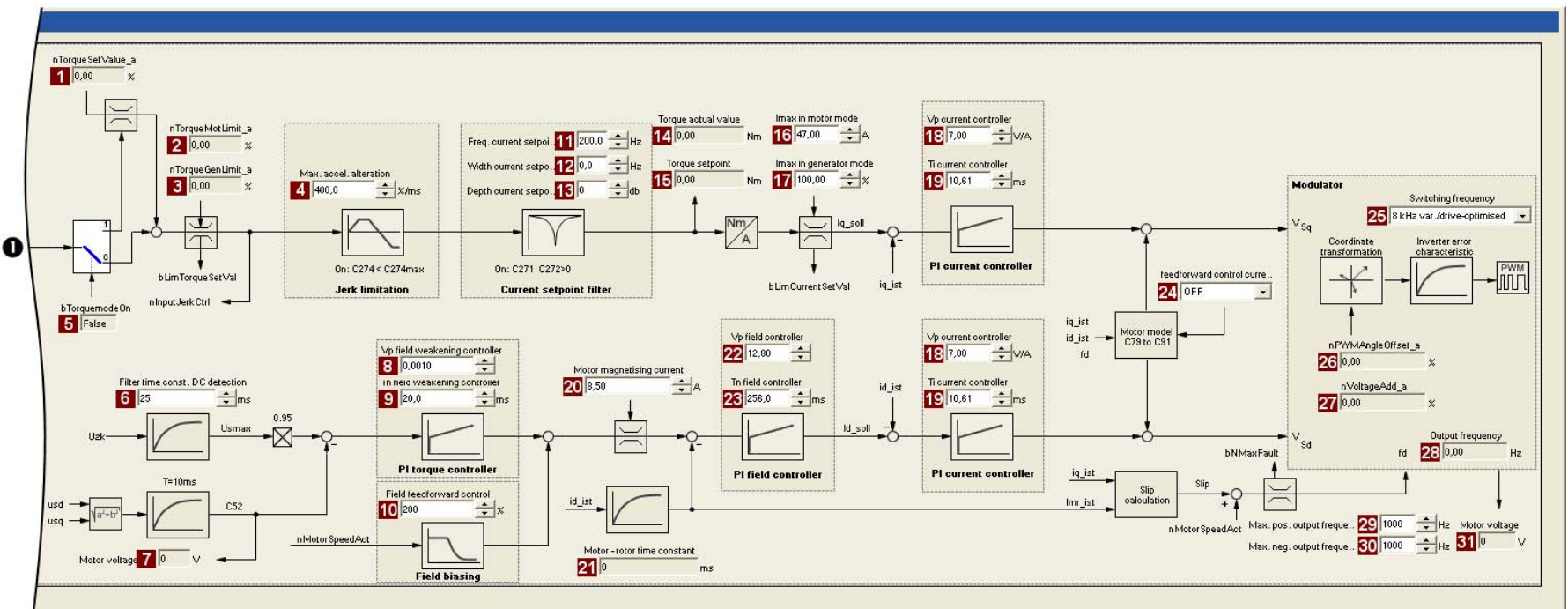


Parameter	Info	Parameter	Info	Parameter	Info
1	C00830/27 MCTRL: nTorqueSetValue_a	6	C00270 SC: Freq. current setpoint filter	15	C00079/1 SC: Current controller - feedforward control
2	C00830/29 Limitation of torque in motor mode	7	C00271 SC: Current setpoint filter width	16	C00018 Switching frequency
3	C00830/28 Limitation of torque in generator mode	8	C00272 SC: Current setpoint filter depth	17	C00830/32 MCTRL: nPWMAngleOffset_a
4	C00274 SC: Max. change in acceleration	9	C00056/2 Actual torque value	18	C00830/31 MCTRL: nVoltageAdd_a
5	C00833/30 MCTRL: bTorqueModeOn	10	C00056/1 Torque demand	19	C00058 Output frequency
6	C00280 SC: Filter time const. DC detection	11	C00022 I _{max} in motor mode	20	C00052 Motor voltage
7	C00052 Motor voltage	12	C00023 I _{max} in generator mode		
8	C00577 SC: V _p field weakening controller	13	C00075 V _p current controller		
9	C00578 SC: T _n field weakening controller	14	C00076 T _i current controller		
10	C00576 SC: Field feedforward control				

Signal flow for servo control for asynchronous motor (ASM):



Parameter	Info	Parameter	Info	Parameter	Info
1	C00830/22 Speed setpoint	14	C00909/1 Max. pos. speed	22	C00275 Setpoint feedforward control filtering
2	C00833/67 MCTRL: bPosDerivativeOn	15	C00909/2 Max. neg. speed	23	C00273 Moment of inertia
3	C00834/4 MCTRL: dnDeltaPos_p	16	C00050 Speed setpoint	24	C00830/29 Limitation of torque in motor mode
4	C00834/5 MCTRL: dnPosSetValue_p	17	C00105 Decel. time - quick stop	25	C00830/28 Limitation of torque in generator mode
5	C00833/35 MCTRL: bDeltaPosOn	18	C00830/88 MCTRL: nSpeedHighLimit_a	26	C00830/24 MCTRL: nSpeedCtrlI_a
6	C00254 Kp position controller	19	C00830/23 MCTRL: nSpeedLowLimit_a	27	C00833/31 MCTRL: bSpeedCtrlIOn
7	C00830/20 MCTRL: nPosCtrlIPAdapt_a	20	C00497/1 Encoder filter time FreqIn12	28	C00830/25 MCTRL: nSpeedCtrlIPAdapt_a
8	C00830/21 MCTRL: nPosCtrlOutLimit_a	21	C00497/2 Encoder filter time FreqIn67	29	C00070/2 SC: Vp speed controller
9	C00833/27 MCTRL: bPosCtrlOn			30	C00071/2 SC: Ti speed controller
10	C00490 Position encoder selection			31	C00072 SC: Tdn speed controller
11	C00495 Speed sensor selection			32	C00833/29 MCTRL: bTorqueInterpolatorOn
12	C00833/68 MCTRL: bMotorRefOffsetOn				
13	C00834/6 MCTRL: dnMotorRefOffset_p				



Parameter	Info		Parameter	Info		Parameter	Info	
1	C00830/27	MCTRL: nTorqueSetValue_a	11	C00270	SC: Freq. current setpoint filter	24	C00079/1	SC: Current controller - feedforward control
2	C00830/29	Limitation of torque in motor mode	12	C00271	SC: Current setpoint filter width	25	C00018	Switching frequency
3	C00830/28	Limitation of torque in generator mode	13	C00272	SC: Current setpoint filter depth	26	C00830/32	MCTRL: nPWMAngleOffset_a
4	C00274	SC: Max. change in acceleration	14	C00056/2	Actual torque value	27	C00830/31	MCTRL: nVoltageAdd_a
5	C00833/30	MCTRL: bTorqueModeOn	15	C00056/1	Torque demand	28	C00058	Output frequency
6	C00280	SC: Filter time const. DC detection	16	C00022	Imax in motor mode	29	C00910/1	Max. pos. output frequency
7	C00052	Motor voltage	17	C00023	Imax in generator mode	30	C00910/2	Max. neg. output frequency
8	C00577	SC: Vp field weakening controller	18	C00075	Vp current controller	31	C00052	Motor voltage
9	C00578	SC: Tn field weakening controller	19	C00076	Ti current controller			
10	C00576	SC: Field feedforward control	20	C00095	Motor magnetising current			
			21	C00083	Motor rotor time constant			
			22	C00077	SC: Vp field controller			
			23	C00078	SC: Tn field controller			

5.9.2 Types of control

The servo control can be operated in two different modes:

- [Speed control with torque limitation](#) (*bTorquemodeOn* = FALSE)
- [Torque control with speed limitation](#) (*bTorquemodeOn* = TRUE)

**Tip!**

A position-controlled application requires a speed control with torque limitation (*bTorquemodeOn* = FALSE).

5.9.2.1 Speed control with torque limitation

When *bTorquemodeOn* = FALSE, the drive system is operated with a selected speed setpoint in a speed-controlled manner.

**Note!**

From version 13.00.00, the torque setpoint *nSpeedSetValue_a* is set to 0 by quick stop (QSP) device-internally and the torque limit values *nTorqueMotLimit_a* and *nTorqueGenLimit_a* are set to 100 % to stop the drive quickly and safely anytime. The previous behaviour can be set in [C2865/1](#) via bit 12 and bit 13.

The operational performance can be adapted in the following ways:

- Overload limitation in the drive train
- Motor current limitation

Overload limitation in the drive train

The torque is limited via the torque setpoint.

- The torque setpoint is identical to the value at the output of the speed controller, *nOutputSpeedCtrl*.
- To avoid overload in the drive train, the torque in motor mode can be limited via the *nTorqueMotLimit_a* process input signal, and the torque in generator mode can be limited via the *nTorqueGenLimit_a* process input signal:

Identifier DIS code data type	Information/possible settings
<i>nTorqueMotLimit_a</i> C00830/29 INT	Torque limitation in motor mode <ul style="list-style-type: none"> • Scaling: 16384 \equiv 100 % M_{\max} (C00057) • Setting range: 0 ... +199.99 % • If keypad control is performed: Parameterisable via C00728/1.
<i>nTorqueGenLimit_a</i> C00830/28 INT	Torque limitation in generator mode <ul style="list-style-type: none"> • Scaling: 16384 \equiv 100 % M_{\max} (C00057) • Setting range: -199.99 ... 0 % • If keypad control is performed: Parameterisable via C00728/2.

**Note!**

To avoid instabilities during operation, the torque limit values are internally processed as absolute values.

Motor current limitation

A cross current setpoint is calculated from the torque setpoint which is limited depending on the magnetising current, the max. current in motor mode ([C00022](#)) and the max. current in generator mode ([C00023](#)). The total current injected into the motor does not exceed the max. currents in motor mode and in generator mode.

**Note!**

For synchronous motors, the Lenze setting of the torque limits *nTorqueMotLimit_a* and *nTorqueGenLimit_a* to 100 % can result in the activation of the torque limitation for motor temperature < max. motor temperature before the set current limit values ([C00022](#), [C00023](#)) are reached.

- With a motor temperature of approx. 20°C and maximum load, the maximum current will then be set to approx. 15 % below the set current limit values.
- **Remedy:** If the torque limits *nTorqueMotLimit_a* and *nTorqueGenLimit_a* are increased to 115 %, the set current limit values can also be reached for a motor temperature of 20°C and maximum load. Alternatively, the motor temperature compensation can be switched off via [C02878](#). In this case, however, the torque accuracy decreases.

5.9.2.2 Torque control with speed limitation

When *bTorquemodeOn* = TRUE, a torque-controlled operation is activated. The setpoint torque directly follows the default value *nTorqueSetValue_a*.

Due to its speed limitation, the torque-controlled drive can only rotate within a speed range whose positive speed is limited by *nSpeedHighLimit_a* and whose negative speed is limited by *nSpeedLowLimit_a*.



Note!

- Absolute speed limitation to speed 0 min^{-1} (*nSpeedLowLimit_a* or *nSpeedHighLimit_a* = 0) is only possible [from version 12.00.00](#).
- Quick stop (QSP) is used to switch over to [Speed control with torque limitation](#).
 - From version 13.00.00, the torque setpoint *nSpeedSetValue_a* is set to 0 by quick stop (QSP) device-internally and the two torque limit values *nTorqueMotLimit_a* and *nTorqueGenLimit_a* are set to 100 % to stop the drive quickly and safely anytime. The previous behaviour can be set in C2865/1 via bit 12 and bit 13.
- [From version 13.00.00](#), the *bLimSpeedTorquemodeOn* status signal is used to show that the speed limitation is active.
- The speed is defined by the process.
- The torque setpoint is calculated directly from *nTorqueSetValue_a*.
 - [From version 12.00.00 onwards](#), the torque limitation is active via *nTorqueMotLimit_a* and *nTorqueGenLimit_a* in this control mode, too, for the torque setpoint to be limited. The torque limitation can be deactivated in [C2865/1](#) via bit 0 to obtain the previous function.

Identifier DIS code data type	Information/possible settings
<i>nTorqueSetValue_a</i> C00830/27 INT	Torque setpoint / additive torque <ul style="list-style-type: none"> • Scaling: $16384 \equiv 100 \% M_{\max}$ (C00057)
<i>nSpeedHighLimit_a</i> C00830/88 INT	Upper speed limit for the speed limitation <ul style="list-style-type: none"> • During torque-controlled operation only (<i>bTorquemodeOn</i> = TRUE) • Scaling: $16384 \equiv 100 \% \text{ rated speed}$ (C00011)
<i>nSpeedLowLimit_a</i> C00830/23 INT	Lower speed limit for speed limitation <ul style="list-style-type: none"> • During torque-controlled operation only (<i>bTorquemodeOn</i> = TRUE) • Scaling: $16384 \equiv 100 \% \text{ rated speed}$ (C00011)
<i>nTorqueMotLimit_a</i> C00830/29 INT	Torque limitation in motor mode <ul style="list-style-type: none"> • Scaling: $16384 \equiv 100 \% M_{\max}$ (C00057) • Setting range: 0 ... +199.99 % • If keypad control is performed: Parameterisable via C00728/1.
<i>nTorqueGenLimit_a</i> C00830/28 INT	Torque limitation in generator mode <ul style="list-style-type: none"> • Scaling: $16384 \equiv 100 \% M_{\max}$ (C00057) • Setting range: -199.99 ... 0 % • If keypad control is performed: Parameterisable via C00728/2.

5.9.3 Basic settings

The following "Initial commissioning steps" must be performed to commission the servo control:

Initial commissioning steps			
1.	<p>Determine the motor control:</p> <ul style="list-style-type: none"> For the closed-loop control of a synchronous motor (PSM): C00006 = "1: SC: Servo control PSM" For the closed-loop control of an asynchronous motor (ASM): C00006 = "2: SC: Servo control ASM" 		
2.	<p>Set the motor selection/motor data</p> <ul style="list-style-type: none"> When selecting and parameterising the motor, the motor nameplate data and the equivalent circuit diagram data are relevant. Detailed information can be found in the "Motor selection/Motor data" chapter. (135) <p>Depending on the motor manufacturer, proceed as follows:</p> <table border="1"> <tr> <td> <p>Lenze motor: Selecting a motor from the motor catalogue in the »Engineer«</p> <p>- or -</p> <ol style="list-style-type: none"> Set the motor nameplate data Automatic motor data identification </td><td> <p>Third party manufacturer's motor:</p> <ol style="list-style-type: none"> Set the motor nameplate data Automatic motor data identification or set known equivalent circuit diagram data manually: C00082: Motor rotor resistance* C00084: Motor stator resistance C00085: Motor stator leakage inductance C00092: Motor magnetising inductance* C00095: Motor magnetising current* * Setting only required for asynchronous motors. </td></tr> </table>	<p>Lenze motor: Selecting a motor from the motor catalogue in the »Engineer«</p> <p>- or -</p> <ol style="list-style-type: none"> Set the motor nameplate data Automatic motor data identification 	<p>Third party manufacturer's motor:</p> <ol style="list-style-type: none"> Set the motor nameplate data Automatic motor data identification or set known equivalent circuit diagram data manually: C00082: Motor rotor resistance* C00084: Motor stator resistance C00085: Motor stator leakage inductance C00092: Motor magnetising inductance* C00095: Motor magnetising current* * Setting only required for asynchronous motors.
<p>Lenze motor: Selecting a motor from the motor catalogue in the »Engineer«</p> <p>- or -</p> <ol style="list-style-type: none"> Set the motor nameplate data Automatic motor data identification 	<p>Third party manufacturer's motor:</p> <ol style="list-style-type: none"> Set the motor nameplate data Automatic motor data identification or set known equivalent circuit diagram data manually: C00082: Motor rotor resistance* C00084: Motor stator resistance C00085: Motor stator leakage inductance C00092: Motor magnetising inductance* C00095: Motor magnetising current* * Setting only required for asynchronous motors. 		
3.	<p>Define the type of control:</p> <p><i>bTorquemodeOn</i> = FALSE: Speed control with torque limitation</p> <p><i>bTorquemodeOn</i> = TRUE: Torque control with speed limitation</p>		
4.	<p>Parameterise the encoder/feedback system. ▶ Encoder/feedback system (314)</p>		
5.	<p>Only with servo control for synchronous motors (PSM):</p> <p>Detect pole position of the motor. ▶ Pole position identification (PPI) (358)</p>		

**Note!**

- The Lenze settings of the controller are predefined for a power-adapted standard asynchronous motor. For an optimal drive behaviour, we recommend to adapt the controller settings.
- When controlling an asynchronous motor (ASM), magnetisation is carried out prior to enabling the setpoint after a controller enable in the Lenze setting. The (delayed) setpoint enabling ensures direct availability of the maximum torque at the motor.
 - The delay of the setpoint enabling associated with the magnetisation can be reduced by reducing the threshold set in [C00918](#). However, this also reduces the maximum torque which is directly available after the setpoint enabling.
 - If [C00918](#) = "0 %", magnetisation is not carried out.

**Tip!**

Information on the optimisation of the control mode and the adaptation to the real application is provided in chapter "[Optimising the control mode](#)". ([book 236](#))

Parameterisable additional functions are described correspondingly in the chapter "[Parameterisable additional functions](#)". ([book 256](#))

5.9.4

Optimising the control mode

**Note!**

When the controller has been enabled, starting up is delayed by the magnetization process of the motor. The speed setpoint is only enabled for motor control if 87 % of the motor magnetising current are available. If this delay is not tolerable for certain applications, the preset percentage threshold can be reduced in [C00918](#).

From version 12.00.00:

- Following successful motor parameter identification, the current controller parameters ([C00075](#), [C00076](#)) and field controller parameters ([C00077](#), [C00078](#)) are calculated automatically.
 - If these parameters are not to be calculated, bit 4 of [C02865/1](#) must be set to "1".
- Following successful motor parameter identification, the speed controller parameters ([C00070/2](#), [C00071/2](#), [C00072](#)) can be calculated automatically.
 - If these parameters are to be calculated, bit 6 of [C02865/1](#) must be set to "5".
- Following successful motor parameter identification, other controller parameters ([C00011](#), [C00022](#), [C00497](#)) can be calculated automatically.
 - If these parameters are to be calculated, bit 6 of [C02865/1](#) must be set to "6".

The "optimisation steps" given in the table below serve to further optimise the control behaviour of the servo control and adjust it to the concrete application.

- Detailed information on the individual steps can be found in the following subchapters.

Generally, the following optimisation steps are recommended:

Optimisation steps	
1.	Optimise current controller . (book 237) <ul style="list-style-type: none"> • The current controller should always be optimised if a motor of a third-party manufacturer with unknown motor data is used!
2.	Optimise speed controller . (book 238) <ul style="list-style-type: none"> • The setting of the speed controller must be adapted depending on the mechanical path.
3.	Optimise response to setpoint changes and determine mass inertia . (book 241) <ul style="list-style-type: none"> • For an optimal reference behaviour, the total moment of inertia can be used to make a feedforward control of the speed setpoint.

Special cases may require further optimisation steps:

Optimisation steps	
1.	Setting the current setpoint filter (band-stop filter) . (□ 244) • In order to suppress or damp (mechanical) resonant frequencies, a current setpoint filter is integrated in the speed control loop which is switched off in the default setting but can be parameterised accordingly, if required. Then readjust the speed controller: Optimise speed controller . (□ 238)
2.	Adapting the max. acceleration change (jerk limitation) . (□ 245)
3.	Only with servo control for asynchronous motors (ASM): Optimising the behaviour of the asynchronous motor in the field weakening range . (□ 250) (For synchronous motors, this function is in preparation)



Tip!

In order to traverse a typical speed profile for optimisation of motor control, you can also use the basic function "[Manual jog](#)" with appropriately adapted manual jog parameters if this basic function is supported by the selected technology application. (□ 625)

5.9.4.1 Optimise current controller



Note!

An optimisation of the current controller should generally be carried out unless a power-adapted standard asynchronous motor is used or the motor has been selected from the motor catalogue of the »Engineer«!

An optimisation of the current controller is sensible since the two control parameters gain ([C00075](#)) and reset time ([C00076](#)) depend on the required maximum current and the set switching frequency.

Parameter	Info	Lenze setting	
		Value	Unit
C00075	Vp current controller	7.00	V/A
C00076	Ti current controller	10.61	ms

- Gain and reset time can be calculated as per the following formulae:

$V_p = \frac{L_{ss}[H]}{T_E[s]}$ $T_i = \frac{L_{ss}[H]}{R_s[\Omega]}$	<p>V_p = Current controller gain (C00075) T_i = Current controller reset time (C00076) L_{ss} = Motor stator leakage inductance (C00085) R_s = Motor stator resistance (C00084) T_E = Equivalent time constant (= 500 µs)</p>
--	--

5.9.4.2 Optimise speed controller

**Note!**

With servo control, an optimisation of the speed controller is recommended in order that the connection to a motor rotating with very high speed after controller enable always functions properly.

The speed controller is in the form of a PID controller with an additional differential speed-setpoint gain. For optimum behaviour, the PID speed controller has to be optimised and the overall mass inertia of the drive train has to be determined.

- In the Lenze setting, the configuration of the speed controller provides robustness and moderate dynamics.

Parameter	Info	Lenze setting	
		Value	Unit
C00070/2	SC: Vp speed controller	6.00	
C00071/2	SC: Ti speed controller	50.0	ms
C00072	SC: Tdn speed controller	0.00	ms

Speed controller gain Vp

The gain Vp ([C00070/2](#)) of the speed controller is defined in a scaled representation which enables a comparable parameterisation almost independent of the power of the motor or inverter. Here, the speed input difference of the controller is scaled to the rated motor speed whereas the output torque refers to the rated motor torque. A gain of 10 means that a speed difference of 1 % is gained through the P component with 10 % torque.

If the rated data of the motor and the mass inertia of the drive system are known, we recommend the following setting:

$$V_p \approx 1.5 \dots 3 \cdot \frac{T_M[s]}{0.01[s]}$$

$$T_M[s] = \frac{2 \cdot \pi \cdot n_N[\text{rpm}]}{M_N[\text{Nm}] \cdot 60} \cdot J_{\text{Drive, total}}[\text{kgm}^2]$$

$$M_N[\text{Nm}] = \frac{P_N[\text{W}] \cdot 60}{2 \cdot \pi \cdot n_N[\text{rpm}]}$$

V_p = Gain of the speed controller ([C00070/1](#))

T_M = Time constant for the acceleration of the motor

M_N = Rated motor torque

n_N = Rated motor speed

$J_{\text{drive, total}}$ = Total moment of inertia of the drive

[5-16] Recommendation for the setting of the gain of the speed controller

If the mass inertia of the drive is unknown, the optimisation can be achieved as follows:

1. Specify speed setpoint.
2. Increase Vp ([C00070/2](#)) until the drive is unstable (observe motor noise).
3. Reduce Vp ([C00070/2](#)) until the drive runs stable again.
4. Reduce Vp ([C00070/2](#)) to approx. half the value.



Tip!

Values recommended by Lenze for the setting of the (proportional) gain:

- For drive systems without feedback: Vp = 6 ... 20
- For drive systems with a good disturbance behaviour: Vp > 12

Speed controller reset time Ti

Apart from setting the P component, [C00071/2](#) provides the possibility to take influence on the I component of the PI controller.

If the mass inertia of the drive is unknown, the optimisation can be achieved as follows:

1. Specify speed setpoint.
2. Reduce Ti ([C00071/2](#)) until the drive is unstable (observe motor noise).
3. Increase Ti ([C00071/2](#)) until the drive runs stable again.
4. Increase Ti ([C00071/2](#)) to approx. twice the value.



Tip!

Value range recommended by Lenze for the setting of the reset time:

Ti = 20 ms ... 150 ms

Differential time constant Tdn (rate time)

The differential time constant Tdn of the speed controller can be set in [C00072](#).

If the mass inertia of the drive is unknown, the optimisation can be achieved as follows:

- Increase Tdn ([C00072](#)) during operation until optimal control mode is reached.

Using the ramp response for setting the speed controller

If the mechanical components cannot be operated at the stability limit, the ramp response can also be used for setting the speed controller.



Stop!

If the controller parameters are preset unfavourably, the control can tend to heavy overshoots up to instability!

- Following and speed errors can adopt very high values.
- If the mechanics are sensitive, the corresponding monitoring functions are to be activated.



Note!

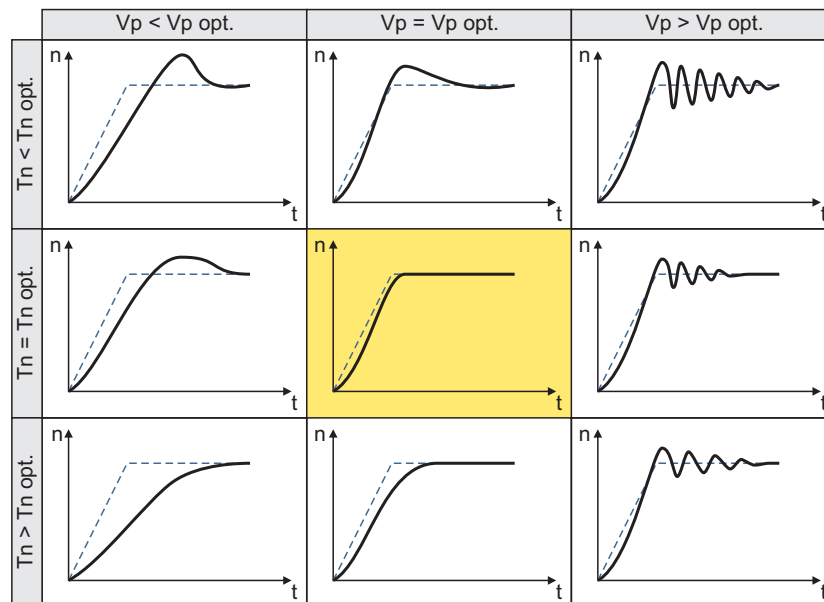
For an optimal setting, we recommend to determine the mass inertia (optimal response to setpoint changes) first.

► [Optimise response to setpoint changes and determine mass inertia](#) (241)



How to optimise the speed controller setting by means of the ramp response:

- Run a typical speed profile and record the ramp response of the speed using the data logger.
 - Motor control variables to be recorded:
`nSpeedSetValue_a` (speed setpoint)
`nMotorSpeedAct_a` (actual speed value)
- Evaluate the ramp response:



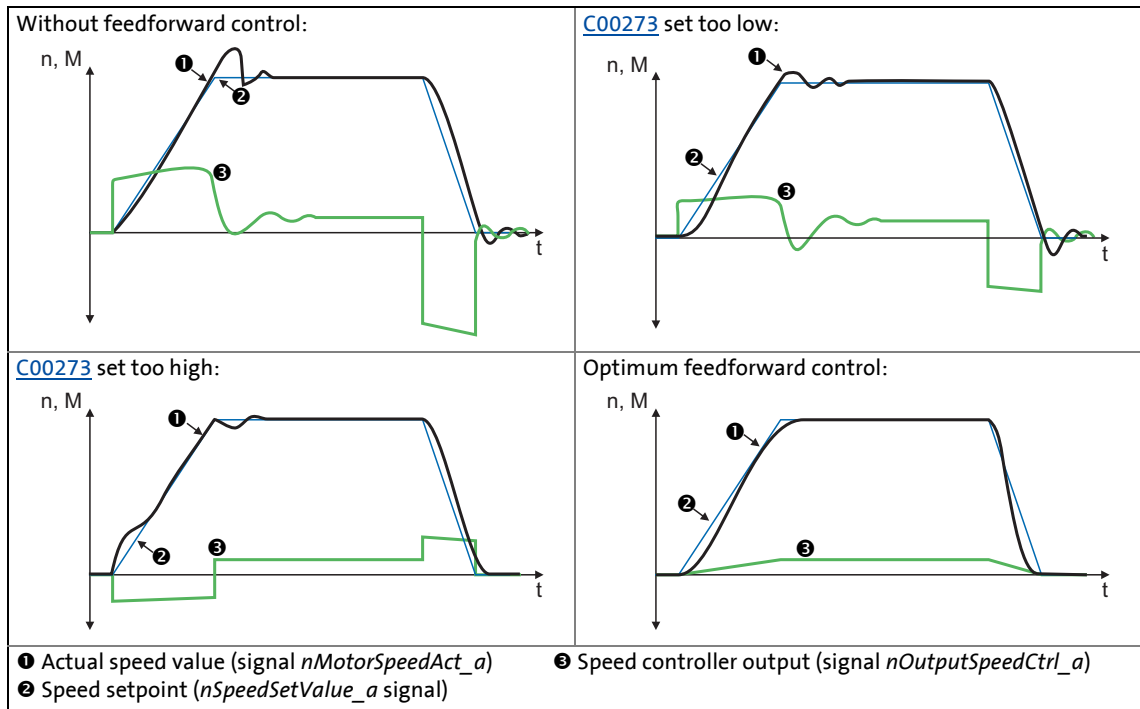
- Solid line = ramp response (actual speed value)
- Dash line = speed setpoint

- Change gain V_p in [C00070/2](#) and reset time T_n in [C00071/2](#).
- Repeat steps 1 ... 3 until the optimum ramp response is reached.

5.9.4.3 Optimise response to setpoint changes and determine mass inertia

Optimisation at constant mass inertia

Setting the total moment of inertia under [C00273](#) provides the optimum torque feedforward control. Depending on the application, an adjustment of the setting under [C00273](#) may be necessary to optimise the response to position/speed setpoint changes by means of the torque feedforward control.



[5-17] Typical signal characteristics for different settings of the load moment of inertia



How to optimise the torque feedforward control:

- Run a typical speed profile and record the inputs and outputs of the speed controller with the data logger.
 - Motor control variables to be recorded:
nSpeedSetValue_a (speed setpoint)
nMotorSpeedAct_a (actual speed value)
nOutputSpeedCtrl_a (speed controller output)
- Estimate the moment of inertia and set it in [C00273](#) in relation to the motor end (i.e. with account being taken of the gearbox factors).
- Repeat the data logger recording (see step 1).
 Now the data logger should show that part of the required torque is generated by the feedforward control and the speed controller output signal (*nOutputSpeedCtrl_a*) is correspondingly smaller. The resulting following error decreases.
- Change the setting in [C00273](#) and repeat the data logger recording until the intended response to setpoint changes is reached.
 - The optimisation could aim at the speed controller being completely relieved (see signal characteristics in Fig. [5-17]).
- Save the parameter set (device command: [C00002/11](#)).

Optimisation at variable mass inertia

From version V12.00.00, mass inertia that changes during the process (e.g. a reel) can be taken into account when optimising the response to setpoint changes.

How to proceed:

1. In [C00273](#) the known constant total moment of inertia (motor, gearbox, shaft, etc.) must be set or determined according to previous instructions ("[How to optimise ...](#)").
 - The determination requires travelling the typical speed profile without variable mass inertia (e.g. reels).
2. At the [LS_MotorInterface](#) SB, the *nInertiaAdapt_a* process signal must be interconnected in a way which ensures that a value of "100 %" is applied at this input.
3. In [C00919/1](#) set the known maximum value of the variable moment of inertia or determine the value according to previous instructions ("[How to optimise ...](#)").
 - The determination requires travelling the typical speed profile including variable mass inertia (e.g. maximum reels).
4. The *nInertiaAdapt_a* process signal can be used during the process to dynamically control the percentage of the variable moment of inertia set in [C00919/1](#) which is to be considered for setpoint feedforward control.

Example:

- If there is no variable moment of inertia (e.g. no reel), the *nInertiaAdapt_a* process signal must be set to "0 %".
- If the maximally variable moment of inertia is available (e.g. maximum reels), the *nInertiaAdapt_a* process signal must be set to "100 %".



Tip!

Via the *nTorqueSetValue_a* process signal at the [LS_MotorInterface](#) SB, any differential signal can be defined for torque feedforward control. First the speed controller, then this additive torque is connected which is hence not derived from the differential change in speed setpoint.

Other functions for differential setpoint feedforward control

From version V12.00.00 onwards, the following additional functions are available for differential setpoint feedforward control (torque feedforward control):

- In [C00653/1](#), the sensitivity of setpoint feedforward control can be adapted.
- In [C00654/1](#), alternatively to the *nSpeedSetValue_a* process signal, the new *nSpeedSetValueInertia_a* process signal for the setpoint feedforward control can be selected at the [LS_MotorInterface](#) SB. Via the *nSpeedSetValueInertia_a* process signal, an optional input value (e.g. setpoint of the position or process controller) for the torque feedforward control can be specified.
- For *bTorqueModeOn* = TRUE, the setpoint feedforward control is added to the torque setpoint *nTorqueSetValue_a*. In this way, feedforward control of torque is also possible for torque-controlled operation (e.g. for winder applications).



Stop!

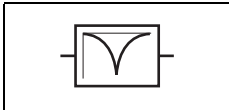
In the Lenze setting of [C00654/1](#), the speed setpoint of the speed controller (*nSpeedSetValue_a*) is used for the torque feedforward control which is why it is also called "differential setpoint feedforward control". A very sharp change of the speed setpoint at the speed controller thus causes a strong torque impulse at the machine!

A very sharp change of the speed setpoint of the speed controller occurs if a control creates the setpoint ramp itself and the speed setpoint is only written every 20 ms to the drive. (In this case, the speed setpoint is changed every 20 ms.)

Deactivate the speed feedforward control for the speed setpoint in [C00654/1](#) if the speed setpoint changes very sharply or the mass inertia is unknown (e.g. in case of hoists)!

5.9.4.4 Setting the current setpoint filter (band-stop filter)

Due to the high dynamic performance/limit frequency of the closed current control loop, mechanical natural frequencies can be activated which may lead to an unstable speed control loop.



To mask out or at least damp these resonant frequencies, a so-called current setpoint filter is integrated into the speed control loop of the controller.

Parameter	Info	Lenze setting	
		Value	Unit
C00270	SC: Freq. current setpoint filter	200.0	Hz
C00271	SC: Current setpoint filter width	0.0	Hz
C00272	SC: Current setpoint filter depth	0	dB

- In the default setting of 0 dB of the filter depth ([C00272](#)), the current setpoint filter is switched off.

Setting of the current setpoint filter

Since the frequency response of the speed controlled system is only rarely known to such an extent that the current setpoint filter can be adjusted to the controlled system in the run-up, the following example describes how to set the current setpoint filter.



How to set the current setpoint filter:

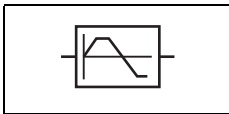
1. [Optimise current controller](#) (□ 237).
2. [Optimise speed controller](#) (□ 238)
3. Measure the oscillation frequency (observe current or speed).
4. Set the measured oscillation frequency in [C00270](#) as filter frequency.
5. Set "25%" of the filter frequency in [C00271](#) as filter width.
 - Example: Filter frequency = 200 Hz → filter width = 50 Hz.
6. Set "40 dB" in [C00272](#) as filter depth.
 - If the filter depth is set to "0 dB" (default setting), the filter is not active.



Note!

Readjust the speed controller after setting the current setpoint filter. ▶ [Optimise speed controller](#). (□ 238)

5.9.4.5 Adapting the max. acceleration change (jerk limitation)



Via the max. acceleration change that can be set in [C00274](#), the change of the setpoint torque can be limited for jerk limitation. Hence, sudden torque step changes can be avoided. The entire speed characteristic is smoothed.

Parameter	Info	Lenze setting	
		Value	Unit
C00274	SC: Max. change in acceleration	400.0	%/ms

In the default setting of 400 %/ms of the max. acceleration change ([C00274](#)), jerk limitation is switched off.

The setting defines the permissible maximum torque change per ms (based on the rated motor torque).

**Note!**

Only activate this jerk limitation for speed-controlled applications!

If table positioning or a free function block interconnection with a positioning operating mode is selected, jerk limitation must be switched off.

- Here, jerk limitation is provided for in the travel profile generator. Setting this jerk limitation in the motor control would lead to following errors!

5.9.4.6 Slip calculation from motor equivalent circuit diagram data

This function extension is available from version 02.00.00!

In order to achieve a better speed stability and torque accuracy, the slip calculation can be either derived from the motor nameplate data (e.g. rated motor speed) or the motor equivalent circuit diagram data (stator resistance, rotor resistance etc.).

In case of servo control for asynchronous motors ([C00006](#) = "2"), the slip calculation is always made

- up to and including version 01.xx.xx from the motor nameplate data.
- from version 02.00.00 onwards in the Lenze setting from the motor equivalent circuit diagram data in order to obtain a higher torque accuracy.

The data to be used for servo control (for asynchronous motors) is selected via bit 1 in [C02879/1](#):

Setting	Info
Bit 0 SLVC	In case of sensorless vector control: <ul style="list-style-type: none"> • "0" ≡ Slip calculation from motor nameplate data (Lenze setting) • "1" ≡ Slip calculation from motor equivalent circuit diagram data
Bit 1 SC_ASM	In case of servo control for asynchronous motors: <ul style="list-style-type: none"> • "0" ≡ Slip calculation from motor nameplate data • "1" ≡ Slip calculation from motor equivalent circuit diagram data (Lenze setting)
Bit 2 ... 7	Reserved



Note!

In order that the slip can be calculated from the motor equivalent circuit diagram data, the equivalent circuit data (stator resistance, rotor resistance etc.) must be known as exactly as possible.

- Selecting a motor in the »Engineer« motor catalogue loads the exact motor equivalent circuit diagram data.
- When the motor nameplate data is entered manually and the motor equivalent circuit diagram data is then detected via the motor parameter identification, the "extended identification" ([C02867/1](#) = 2) must be used. ▶ [Automatic motor data identification](#) (141)

In case of servo control for asynchronous motors, the slip calculation can also be made from the motor nameplate data ([C02879/Bit 1](#) = "0"). In this case, the slip is too high by a factor of 1.35 as the rated motor speed ([C00087](#)) is assumed for a cold machine. This has the following consequences:

- The higher slip provides a better behaviour for the field weakening range.
- In the motor setting range, a considerably too high torque is detected (torque accuracy is worse).
- The achieved maximum torque in the motor setting range is smaller.

From version 15.00.00, the excessive slip with the activated "slip calculation from motor nameplate data" option ([C02879/bit 1](#) = "0") can be corrected by setting bit 7 to "1" in [C02864/1](#). With this setting, the rated motor speed ([C00087](#)) for a warm machine is assumed.

- By selecting the motor in the »Engineer« motor catalogue or executing the motor parameter identification, bit 7 is set to "1" in [C02864/1](#).

**Note!****Exchange of devices**

When devices with a parameterised servo control for asynchronous motors are exchanged, problems regarding the control quality may occur if motor parameters set for a device with version 01.xx.xx are transferred to a replacement device of a higher version.

- In this case, we recommend to load the very precise motor data available from »Engineer« V2.17 or to execute the "advanced motor parameter identification" ([C02867/1](#) = 2). ▶ [Automatic motor data identification](#) (□ 141)
- As an alternative, the slip calculation from the motor nameplate data can be set again in [C02879/1](#) (bit 1 = "0") to obtain the previous behaviour.

5.9.4.7 Temperature compensation within the motor control

This function extension is available from version 02.00.00!

A temperature compensation over the detected motor temperature (display in [C00063/1](#)) serves to compensate inaccuracies in the output torque within the motor control in case of temperature changes of the asynchronous or synchronous motor.



Note!

In the Lenze setting, the temperature compensation within the motor control is activated. The temperature compensation, however, is only active with speed encoder selection "3: Multi encoder" or "4: Resolver" in [C00495](#) as well as error-free KTY temperature detection (display in [C00063/1](#) \neq 255 °C).

Behaviour in case the temperature compensation is not active

If the temperature compensation is not active,

- we assume a motor temperature of 20 °C when using an asynchronous motor. If the asynchronous motor is at operating temperature, however, a too low actual torque value is detected, especially in the field weakening range. This leads to a strong decrease in the torque setting range.
- we assume a motor temperature of 150 °C when using a synchronous motor. If the synchronous motor is cold, however, a too high actual torque value is detected. This leads to a decrease in the torque setting range.

From version 14.00.00 onwards, this negative behaviour in case of warm asynchronous motors or cold synchronous motors can be improved by setting the option "warm machine" (bit= "1") in [C02864](#). We then assume a motor temperature of 90 °C.

The temperature compensation is switched on/off bit-coded in [C02878/1](#):

Setting		Info
Bit 0	SC_PSM	KTY motor temperature compensation with servo control for synchronous motors: <ul style="list-style-type: none"> • "0" \equiv Off • "1" \equiv On (Lenze setting)
Bit 1	SC_ASM	KTY motor temperature compensation with servo control for asynchronous motors: <ul style="list-style-type: none"> • "0" \equiv Off • "1" \equiv On (Lenze setting)
Bit 2 ... 7	Reserved	

General information on temperature behaviour of the asynchronous and synchronous motor

In case of the **asynchronous motor**, the nameplate data always refer to rated data, i.e. on the rated load and thus on the rated temperature of the motor. For the 8400 device series, the equivalent circuit data for stator resistance ([C00084](#)) and rotor resistance ([C00082](#)) are always given for a cold asynchronous motor (20 °C) and converted to star connection. In case of a cold motor (20 °C), the real slip frequency thus corresponds to the calculated setpoint slip. In case of a warm motor, the real slip frequency is higher. This becomes especially apparent at high torques as an inaccuracy of the torque over the motor temperature.

In case of the **synchronous motor**, the field strength generated by the permanent magnet in the rotor is temperature-dependent. With a rated motor temperature, a rated field strength is generated. A negative temperature coefficient of -0.11 %/°C means that with a cold motor at the same setpoint torque a higher output torque is output than with a warm motor.

These errors must be compensated by means of the temperature compensation for asynchronous and synchronous motors in order to have a constant output torque over the motor temperature independent of the motor temperature.

5.9.4.8 Optimising the behaviour of the asynchronous motor in the field weakening range

The behaviour of the asynchronous motor in the field weakening range is influenced by:

- the field controller
- the field weakening controller
- the field feedforward control unit
- adaptive adaptation of the P component of the field and speed controllers
- An additional limitation of the I component of the controller when the voltage limit is reached



Note!

By default, these control parts are called every 1 ms. However, the 1-ms cycle is not always sufficient to achieve an optimum jerk-free transition to the field weakening range.

From version 14.00.00, the control parts can be called for an optimum jerk-free transition to the field weakening range in a 500-μs cycle. For this purpose, bit 5 has to be set to "1" int in [C02864/1](#).

- With this setting, [C00015](#) and [C00576](#) do not have any influence anymore on the field feedforward control.
- We recommend this setting for new applications.
- In existing applications, this setting may require an increase of the reset times of the field weakening controller ([C00578](#)) and the field controller ([C00078](#)) by the factor 2 in order to achieve a stable operation.

In general, these settings are pre-optimised so that further optimisation is not required.

Optimisation for special motors (e.g. mid-frequency motors) or for standard asynchronous motors whose power is not adapted can be carried out according to the algorithms shown in the following sections.

Field controller

The field controller is designed as a PI controller.

Parameter	Info	Lenze setting	
		Value	Unit
C00077	SC: Vp field controller	12.80	
C00078	SC: Tn field controller	256.0	ms

The gain Vp ([C00077](#)) of the field controller can be calculated using the motor rotor time constant and the equivalent time constant of the current-controlled motor:

$$V_{pFeld} = \frac{T_R[s]}{a^2 \cdot T_{Replacement}[ms]} [\%]$$

V_{pFeld} : Gain of the field controller ([C00077](#))
 T_R : Motor rotor time constant ([C00083](#))
 $T_{Equivalent}$: Motor equivalent time constant (approx. 2.5 ms)
 a : Measure for damping (z. B. $a = 2$)

If the rated data of the motor and the mass inertia of the drive system are known, we recommend the following setting:

$$V_{pFeld} \approx \frac{T_R[s]}{4 \cdot T_{Replacement}[ms]} = \frac{T_R[s]}{0.01[s]}$$

$$T_{NFeld}[ms] = T_R[ms]$$

V_{pFeld} : Gain of the field controller ([C00077](#))
 T_R : Motor rotor time constant ([C00083](#))
 T_{Equi} : Motor equivalent time constant
 T_{NFeld} : Time constant of the field controller ([C00078](#))

[5-18] Recommendation for the setting of the gain and the time constant of the field controller



Tip!

The motor rotor time constant depends on the motor rotor resistance, the magnetising inductance, and the leakage inductance.

- For an optimal calculation, we recommend to select the motor from the motor catalogue of the »Engineer« first if a Lenze motor is used. ▶ [Selecting a motor from the motor catalogue in the »Engineer«](#) (139)
- If a third party manufacturer's motor is used, motor parameter identification must be carried out previously. ▶ [Automatic motor data identification](#) (141)

Field weakening controller

The field weakening controller serves to adapt the magnetising current when the maximum control voltage has been reached so that in steady operation approximately 95 % of the maximally possible control voltage is output. Thus, there is a voltage reserve for dynamic load or speed variations.

Parameter	Info	Lenze setting	
		Value	Unit
C00577	SC: Vp field weakening controller	0.0010	
C00578	SC: Tn field weakening controller	20.0	ms

$$V_{p,FS} = 4774.65 \cdot \frac{L_h[\text{mH}] + L_{ss}[\text{mH}]}{L_h[\text{mH}]^2 \cdot n_N[\text{rpm}] \cdot I_N[\text{A}]}$$

$$C00577 = 4774.65 \cdot \frac{C00092[\text{mH}] + C00085[\text{mH}]}{C00092[\text{mH}]^2 \cdot C00087[\text{rpm}] \cdot C00088[\text{A}]}$$

$$T_{n,FS} = 20 \text{ ms} \cdot \frac{0.0010}{V_{p,FS}}$$

$$C00578 = 20 \text{ ms} \cdot \frac{0.0010}{C00577}$$

L_m : Mutual motor inductance ([C00092](#))

L_{sl} : Motor stator leakage inductance ([C00085](#))

n_{rated} = rated motor speed ([C00087](#))

I_{rated} = rated motor current ([C00088](#))

[5-19] Recommendation for the setting of the gain and the time constant of the field weakening controller



Tip!

A field weakening controller set too slow can be recognised by the fact that the actual speed value cannot follow the speed setpoint in the field weakening range. In this case, carry out the setting of the field weakening controller as described in the formula. If the speed setpoint still cannot follow the actual speed value, increase the setting in [C00577](#) to maximally twice the value and reduce the setting in [C00578](#) according to the formula mentioned above.

If the field weakening controller is set too fast, vibrations occur in the magnetising current, in the direct-axis current and in the cross current, in the torque and in the speed in the field weakening range. This is also audible by an increased motor noise (humming). The vibrations can be dampened by a decrease of the proportional gain of the field weakening controller.

Procedure:

- Operate the drive with max. required speed in the field weakening operation.
- Reduce Vp ([C00577](#)) of the field weakening controller until the vibration response cannot be detected anymore. Increase Tn ([C00578](#)) according to the formula.



Note!

Vp ([C00577](#)) can also be set to 0. In this case, Tn ([C00578](#)) should first be set to 2000 ms.

Field feedforward control

To have enough voltage reserve available for dynamic acceleration processes, a timely weakening of the field is required. The field weakening is controlled by the field feedforward control.

Parameter	Info	Lenze setting	
		Value	Unit
C00576	SC: Field feedforward control	200.0	%



Note!

The function of the field feedforward control and thus the field weakening control requires a correct setting of the V/f base frequency ([C00015](#)).

- The selection of the motor from the »Engineer« motor catalogue and the motor parameter identification serve to set the V/f base frequency correctly.
- When third-party motors are entered, either the V/f base frequency ([C00015](#)) has to be calculated manually or a motor parameter identification has to be carried out.
 - ▶ [Adapting the V/f base frequency](#) (□ 164)
 - ▶ [Automatic motor data identification](#) (□ 141)

Due to an error in the device software, the field feedforward control of the servo control only operates properly if the V/f base frequency ([C00015](#)) is reduced by the following factor after being set:

- 400-V devices: Factor 0.173
- 230-V devices: Factor 0.34

The same factor has to be considered for the field feedforward control ([C00576](#)).

From version 14.00.00, the control parts can be called for an optimum jerk-free transition to the field weakening range in a 500-μs cycle. For this purpose, bit 5 has to be set to "1" int in [C02864/1](#).

- With this setting, [C00015](#) and [C00576](#) do not have any influence anymore on the field feedforward control.
- We recommend this setting for new applications.

The field feedforward control reciprocally reduces the magnetising current from the V/f base frequency ([C00015](#)) on. The starting point of the reduction can be shifted to low frequencies via the field feedforward control ([C00576](#)). Thus, more voltage reserve is available for acceleration processes.

The field feedforward control ([C00576](#)) must be specified in %, based on the rated slip of the machine.



Tip!

Generally, the Lenze setting is sufficient for most applications.

- We recommend to increase the field feedforward control for applications with very dynamic acceleration processes in the field weakening range.
- Reduce the field feedforward control for very slow applications if necessary.

Adaptive adaptation of the P component of the field and speed controllers

In the field weakening range, the properties of the drive change due to the reduction of the magnetisation and the voltage limitation of the inverter. To be able to continue to provide a stable, well dampened drive behaviour, the servo control has an automatic adaptation of the P component of the field weakening controller and speed controller.

In the Lenze setting, this function is activated. Depending on the application, this function can be deactivated via [C00079/2](#).

Parameter	Info	Lenze setting
C00079/2	SC: Adaptive field weakening controller	1: On



Tip!

Lenze recommends to always activate the adaptation of the field weakening and speed controller.

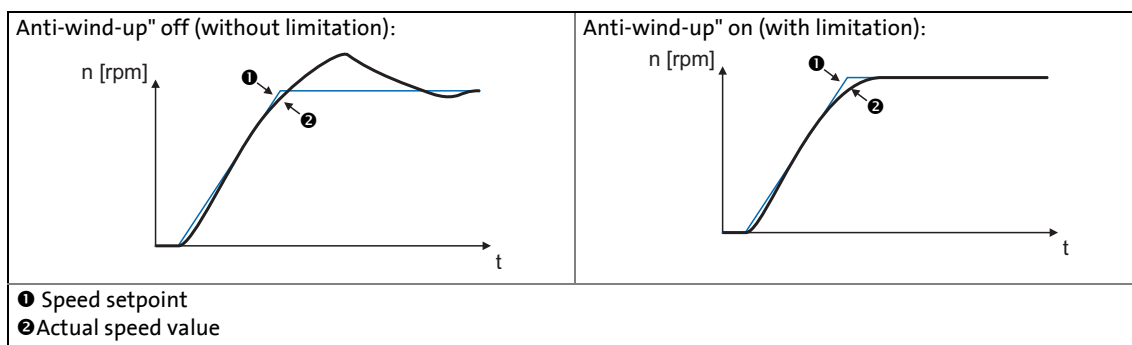
Additional limitation of the I component of the speed controller when the voltage limit is reached (anti-wind-up)

In dynamic acceleration processes in the field weakening range, the acceleration torque is limited due to the limitation of the maximum output voltage of the inverter. Acceleration ramps that are set too high ([C00012](#)) may lead to undesired charging of the integrator of the speed controller, which result in very strong overshoots of the actual speed value when the setpoint is reached.

The so-called anti-wind-up function serves to intelligently limit the integrator part in dynamic acceleration processes in the field weakening range so that an overshoot of the actual speed value can be prevented when the setpoint speed is reached.

This function is deactivated in the Lenze setting because the robustness of the drive may decrease in the field weakening range. Possible consequences are slight speed variations. If required by the application, the function can be activated via [C00079/3](#).

Parameter	Info	Lenze setting
C00079/3	SC: n-Ctrl Anti-Wind-Up	0: Off



[5-20] Typical signal characteristics for switched-on/off anti-wind-up function

**Tip!**

Lenze recommend to activate the additional limitation of the speed controller's I component on reaching the voltage limit ([C00079](#) = 1) if dynamic acceleration processes in the field weakening range are wanted.

- The function should be deactivated again if slight speed variations occur in the field weakening range.
- If this function is activated, the actual speed value may not follow the speed setpoint correctly in the field weakening range.

5.9.4.9 Feedforward control of the current controller

**Note!**

Function only possible with servo control (SC) for asynchronous motors!

In [C00079/1](#), the feedforward control of the current controller can be switched on. The feedforward control serves to unload the current controller so that the current control loop is able to operate more stable and dynamically. The feedforward control can contribute to dampen vibrations at very high speeds.

Before the feedforward control is activated in [C00079/1](#), we recommend the execution of the motor parameter identification in order to get an optimum result with the feedforward control.

► [Automatic motor data identification](#) (141)

**Note!**

If the data of the motor equivalent circuit (motor magnetising inductance, motor stator leakage inductance, motor stator resistance, motor rotor resistance) are not known, the feedforward control of the current controller must not be switched on as otherwise it might cause instabilities in the control loop!

Up to and including version 13.xx.xx the following applies:

The feedforward control of the current controller may only be switched on in [C00079/1](#) if the motor magnetising inductance set in [C00092](#) is not more than 4 % higher than the real magnetising inductance of the connected motor detected by an identification process. Otherwise, instabilities may occur at high speeds in the control loop and the motor can accelerate in an uncontrolled manner up to maximum speed.

- The magnetising inductance of a motor has a tolerance of more than 4 % so that this problem might occur when the motor parameters are loaded from the »Engineer« motor catalogue and the feedforward control of the current controller is activated.
- If the feedforward control is to be used and instabilities occur: Reduce the motor magnetising inductance ([C00092](#)) until a stable behaviour occurs or carry out a motor parameter identification.

From version 14.00.00 the following applies:

The feedforward control of the current controller operates properly within the tolerances of the motor. It is sufficient to select the motor from the »Engineer« motor catalog or enter the data of the motor equivalent circuit manually.

5.10 Parameterisable additional functions

5.10.1 Selection of switching frequency

The switching frequency of the inverter that can be selected in [C00018](#) influences the smooth running performance and the noise generation in the connected motor as well as the power losses in the controller.

The lower the switching frequency the higher the concentricity factor, the smaller the losses, and the higher the noise generation.



Stop!

If operated at a switching frequency of 16 kHz, the output current of the controller must not exceed the current limit values specified in the technical data! (See chapter "Rated data" of the hardware manual.)



Note!

- Operate mid-frequency motors only at a switching frequency of 8 kHz or 16 kHz (var./drive-opt.).
- If operated at a switching frequency of 16 kHz, the Ixt evaluation ([C00064](#)) is considered including the required derating to 67 % of the rated device current at switching frequencies of 2.4 and 8 kHz.
- Ensure that the value does not fall below the permissible switching frequency,
 - if the motor is not approved for the setting switching frequency
 - or -
 - if a sinusoidal filter has been connected between the output of the inverter and the motor which is not approved for the setting switching frequency. (see section "[Preventing a decrease of the switching frequency](#)")

Short overview of the relevant parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C00018	Switching frequency	2: "8 kHz var./drive-opt."	
C00144	Switching frequency reduction (temp.)	1: On	
C00725	Current switching frequency	-	
C00910/1	Max. pos. output frequency	1000	Hz
C00910/2	Max. neg. output frequency	1000	Hz
C02864/1	Bit 4: MCTRL: Special settings 2 Option "Motor ident: Switching frequency 8 kHz" (from version 14.00.00)	0x0000 (Off)	
Highlighted in grey = display parameter			

Settable switching frequencies

Selection in C00018			
1	4 kHz var./drive-optimised	21	8 kHz var./drive-opt./4 kHz min
2	8 kHz var./drive-optimised	22	16 kHz var./drive-opt./4 kHz min
3	16 kHz var./drive-optimised	23	16 kHz var./drive-opt./8 kHz min
5	2 kHz constant/drive-optimised	31	8 kHz var./min. Pv/4 kHz min
6	4 kHz constant/drive-optimised	32	16 kHz var./min. Pv/4 kHz min
7	8 kHz constant/drive-optimised	33	16 kHz var./min. Pv/8 kHz min
8	16 kHz constant/drive-optimised	Abbreviations used: • "var.": Adaptation of the switching frequency depending on the current • "drive-opt.": drive-optimised modulation ("sine/delta modulation") • "fixed": fixed switching frequencies • "min. Pv": additional reduction of power loss	
11	4 kHz var./min. Pv		
12	8 kHz var./min. Pv		
13	16 kHz var./min. Pv		
15	2 kHz constant/min. Pv		
16	4 kHz constant/min. Pv		
17	8 kHz constant/min. Pv		
18	16 kHz constant/min. Pv		



Tip!

The Lenze setting [C00018](#) = "2: 8 kHz var.drive-opt." is the optimal value for standard applications.

Preventing a decrease of the switching frequency

The value must not fall below the permissible switching frequency if the motor is not approved for the setting switching frequency or if a sinusoidal filter is connected between the output of the inverter and the motor that is not approved for the setting switching frequency.

In order to prevent a decrease of the switching frequency, the following settings have to be made:

1. The temporary switching frequency reduction has to be activated by the setting [C00144](#) = "0: Off".
2. The switching frequency has to be set in [C00018](#) so that the value is not fallen below the permissible switching frequency.
3. If a sinusoidal filter is available, only a drive-optimised switching frequency ("drive-opt.") is permissible.

Example: A sinusoidal filter is connected between the output of the inverter and the motor which only is to be operated with a minimum switching frequency of 8 kHz.

In this case, only the following settings in [C00018](#) are permissible:

Selection in C00018	
7	8 kHz constant/drive-optimised
8	16 kHz constant/drive-optimised
23	16 kHz var./drive-opt./8 kHz min

**Note!****Switching frequency for the motor parameter identification**

Up to and including version 13.xx.xx, the motor parameter identification is executed with a switching frequency of 4 kHz.

- Thus, a motor parameter identification is not permissible for the previously mentioned example as the sinusoidal filter may only be operated with a minimum switching frequency of 8 kHz!

From version 14.00.00, the motor parameter identification can also be executed with a switching frequency of 8 kHz instead of 4 kHz. For this purpose, the option "Motor ident.: Switching frequency 8 kHz" (Bit 4 = "1") has to be set in [C02864/1](#).

- With this setting, a motor parameter identification would be permissible for the previously mentioned example.

Generally, a switching frequency of 4 kHz is recommended for the motor parameter identification as it serves to obtain the most accurate results.

► [Automatic motor data identification](#) (141)

Lowering the switching frequency due to high heatsink temperatures

Exceeding the maximally permissible heatsink temperature would lead to an inhibited drive due to the "Overtemperature" error and a torquelessly coasting motor. Therefore, if the Lenze setting is selected, the switching frequency is reduced to the next frequency below when the heatsink temperature has risen to 5 °C below the maximally permissible temperature. After the heatsink has cooled down, the controller automatically switches to the next frequency above until the set switching frequency is reached.

Switching frequency reduction due to high heatsink temperature can be deactivated via [C00144](#). If the switching frequency reduction is deactivated, the "oH1: Heatsink overtemperature" error message will be issued when the maximally permissible heatsink temperature is reached. An "Error" response is the result and the motor is coasting.

Parameter	Info	Lenze setting
C00144	Switching frequency reduction (temp.)	1: On

Lowering of the switching frequency depending on the output current

"Variable" switching frequencies can be selected for the controller in [C00018](#), where the controller automatically lowers the switching frequency depending on the controller output current. The modulation mode will not be changed.



The changeover thresholds are listed in the **8400 hardware manual** in the rated data. The hardware manual has been stored in electronic form on the data carrier supplied with the 8400 controller.

When a "fixed" switching frequency is selected, no switching frequency changeover takes place. In case of fixed frequencies, the controller output current is limited to the permissible value of the corresponding switching frequency. In case of larger load impulses, the overcurrent interruption may be activated, to which the controller responds with "Error".

Limiting the maximum output frequency



Note!

If the servo control mode (SC) is selected, the drive assumes the 'maximum current limitation' state if the maximum output frequency ([C00910](#)) has been reached.

► [Defining current and speed limits](#) (154)

The maximum output frequency ([C00910](#)) of the controller is not limited depending on the switching frequency. Therefore, adapt the maximum output frequency according to our recommendation:

$$\text{Maximum output frequency} \leq \frac{1}{8} \text{Switching frequency}$$

- At a switching frequency of 4 kHz, for instance, 500 Hz for the maximum output frequency should not be exceeded.

Carry out further measures:

- If required, deactivate the switching frequency changeover by the heatsink temperature via [C00144](#).
- If required, ensure that the changeover threshold of the controller output current to the next switching frequency below will not be exceeded. If required, select a constant switching frequency in [C00018](#).

Operation at an ambient temperature of 45°C

The controller is designed so that operation at an ambient temperature of 45° C without derating is permissible at a switching frequency of 4 kHz.

5.10.2 Operation with increased rated power

Under the operating conditions described here and under continuous operation, the controller can be operated with a higher power motor (increased rated power). The remaining overload capacity of the drive system (for 60 s/3 s) is reduced accordingly to approx. 120 %/160 %.

Typical applications stand out due to low dynamic requirements, e.g. pumps and fans, general horizontal materials handling technology and line drives.



The controllers which can be operated at an increased rated power are listed in the **8400 hardware manual** in the rated data. The hardware manual is stored in electronic form on the data carrier which is supplied with the 8400 controller.



Stop!

Operation at increased rated power is only permitted ...

- with the controllers listed in the **8400 hardware manual** for this type of operation in the stated mains voltage range.
- at switching frequencies of 2 kHz and 4 kHz.
- at a max. ambient temperature of 40 °C.
- with the types of installation stated in the **8400 hardware manual**.
- with the fuses, cable cross-sections, mains chokes, and filters as required in the **8400 hardware manual** for this operation.
- after parameterisation according to the specifications below.

Required parameterisation

Operation at increased rated power requires the following settings to be made particularly for the V/f characteristic control (VFCplus), but also for all other types of control:

Parameter	Info	Required setting
C00016	VFC: Vmin boost	adapt to motor (reduce)
C00018	Switching frequency	1: 4 kHz var./drive-opt.
C00021	Slip compensation	adapt to motor
C00120	Setting of motor overload (I _{xt})	adapt to motor
C00123	Device utilisat. threshold (I _{xt})	120 %
C00173	Mains voltage	see hardware manual → Rated data

All other types of control require the following settings in addition:

Parameter	Info	Required setting
C00022	I _{max} in motor mode	higher than rated motor current (max. 160 % rated motor current)
C00081	Rated motor power	adapt motor data (see motor nameplate), then carry out identification run ▶ Automatic motor data identification (141)
C00087	Rated motor speed	
C00088	Rated motor current	
C00089	Rated motor frequency	
C00090	Rated motor voltage	
C00091	Motor cos φ	

5.10.3 Current-dependent stator leakage inductance Ppp(I)



Note!

Function only possible with:

- Servo control (SC) for synchronous motors
- Sensorless control for synchronous motors (SLPSM)

The current controller must be adjusted to the electrical characteristics of the motor stator resistance ([C00084](#)) and stator leakage inductance ([C00085](#)). In case of modern motors, the stator leakage inductance changes with the height of the current so that a new current controller setting is required for each current height.

When the motor is operated with very low and very high currents (e.g. in *Pick and place* applications), it is not always possible to achieve a satisfactory current controller setting for all operating points. For this purpose, the correction of the stator leakage inductance and current controller parameters is now possible via an adjustable saturation characteristic (17 interpolation points).

Short overview of the relevant parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C02853/1...17	PSM: Ppp saturation characteristic (17 interpolation points)	100	%
C02855	PSM: I _{max} L _{ss} saturation characteristic	3000.0	A
C02859	PSM: Activate Ppp saturation char.	0: Off	

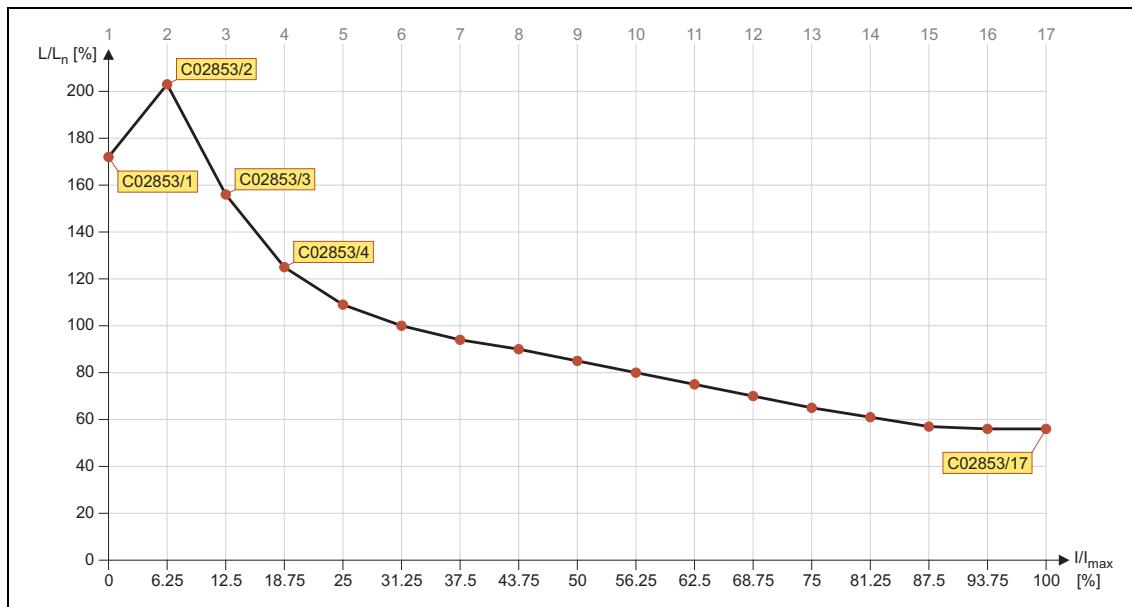


Note!

- The saturation characteristic is not only used for the correction of the current controller but also influences the current controller feedforward control ([C00079/1](#)).
- When a Lenze motor is selected from the »Engineer« motor catalogue, the corresponding saturation characteristic is set in [C02853/1...17](#) and – if required – the correction via this saturation characteristic is switched on in [C02859](#).
- For third-party motors: If the current controller becomes unstable with high currents, contact the motor manufacturer to find out whether the stator leakage inductance changes with the current level. If required, the saturation characteristic of this motor must be set in [C02853/1...17](#) and then activated in [C02859](#).

Distribution of the interpolation points

- The saturation characteristic is represented by 17 interpolation points linearly distributed on the X axis ([C02853/1...17](#)).
- Interpolation point 17 represents 100 % of the maximum motor current in the process ([C02855](#)).
- The following diagram shows the saturation characteristic stored in the »Engineer« motor catalogue for the Lenze motor "MCS12H15" as an example:



[5-21] Saturation characteristic: Inductance referring to the inductance for rated current

5.10.4 Flying restart function

The flying restart circuit for asynchronous motors uses a simple motor model which requires knowledge of the motor stator resistance R_S and the rated motor current.



Note!

- Currently, the flying restart circuit is only available for asynchronous motors. (A flying restart circuit for synchronous motors is in preparation.)
- For a correct functioning of the flying restart circuit, we recommend to perform a parameter identification first. ▶ [Automatic motor data identification](#) (📖 141)
- The flying restart function works safely and reliably for drives with great centrifugal masses.
- Do not use the flying restart function if several motors with different centrifugal masses are connected to a controller.
- After the controller is enabled, the motor can start for a short time or reverse when machines with low friction and low mass inertia are used.
- The flying restart function serves to identify max. field frequencies up to ± 200 Hz.
- When power-adapted standard asynchronous motors are used (rated motor power approximately corresponds to the rated inverter power), a motor parameter identification is not required.
- On drive systems with feedback, you do not need to use the flying restart function because the synchronisation to the speed detected by the feedback is always carried out in a jerk-free manner.
- Especially in case of very high power, very high mass inertia and a mains voltage higher than 440 V, an overvoltage in the DC bus may be caused temporarily. Using a brake resistor may avoid this behaviour.
 - From version 15.00.00, frequency can be set as a remedy in [C00989](#) which is added to the found flying restart frequency. Here, the setting in [C00989](#) has to be increased in small steps up to double the slip frequency until the behaviour does not occur anymore.



Tip!

In association with the flying restart function, we recommend information provided in this documentation on the following topic:

▶ [Automatic DC-injection braking \(Auto-DCB\)](#) (📖 268)

General information

This function serves to activate a mode which is used to "catch" a coasting motor during operation without speed feedback. This means that the synchronicity between controller and motor is to be adjusted in such a way that a jerk-free transition to the rotating machines is achieved in the instant of connection.

The drive controller determines the synchronicity by identifying the synchronous field frequency.

Duration

The "catching" process is completed after approx. 0.5 ... 1.5 seconds. The duration is influenced by the starting value. If the field frequency is not known, we recommend a fixed starting value of 10 Hz (or -10 Hz with systems rotating in negative direction).

Short overview of the relevant parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C00989	Restart on the fly: Flying restart frequency f_{d_add} (from version 15.00.00)	0.00	Hz
C00990	Flying restart fct.: Activate	Off	
C00991	Flying restart fct.: Process	-n...+n Start: +10 Hz	
C00992	Flying restart fct.: Start frequency	5	Hz
C00993	Flying restart fct.: Int. time	300	ms
C00994	Flying restart fct.: Current	25.00	%



How to parameterise the flying restart function:

1. Activate the flying restart circuit by selecting "1: On" in [C00990](#).
 - Every time the controller is enabled, a synchronisation to the rotating or standing drive is carried out.

When the Lenze setting is used, most applications do not require additional controller settings.

If additional settings are necessary, proceed as follows:

2. Define the process and hence the speed range/rotational frequency range in [C00991](#) which is to be examined by the flying restart circuit:
 - positive speed range ($n \geq 0$ rpm)
 - negative speed range ($n \leq 0$ rpm)
 - total speed range
3. Define the starting frequency.

The starting frequency which defines the starting point of the flying restart function is 10 or -10 Hz for processes 0 ... 3 and has been pre-optimised for standard motors.

If process 4 is selected in [C00991](#), an arbitrary starting frequency can be defined via [C00992](#). This is especially recommended for motors with higher rated frequencies.

- We recommend to define a starting frequency of approximately 20 % of the rated motor frequency to enable a safe and fast connection to standing drive systems.
- For systems with a known search speed (e.g. torque-controlled drive systems which are to synchronise to a defined speed) the starting value can be adapted to reduce the flying restart time.

4. Set the flying restart current in [C00994](#).

We recommend setting a flying restart current of 10 % ... 25 % of the rated motor current.

- During a flying restart process, a current is injected into the motor to identify the speed.
- Reducing the current causes a reduction of the motor torque during the flying restart process. A short-time starting action or reversing of the motor is prevented with low flying restart currents.
- An increase of the current improves the robustness of the flying restart function.
- At too high mass inertias and high speeds at the same time, the flying restart circuit may cause an overvoltage in the DC bus ("oU") if no brake resistor is connected. In this case, reduce the flying restart current.



Tip!

Use of motors with higher rated frequencies

For trouble-free operation, we recommend to manually enter a starting frequency of 20 % of the rated motor frequency in [C00992](#) as well as to accelerate the flying restart process (see above) and to use a lower flying restart current (10 % of the rated motor current) if motors with higher rated frequencies are used.

Optimisation of the flying restart time

The duration of the flying restart process can be influenced via the setting of the integration time ([C00993](#)). A reduction of the integration time causes the flying restart function to accelerate and thus a reduced flying restart time.

- We recommend not to change the Lenze setting of the integration time.
- When special motor are used (e.g. multi-pole motors or ASM servo motors), a reduced integration time may improve the flying restart behaviour.

Optimising the current controller if the behaviour is unstable

During the execution of flying restart function, peak currents/torques are avoided by controlling the current amplitude.

Gain ([C00075](#)) and reset time ([C00076](#)) of the current controller can be adapted to improve the jerk-free/torque-free connection of the inverter to the supply of the rotating motor.

- We recommend not to change the Lenze setting of the current controller.
- If the behaviour of the current controller is unstable, gain and reset time can be calculated as per the following formulae:

$$V_p = \frac{L_{ss}[H]}{T_E[s]}$$

$$T_i = \frac{L_{ss}[H]}{R_s[\Omega]}$$

V_p = Current controller gain ([C00075](#))

T_i = Current controller reset time ([C00076](#))

L_{ss} = Motor stator leakage inductance ([C00085](#))

R_s = Motor stator resistance ([C00084](#))

T_E = Equivalent time constant (= 500 µs)

[5-22] Formulae for the calculation of the gain and reset time of the current controller

5.10.5 DC-injection braking

**Note!**

The DC-injection braking function (manually or automatically) is only possible for the following motor control modes:

- [V/f characteristic control \(VFCplus\)](#) (📖 157)
- [V/f characteristic control - energy-saving \(VFCplusEco\)](#) (📖 176)
- [V/f control \(VFCplus + encoder\)](#) (📖 186)
- [Sensorless vector control \(SLVC\)](#) (📖 193)

**Danger!**

Holding braking is not possible when this braking mode is used!

For low-wear control of a holding brake, use the basic function "[Holding brake control](#)". (📖 655)

DC-injection braking allows the drive to be quickly braked to a standstill without the need to use an external brake resistor.

- The braking current is set in [C00036](#).
- The maximum braking torque to be generated by the DC braking current is approx. 20 ... 30 % of the rated motor torque. It is lower than that for braking in generator mode with an external brake resistor.
- The DC-injection braking can be activated manually via a control input of the application or automatically ("Auto-DCB"). The two different modes are described in the following subchapters.

**Tip!**

DC-injection braking has the advantage that it is possible to influence the braking time by changing the motor current or the braking torque..

The automatic DC-injection braking (Auto-DCB) improves the starting performance of the motor in case of V/f operation without speed feedback.

Short overview of the relevant parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C00019	Auto-DCB: Threshold • Operating threshold for activating DC-injection braking	3	rpm
C00036	DC braking: Current • Braking current in [%] based on rated device current (C00098)	50	%
C00106	Auto-DCB: Hold time	0.500	s
C00107	DC braking: Hold time • When "999.000 s" is set, the hold time is infinite.	999.000	s

5.10.5.1 Manual DC-injection braking (DCB)

DC-injection braking can be activated manually for the two technology applications "speed actuating drive" and "switch-off positioning" by connecting the *bSetDCBrake* input of the [LA_NCtrl](#) or [LA_SwitchPos](#) application block to a digital signal source (e.g. via a digital signal source *bCtrl1_B3* of the [LP_CanIn1](#) port block).

- For HIGH-active inputs, DC-injection braking is active as long as the signal is at HIGH level.
- After the hold time ([C00107](#)) has expired, the controller set the pulse inhibit.

Short overview of the relevant configuration parameters:

Parameter	Info	Lenze setting
C00701/4	LA_NCtrl : <i>bSetDCBrake</i> <ul style="list-style-type: none"> • "Speed actuating drive" application: Selection of the signal source for manually activating DC-injection braking. 	Dependent on the selected control mode
C00761/4	LA_SwitchPos : <i>bSetDCBrake</i> <ul style="list-style-type: none"> • "Switch-off positioning" application: Selection of the signal source for manually activating DC-injection braking. 	Dependent on the selected control mode

5.10.5.2 Automatic DC-injection braking (Auto-DCB)

"Automatic DC-injection braking" (referred to in the following as "auto DCB") can be used if there is a requirement that the drive be isolated from the supply at $n \approx 0$.



Note!

Deactivate automatic DC-injection braking when a holding brake is used!

- For this purpose, go to [C00019](#) and set the auto DCB threshold to "0".
- Background: Controller inhibit is already activated by the [Holding brake control](#). ([655](#))

Function

For understanding the auto DCB function, it is necessary to distinguish between three different types of operation:

- The drive has been enabled and, in the course of operation, the speed setpoint falls below the auto DCB threshold.
 - In case of V/f operation without speed feedback, a braking current ([C00036](#)) is injected. After the auto DCB hold time ([C00106](#)) has expired, the motor is deenergised via the auto DCB function, i.e. pulse inhibit is set.
 - In case of V/f operation with speed feedback, the motor is deenergised via the auto DCB function after the auto DCB hold time ([C00106](#)) has expired, i.e. pulse inhibit is set. The braking current which can be parameterised in [C00036](#) does not have any effect during operation with speed feedback.
- When the controller is enabled, the drive is at standstill ($n = 0$).
If the enabled drive is to start, the speed setpoint passed via the acceleration ramp must exceed the auto DCB threshold ([C00019](#)). Below this threshold, the motor will not be energised.

C. When the controller is enabled, the motor (still) rotates at a speed which is above the auto DCB threshold. If the speed setpoint reached via the acceleration ramp exceeds the auto DCB threshold ([C00019](#)), the motor will be energised and the following action will take place:

- During V/f operation without speed feedback, the drive is "caught". ▶ [Flying restart function](#) ([□ 264](#))
- During V/f operation with speed feedback, the drive synchronises to the current actual speed value.



Tip!

We recommend to deactivate the auto DCB function during V/f operation with speed feedback via a setting of [C00019](#) = 0.

Auto DCB function during V/f operation with speed feedback



Stop!

If the DC-injection braking operation is too long and the braking current or braking voltage is too high, the connected motor may overheat!

If you want to use the auto DCB function contrary to our recommendation (see above), the auto DCB threshold must not fall below the following values depending on the number of encoder increments:

Number of encoder increments (C00420)	Auto-DCB threshold (C00019)
8	16
16	8
32	4
64	2
> 128	No restrictions

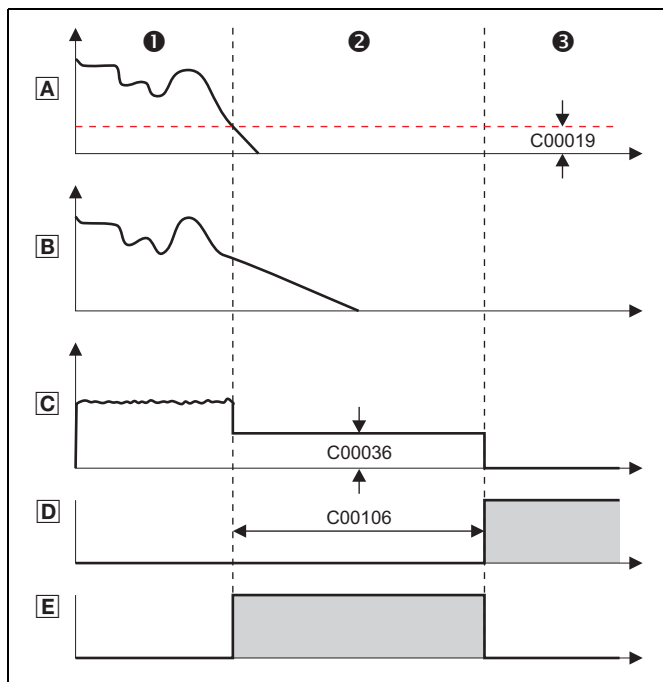
Setting the auto-DCB function



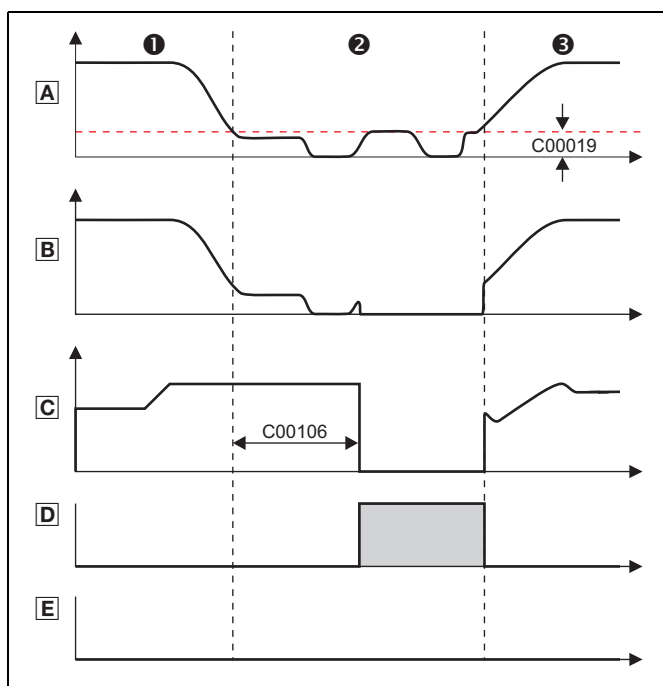
How to set the automatic DC-injection braking:

1. Set a hold time in [C00106](#) > 0 s.
 - Automatic DC-injection braking is active for the time set.
 - In case of V/f operation without speed feedback, the braking set in [C00036](#) is injected.
 - After the set hold time has expired, the controller sets pulse inhibit.
2. Set the operating threshold in [C00019](#).
 - The operating threshold can serve to set a dead band in the setpoint. If DC-injection braking is not to be active then, [C00106](#) must be set to a value of "0".

Explanation of the automatic DC-injection braking function by means of two examples



[5-23] Example 1: Auto-GSB signal characteristic during V/f operation without speed feedback



[5-24] Example 2: Auto-GSB signal characteristic during V/f operation with speed feedback

- ❶ The motor rotates at a specified speed. The current adjusts itself to the load, see [C](#).
- ❷ The DC braking current set in [C00036](#) is injected.
- ❸ After the hold time ([C00106](#)) has expired, a pulse inhibit is set.

- [A](#) Speed setpoint
- [B](#) Actual speed value of the motor
- [C](#) Controller output current
- [D](#) Disable voltage
- [E](#) DC-injection braking is active

- ❶ The motor rotates at a specified speed. The current adjusts itself to the load, see [C](#).
- ❷ The current sets itself load-dependent until the hold time ([C00106](#)) has expired.
- ❸ The actual speed value of the motor follows the speed setpoint. The resulting current depends on the load.

- [A](#) Speed setpoint
- [B](#) Actual speed value of the motor
- [C](#) Controller output current
- [D](#) Disable voltage
- [E](#) DC-injection braking is active

5.10.6 Slip compensation

**Note!**

Slip compensation is only active with the following motor control modes:

- [V/f characteristic control \(VFCplus\)](#) (□ 157)
- [Sensorless vector control \(SLVC\)](#) (□ 193)

Under load, the speed of an asynchronous motor decreases. This load-dependent speed drop is called slip. The slip can partly be compensated for by the setting in [C00021](#).

Parameter	Info	Lenze setting	
		Value	Unit
C00021	Slip compensation	2.11	%

- The setting of [C00021](#) can be done automatically in the course of motor parameter identification. ▶ [Automatic motor data identification](#) (□ 141)
- The setting must be made manually if the motor parameter identification cannot be called up.

**How to set the slip compensation manually:**

1. Set rated motor current ([C00088](#)) and rated motor frequency ([C00089](#)).
2. Calculate the slip compensation according to motor nameplate data:

$$s = \frac{n_{rsyn} - n_r}{n_{rsyn}} \cdot 100\%$$

$$n_{rsyn} = \frac{f_r \cdot 60}{p}$$

- s Slip constant ([C00021](#)) [%]
- n_{rsyn} Synchronous motor speed [rpm]
- n_r Rated motor speed according to the motor nameplate [rpm]
- f_r Rated motor frequency according to the motor nameplate [Hz]
- p Number of motor pole pairs (1, 2, 3 ...)

3. Transfer the calculated slip constant s to [C00021](#).
4. Correct the setting in [C00021](#) while the drive is running until the load-dependent speed drop does not occur anymore between idling and maximum load of the motor in the desired speed range.

**Tip!**

The following guide value applies to a correctly set slip compensation:

- Deviation from the rated motor speed $\leq 1\%$ for the speed range of 10 % ... 100 % of the rated motor speed and loads \leq rated motor torque.
- Greater deviations are possible in the field weakening range.
- If [C00021](#) is set too high, the drive may get unstable.
- Negative slip ([C00021](#) < 0) with V/f characteristic control results in "smoother" drive behaviour at heavy load impulses or applications requiring a significant speed drop under load.

5.10.7 Oscillation damping

Mechanical oscillations are undesirable effects in every process and they may have an adverse effect on the single system components and/or the production output.

Mechanical oscillations in the form of speed oscillations are suppressed by the oscillation damping function.

Mechanical oscillations may occur:

- In the voltage range (output voltage is lower than max. voltage)
 - Here, the oscillations occur in no-load operation.
 - Here, speeds of 40 ... 80 % of the rated speed are typical.
 - See subchapter "[Oscillation damping voltage range](#)". (□ 273)
- In the field weakening range (output voltage has reached maximum voltage)
 - Here, the oscillations occur in no-load operation and with load.
 - Here, speeds higher than the rated speed are typical, especially when the output frequency is close to the mains frequency.
 - See subchapter "[Oscillation damping in the field weakening range](#)". (□ 274)



Note!

With servo control (SC), the [Oscillation damping voltage range](#) has no influence.

Mechanical natural frequencies can be suppressed or at least dampened in the speed control loop of the servo control by means of a current setpoint filter. ▶ [Setting the current setpoint filter \(band-stop filter\)](#) (□ 244)

Oscillation dampening, especially in the field weakening range, is also possible by activating the current controller feedforward control ([C00079/1](#)).

5.10.7.1 Oscillation damping voltage range

The oscillation damping voltage range is successfully used with

- unloaded motors (no-load oscillations)
- motors whose rated power deviates from the rated power of the controller.
 - e.g. during operation at high switching frequency including the power derating involved.
- operation with higher-pole motors
- operation with special motors
- compensation of resonance in the drive
 - At an output frequency of approx. 20 ... 40 Hz, some asynchronous motors can show resonance which causes current and speed variations and thus destabilise the running operation.

Parameter	Info	Lenze setting	
		Value	Unit
C00234	Oscillation damping influence	5.00	%
C00235	Oscillation damping filter time	32	ms



Note!

Compensate the resonance during operation with feedback (closed loop, feedback of n_{act}) via the parameters of the slip regulator.

► [Parameterising the slip regulator](#) (190)



How to eliminate speed oscillations in no-load operation at speeds with 40 ... 80 % of the rated speed:

1. Approach the area where the speed oscillations occur.
2. Reduce the speed oscillations by changing [C00234](#) step by step (increment 1 %).
 - The filter time oscillation damping ([C00235](#)) should not be changed.
3. These can be indicators for smooth running:
 - Constant motor current characteristic
 - Reduction of the mechanical oscillations in the bearing seat

5.10.7.2 Oscillation damping in the field weakening range

When the max. possible output voltage (full modulation) has been reached, a voltage dip in the DC bus causes a voltage fluctuation in the motor. With load and during no-load operation this voltage fluctuation can cause mechanical oscillations.

The "oscillation damping field weakening" adjustable in [C00236](#) serves to limit the maximum output voltage. This can be used to always compensate voltage dips in the DC bus to the output voltage (constant output voltage). This serves to prevent mechanical oscillations due to these voltage dips.

Parameter	Info	Lenze setting	
		Value	Unit
C00236	Oscillation damping field weakening • Setting "0" \equiv 100 % output voltage can be reached	14	

- With the Lenze setting of [C00236](#) the limitation of the output voltage is set so that voltage dips in the DC bus in the output voltage for the single-phase and three-phase devices can largely be compensated so that no speed oscillations may be expected. Thus, an adaptation of [C00236](#) is not required in the majority of cases.
- Maximum output voltage to be reached with Lenze setting of [C00236](#):
 - Single-phase devices: 98.2 %
 - Three-phase devices: 99.7 %



Note!

The limitation of the output voltage via [C00236](#) in the extreme field weakening range (high speeds) causes a reduction of the max. possible output torque (stalling torque).

- If the output torque to be reached in the extreme field weakening range is not sufficient (motor is stalling too early), reduce the setting in [C00236](#).

With servo control (SC), the Lenze setting of [C00236](#) should not be reduced. Otherwise the field weakening control could not work optimally anymore (the behaviour at high speeds may get worse). When servo control (SC) has been selected, the oscillation damping in [C00236](#) should never be set to "0".



How to eliminate speed oscillations in the field weakening range:

1. Approach the area where the speed oscillations occur.
2. Reduce the speed oscillations by changing [C00236](#) step by step (increment 1).
3. These can be indicators for smooth running:
 - Constant motor current characteristic
 - Reduction of the mechanical oscillations in the bearing seat

5.10.8 Phase sequence reversal for correcting misconnected UVW motor phases

**Note!**

Up to and including version 02.00.00, this function may only be activated for the following motor control types:

- [V/f characteristic control \(VFCplus\)](#) (□ 157)
- [V/f characteristic control - energy-saving \(VFCplusEco\)](#) (□ 176)

For all other motor control types, this function must not be activated because the set control mode would not work in that case!

From version 12.00.00, this function may be activated for all motor control types with the exception of the ones for synchronous motor.

The activation of this function does not affect the control types for synchronous motor since these control types require an in-phase connection of the synchronous motor.

If the motor phases are misconnected at the inverter output (e.g. phase u takes the place of phase v), the motor will rotate in the wrong direction.

To correct such misconnected motor phases, the rotating field of the controller's output can be reversed by selecting "1: Inverted" in [C00905](#). In this case, a phase will be reversed at the output of the inverter.

This function does not have any effect on setpoints and actual values, i.e. the polarity of the speed setpoint/actual speed value, actual torque, output frequency, and AngleOffset do not change.

**Tip!**

Cases of application for this function:

- Phase sequence reversal in case of misconnected motor phases.
- Setting of the correctly signed direction of rotation for inversely mounted motors.

5.10.9 Field weakening for synchronous motors

This function extension is available from version 02.00.00!

**Note!**

Function only possible with:

- Servo control (SC)
- Sensorless control for synchronous motors (SLPSM) (from version 10.00.00)

In the Lenze setting, the field weakening for synchronous motors is activated in [C00079/4](#).

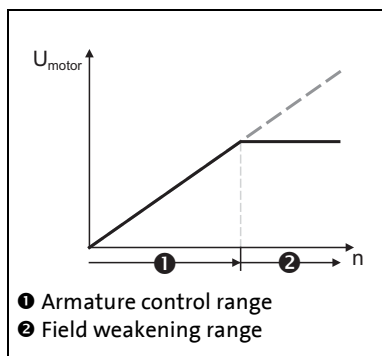
- If a high energy efficiency is required, keep the field weakening switched off or restrict the field weakening operation via [C00938](#).

**Stop!**

In the field weakening operation, a current is injected into the synchronous motor even in idle state which can rise to maximum current ([C00022](#)).

Ensure that this no-load current does not cause the motor to be heated impermissibly!

- The use of a temperature feedback via KTY is recommended. ▶ [Motor temperature monitoring \(KTY\)](#) (□ 373)

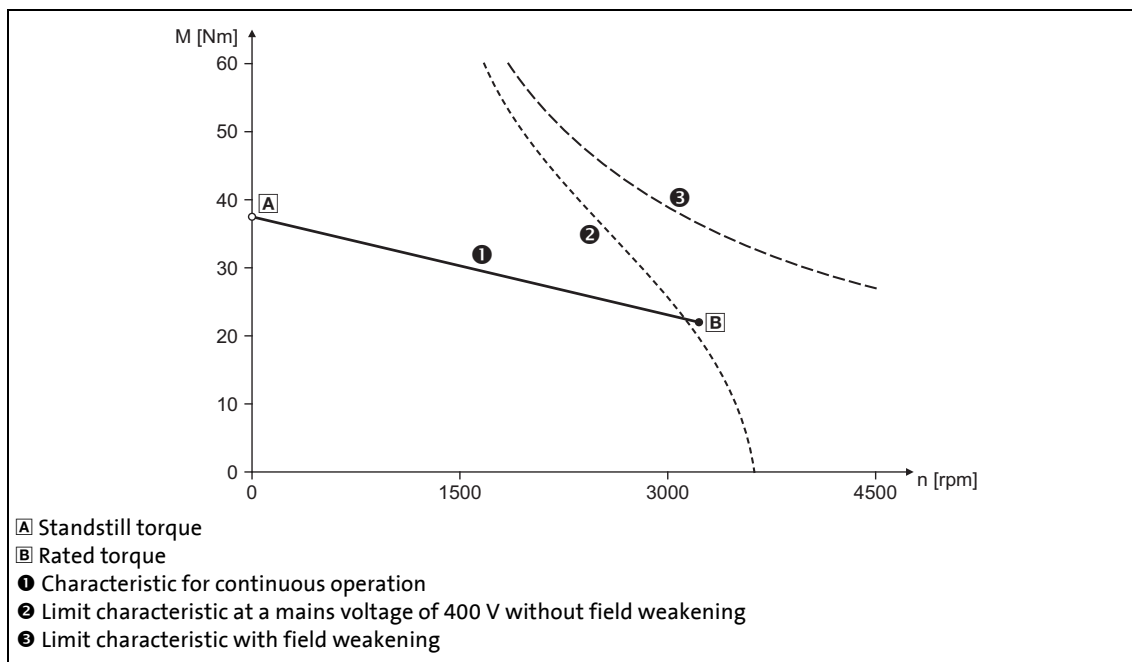


- When field weakening is switched on, the motor magnetising current is increased from 0 A to the maximally effective magnetising current via an internal control loop when the voltage limit is reached.
- As a result, a higher speed can be reached at the same motor voltage or DC-bus voltage.

[5-25] Voltage/speed characteristic with switched-on field weakening

$$n_{\max} = n_{\text{nenn_mot}} \cdot \frac{800\text{V}}{\sqrt{2} \cdot U_{\text{nenn_mot}}}$$

[5-26] Calculation of the maximally reachable speed with switched-on field weakening



[5-27] Speed/torque characteristics of a synchronous servo motor with field weakening

Short overview of the relevant parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C00079/4	Field weakening	1: On	
C00938	Limitation of maximally effective field-producing motor current • With regard to rated motor current (C00088)	30	%
C00937/1	Maximally effective field-producing motor current	-	A

Highlighted in grey = display parameter

- The maximally effective field-producing motor current is calculated based on the motor data set in [C00085](#), [C00089](#) and [C00098](#). Then, the value is internally limited to 98 % of the set maximum current ([C00022](#) or maximally permissible current for the permanent switching frequency set in [C00018](#)).
- [C00938](#) serves to limit the maximally effective field-producing motor current as well.
 - In the Lenze setting, the field weakening for synchronous motors is active ([C00079/4](#)). However, the field-producing motor current is limited via [C00938](#) to 30 % of the rated motor current ([C00088](#)). Hence, the maximum speed is limited during field weakening operation and, at the same time, the temperature rise of the motor during field weakening operation and no-load operation is also limited.
 - If a higher speed for the field weakening operation is required or the current in the field weakening operation is to be limited (e.g. since no motor temperature detection is available and/or heating in the field weakening operation is to be limited), the value must be increased or reduced accordingly in [C00938](#).

- In [C000937/1](#), the actually used maximally effective field-producing motor current is displayed.
 - With switched-on and active field weakening: 0.00 A ... -x.xx A
 - With sensorless control for synchronous motors (SLPSM), the injected current is displayed in open-loop controlled operation: 0.00 A ... +x.xx A
 - If neither field weakening nor open-loop controlled operation are active, "0.00 A" is displayed.



Note!

If a Lenze motor is used:

The controller is automatically parameterised so that field weakening operates optimally and the maximally permissible speed is monitored.



Stop!

If an OEM motor is used:

If pulse inhibit is set in the controller, the DC bus is loaded with the voltage that corresponds to the current speed of the machine.

Since with switched-on field weakening higher speeds can be achieved at a correspondingly higher rotor voltage of the motor, the DC bus can be loaded to a voltage higher than the set DC-bus voltage in case of pulse inhibit and a currently high motor speed and even exceed the maximally permissible voltage of 800 V!

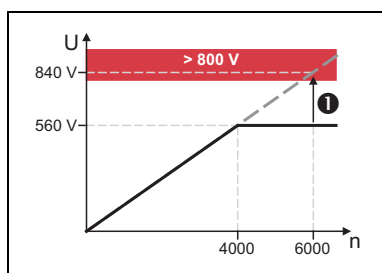
For device protection, either use a brake chopper or parameterise the motor speed monitoring via [C00965](#) in such a way that only a maximum speed is possible which would be also reachable without field weakening with a DC-bus voltage of = 800 V.

► [Motor speed monitoring](#) (📖 304)

Example: Voltage increase in the DC bus when field weakening is switched off

(For instance by an active setting of the controller inhibit or by tripping a fault or error at high motor speed.)

Field weakening	Speed n	Motor voltage peak value
Switched off	4000 rpm	560 V
	5700 rpm	800 V
	6000 rpm	840 V
Switched-on	6000 rpm	560 V



- If pulse inhibit occurs at 6000 rpm and switched-on field weakening, the DC bus is loaded to more than 800 V (❶).
- A speed limitation to 5700 rpm is required since this speed causes a DC-bus voltage of 800 V if field weakening is switched off.

[5-28] Example: Possible DC-bus voltage > 800 V if field weakening gets lost

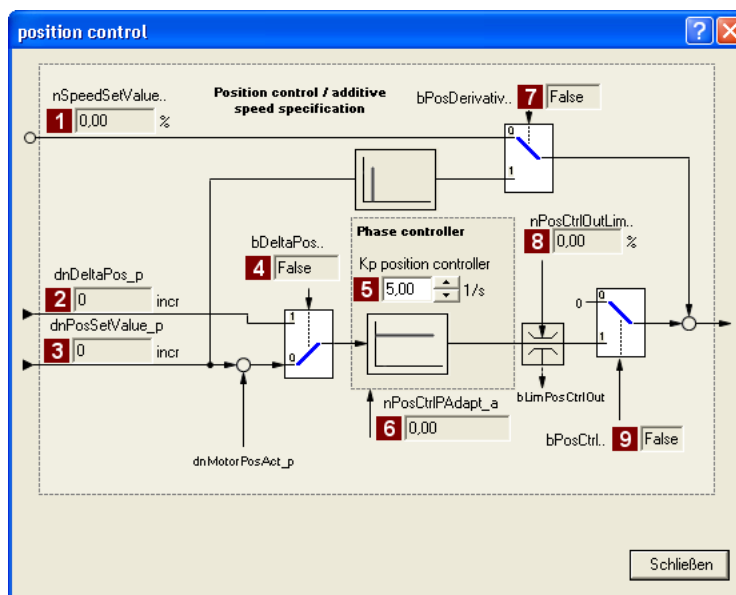
5.11 Position control/additive speed specification

In the Lenze setting, the position control is only active with [TA "Table positioning"](#).



Proceed as follows to open the dialog for parameterising the position control:

1. »Engineer« Go to the *Project* view and select the 8400 TopLine controller.
2. Select the **Application parameters** tab from the *Workspace*.
3. Go to the *Overview* dialog level and click the **Motor control...** button to change to the *Overview → motor control...* dialog level.
4. Click the **Position control** button in the displayed signal flow.



Parameter	Info	
1 C00830/22	MCTRL: nSpeedSetValue_a	Speed setpoint
2 C00834/4	MCTRL: dnDeltaPos_p	Position difference (following error input)
3 C00834/5	MCTRL: dnPosSetValue_p	Absolute position setpoint
4 C00833/35	MCTRL: bDeltaPosOn	TRUE = Position difference is active as setpoint selection
5 C00254	Kp position controller	Gain for following error compensation
6 C00830/20	MCTRL: nPosCtrlPAadapt_a	Adaptation of the position controller gain
7 C00833/67	MCTRL: bPosDerivativeOn	TRUE = Setpoint for the speed controller is created from the position setpoint
8 C00830/21	MCTRL: nPosCtrlOutLimit_a	Limitation of the position controller output
9 C00833/27	MCTRL: bPosCtrlOn	TRUE = Position/angle control active

5.12 Braking operation/brake energy management

When braking electrical motors, the kinetic energy of the drive train is fed back regeneratively to the DC bus. This energy results in a boost of the DC-bus voltage.

- Several different strategies can serve to avoid DC-bus overvoltages:
 - Use of a brake resistor
 - Stopping of the ramp function generator if brake chopper threshold exceeded (RFG_Stop)
 - Use of the "Inverter motor brake" function
 - Combination of the above named options
- In the case of inverters with a 3-phase supply, the following is also possible:
 - Coupling of the inverters in a DC-bus connection
 - Recovery of regenerative energy with a regenerative module



Stop!

If the connected brake resistor is smaller than required, the brake chopper can be destroyed!

- Appropriate protective measures are described in subchapter "[Avoiding thermal overload of the brake resistor](#)". (📖 289)

If no brake resistor or regenerative module is used, the overvoltage switch-off ("oU") may respond, e.g. in case of short deceleration times during feedback operation. ▶ [Error messages of the operating system](#) (📖 696)

Using the integrated brake chopper

We recommend to use the brake chopper (brake transistor) which is integrated into the controller for the braking operation, regardless of the selected motor mode.

- Connect the required brake resistor to the R_{B1} and R_{B2} terminals of the controller.
- In [C00175](#), a ramp function generator stop (FB [L_NSet 1](#)) can be set for instances when the brake resistor is controlled. This prevents overvoltage deactivation in the case of short deceleration times. ▶ [Selecting the response to an increase of the DC-bus voltage](#) (📖 284)



Note!

The brake transistor will be switched off if it remains switched on for a period of 4 seconds.

- If the DC-bus voltage falls under the brake chopper threshold for a short time again, the brake transistor can switch on again for a maximum of 4 seconds, without interruption.
- This protective function is used to prevent the brake chopper from being switched on permanently due to e.g. too high voltages at all times or incorrect interconnection of the *bBrakeChopperOn* signal (from version V12.00.00).
- From version 14.00.00, the limitation of the operating time can be deactivated to max. 4 seconds. For this purpose, set bit 1 to "1" in [C02864/1](#).

The integrated brake chopper is always triggered via the DC-bus voltage with exceedance of the "voltage threshold for braking operation" independent of the device status.

From version 14.00.00, the brake chopper can also be switched off at pulse inhibit or when the "Fault" device status is activated.

- For a switch-off at pulse inhibit, set bit 7 to "1" in [C02865/1](#).
- For a switch-off in the "Fault" device status, set bit 2 to "1" in [C02864/1](#).

DC-bus system

For a DC-bus connection with other devices, we recommend to connect the regenerative power supply module to terminals +UG and –UG.



Note!

DC-bus system without the use of a regenerative module:

- Up to and including version V02.xx.xx, only one internal brake chopper can be used in the DC-bus system to dissipate regenerative energy.
- From version V12.00.00, all internal brake choppers can be used in the DC-bus system to dissipate regenerative energy ("Master-slave operation"). ▶ [Control of multiple internal brake choppers in the DC-bus system](#) (📖 289)

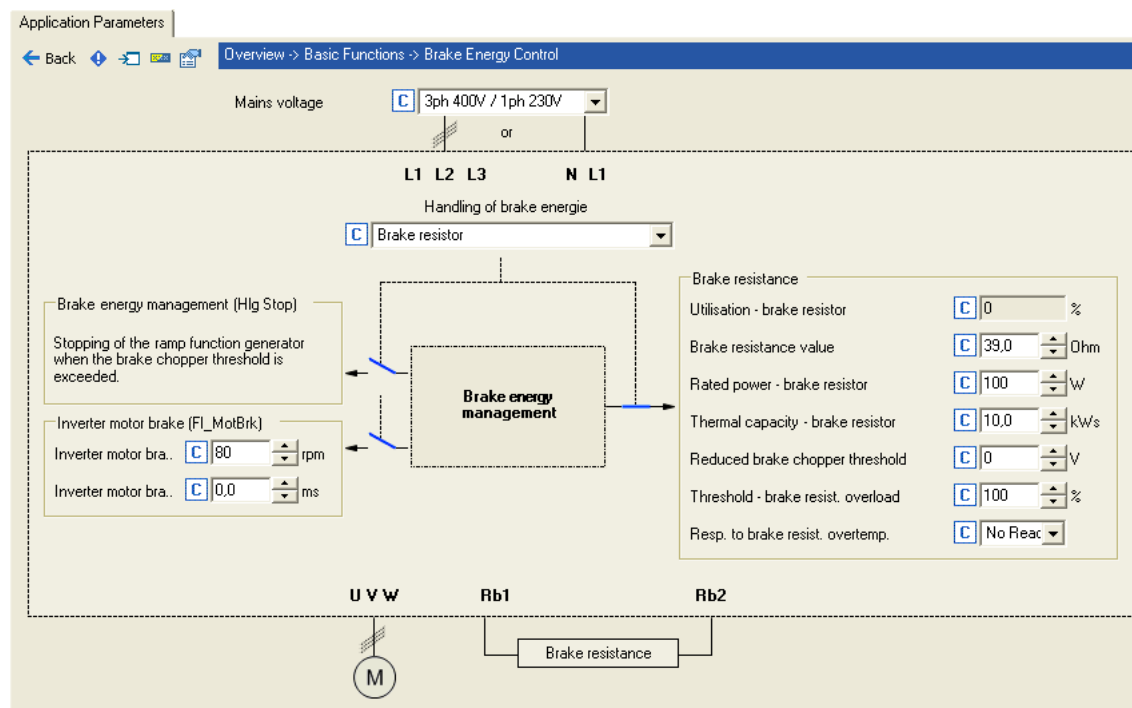


In order to install the regenerative module, follow the notes in the **8400 hardware manual**. The hardware manual has been stored in electronic form on the data carrier supplied with the 8400 controller.



Proceed as follows to open the dialog for parameterising the brake energy management:

1. »Engineer« Go to the *Project* view and select the 8400 TopLine controller.
2. Select the **Application parameters** tab from the *Workspace*.
3. Go to the *Overview* dialog level and click the "basic functions" button.
4. Go to the *Overview* → *basic functions* dialog box and click the **Brake energy management** button.



Short overview of the relevant parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C00173	Mains voltage	3ph 400 V / 1ph 230 V	
C00175	Brake energy management	R_Brake (brake resistance)	
Brake resistor			
C00133	Brake resistor utilisation	-	%
C00129	Brake resistance value	39.0	Ohm
C00130	Rated brake resistor power	100	W
C00131	Thermal capacity - brake resistor	10.0	kWs
C00174	Reduced brake chopper threshold	0	V
C00572	Threshold - brake resist. overload	100	%
C00574	Resp. to brake resist. overtemp.	No response	
Inverter motor brake			
C00987	Inverter motor brake: nAdd	80	rpm
C00988	Inverter motor brake: PT1 filter time	0.0	ms
Highlighted in grey = display parameter			

5.12.1 Setting the voltage source for braking operation

The voltage threshold for braking operation is set via the mains voltage ([C00173](#)) and the reduced brake chopper threshold ([C00174](#)). When this "brake chopper threshold" is exceeded, the response selected in [C00175](#) takes place in the DC bus. The selected function (e.g. use of a brake resistor) serves to dissipate energy in the DC bus and reduce the DC-bus voltage.

- The "brake chopper threshold" is preset as follows so that it is higher than the specified mains voltage ([C00173](#)):

C00173	Mains voltage		Brake chopper threshold	
	1-phase	3-phase	1-phase	3-phase
0	1ph 230V	3ph 400V	DC380V	DC725V
1	1ph 230V	3ph 440V	DC380V	DC735V
2	1ph 230V	3ph 480V	DC380V	DC775V
3	1ph 230V	3ph 500V	DC380V	DC790V

- This brake chopper threshold can be reduced by 0 ... 150 V by means of [C00174](#).



Stop!

The brake chopper threshold resulting from [C00173](#) and [C00174](#) must not exceed the stabilised DC-bus voltage!

Example:

- A 400 V device has a maximum mains voltage of 420 V AC.
 - Maximum stationary DC-bus voltage: $420 \text{ V AC} \cdot 1.414 = 594 \text{ V DC}$
 - [C00173](#) has been set with the selection "0" for 400 V AC mains.
- This means that [C00174](#) can be set to a maximum of 131 V DC (725 V DC - 594 V DC).

5.12.2 Selecting the response to an increase of the DC-bus voltage

If the brake chopper threshold resulting from [C00173](#) and [C00174](#) is exceeded in the DC bus, the reaction selected in [C00175](#) takes place (use of the brake resistor and/or stop of the ramp function generator and/or inverter-motor brake).

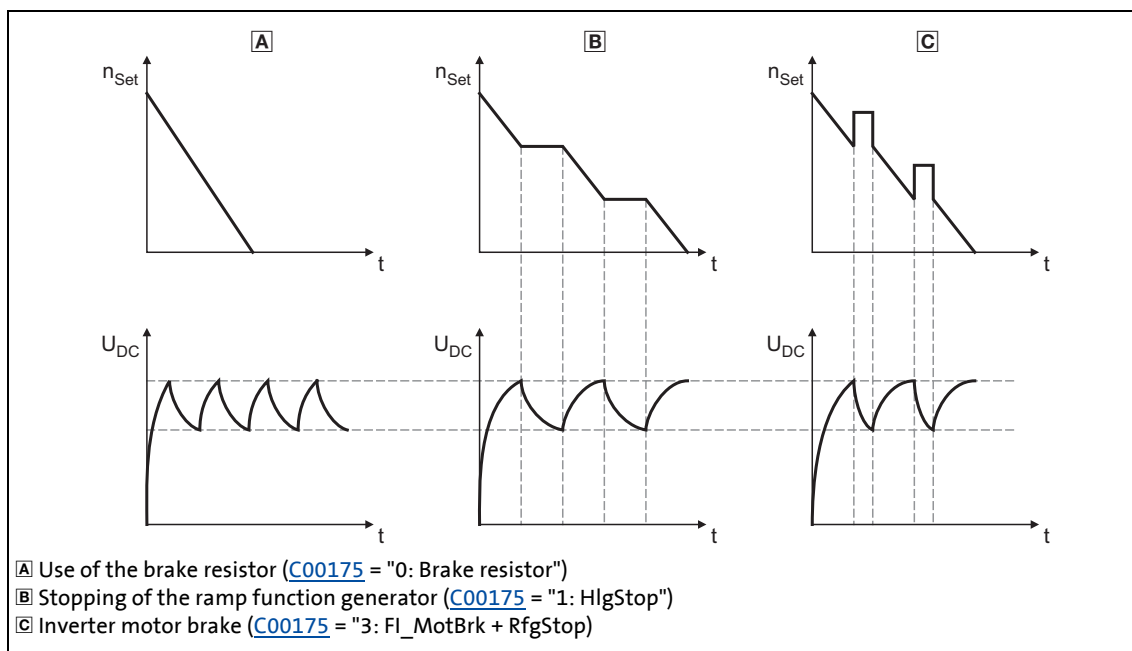
- Optimum following of the actual speed value until the speed setpoint is reached (e.g. the motor is stopped rapidly) is always achieved with the help of a brake resistor.
- Stopping the ramp function generator enables smoother deceleration with lower torque oscillation..
- The inverter-motor brake is available for selection in [C00175](#). This function enables rapid braking without a brake resistor. Torque oscillations can occur due to the traversing dynamics. ▶ [Inverter motor brake](#) (□ 286)



Stop!

- The two braking procedures "Stopping of the ramp function generator" and "Inverter motor brake" can only be used for speed-controlled applications without the influence of a position controller!
- When the "inverter motor brake" function is used, the [Motor load monitoring \(I2xt\)](#) is not adapted. If it is braked too frequently, there is a risk of the motor being thermally overloaded or the motor overload monitoring does not work properly!
- The "inverter motor brake" function must not be used with vertical conveyors (hoists) or with active loads!

The way in which the different braking procedures work is demonstrated schematically in the following illustration:



[5-29] Graph of the effective speed setpoint and the DC bus voltage during braking



Tip!

Independent of the selected motor control, all procedures given in [C00175](#) can be used. The actual speed value always follows the speed setpoint in an optimal way when a brake resistor is used.

If it is possible to dispense with exact adherence to the deceleration ramp in simple applications, selection of a braking method without an external brake resistor enables costs to be reduced due to the avoidance of having to use a brake resistor.

With the "inverter motor brake" function, an effective braking torque of 10 ... 20 % of the rated motor torque can be achieved.

A combination of all three braking procedures is also possible, e.g. for emergency braking if the brake resistor fails

([C00175](#) = "4: Brake resistor + FI_MotBrk + RfgStop").

5.12.2.1 Inverter motor brake

With this braking method, which can be selected as an alternative in [C00175](#), the regenerative energy in the motor is converted as a result of dynamic acceleration/deceleration with down-ramping of the ramp function generator..



Stop!

- This braking method only works without intervention of a position controller in the case of speed-controlled applications!
- When the "inverter motor brake" function is used, the [Motor load monitoring \(I2xt\)](#) is not adapted. If it is braked too frequently, there is a risk of the motor being thermally overloaded or the motor overload monitoring does not work properly!
- The "inverter motor brake" function must not be used with vertical conveyors (hoists) or with active loads!



Tip!

If no brake resistor is used, the DC injection brake can also be used for a braking process in addition to the "inverter motor brake" and "Stopping of the ramp function generator".

► [DC-injection braking](#) (📖 267)

In applications with high mass inertia and long braking times (> 2 s), we recommend the use of the DC injection brake.

- The DC injection brake provides for an oscillation-minimised braking. The braking process generally takes more time than the "inverter motor brake" function with an optimised setting. Moreover, the function is only recommended for braking to a standstill.

In the following cases we recommend the "inverter motor brake" function:

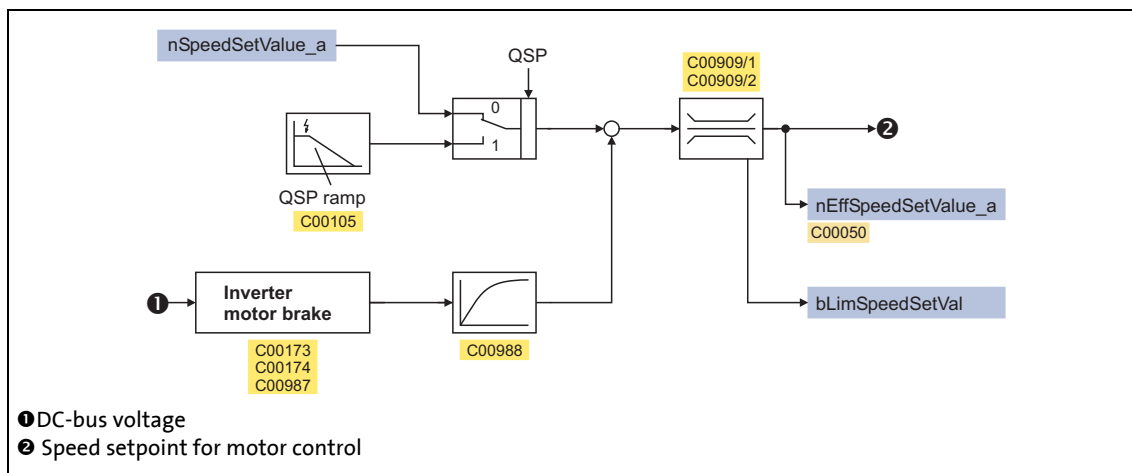
- With servo control (SC).
- For all applications that do not require braking to a standstill (e.g. braking to a lower speed setpoint) or the braking process can be interrupted by selecting a new speed setpoint.
- For applications with low mass inertias and a short braking time (< 1 s).
- For all applications where braking should be as quick as possible.

Operating mode of the inverter motor brake

The ramp function generator is stopped during acceleration. The speed set in [C00987](#) is added to the speed setpoint by means of a hysteresis-type 2-point DC bus voltage controller, whereby the sign of the current actual speed is taken into account. In addition, the ramp function generator is stopped during overvoltage.

If the DC bus voltage falls below a defined DC bus voltage potential of the hysteresis controller, the added speed is subtracted again and the ramp function generator is activated again.

The energy is converted into heat in the motor due to alternating instances of acceleration and deceleration as a result of this switching operation.



[5-30] Signal flow of the "Inverter motor brake" function

- In case of an asynchronous motor, the additive speed setpoint ([C00987](#)) should be 1 ... 4 times the slip of the machine:

$$C00987 \text{ [rpm]} = 1 \dots 4 \cdot (n_{\text{Sync}} \text{ [rpm]} - n_{\text{Rated}} \text{ [rpm]})$$

$$n_{\text{Sync}} \text{ [rpm]} = \frac{f_{\text{Rated}} \text{ Hz} \cdot 60}{p}$$

p = number of pole pairs
 n_{Rat} = Rated speed of the motor
 f_{Rat} = Rated frequency of the motor
 n_{Sync} = Synchronous speed of the motor

[5-31] Formula for calculating the additive speed setpoint for an asynchronous motor

- In case of a synchronous motor, the additive speed setpoint ([C00987](#)) should be 5 ... 20 % of the rated machine speed.

Short overview of the relevant parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C00173	Mains voltage	3ph 400V / 1ph 230V	
C00174	Reduc. brake chopper threshold	0	V
C00175	Resp. to brake resistor control	Brake resistor	
C00987	Inverter motor brake: nAdd • Speed lift which is connected in pulses to the brake rampe when the motor is braked.	80	rpm
C00988	Inverter motor brake: PT1 filter time • PT1 filter time for smoothing the speed lift which is added in pulses.	0.0	ms

**Note!**

When the "inverter motor brake" function is used, torque oscillations occur which may have a negative effect on the service life of the components of the mechanical drive train (e.g. gearbox).

- The extent of the occurring oscillations depends on the drive train (mass inertia, natural frequencies, etc.) and the function setting.
- We recommend optimising the "inverter motor brake" function for an oscillation-free operation as described in the following. Usually, this setting does not cause any torque oscillations which affect the service life of the gearbox.
- The settings of implementing a maximum acceleration ramp are only recommended if the inverter motor brake is used infrequently (e.g. in case of quick stop).

**How to set the "inverter motor brake" function for an oscillation-reduced operation:**

For V/f characteristic open-loop control/closed-loop control (VFCplus):

- Set reduced brake chopper threshold ([C00174](#)) to approx. 70 V.
- Set additive speed ([C00987](#)) to rated slip speed.
- Adapt the deceleration ramp so that the deceleration time is slightly below (10 ... 30 %) the deceleration time that can be realised with the inverter motor brake.

For sensorless vector control (SLVC) and servo control (SC):

- Set reduced brake chopper threshold ([C00174](#)) to approx. 50 V.
- Set additive speed ([C00987](#)) to 1 ... 2-fold rated slip speed.
- Adapt the deceleration ramp so that the deceleration time is slightly below (10 ... 30 %) the deceleration time that can be realised with the inverter motor brake.



How to set the "inverter motor brake" function for a maximum acceleration ramp:

For V/f characteristic open-loop control/closed-loop control (VFCplus):

- Set reduced brake chopper threshold ([C00174](#)) to approx. 70 V.
- Set additive speed ([C00987](#)) to 1,5 ... 2,5-fold rated slip speed.
- Adapt the deceleration ramp so that the deceleration time is slightly below (10 ... 30 %) the deceleration time that can be realised with the inverter motor brake.

For sensorless vector control (SLVC) and servo control (SC):

- Set reduced brake chopper threshold ([C00174](#)) to approx. 70 V.
- Set additive speed ([C00987](#)) to 2 ... 4-fold rated slip speed.
- Adapt the deceleration ramp so that the deceleration time is slightly below (10 ... 30 %) the deceleration time that can be realised with the inverter motor brake.

5.12.3 Avoiding thermal overload of the brake resistor

- Parameterisation of an error response in [C00574](#) and evaluation of the parameterised error message within the application or within the machine control system.
 - See chapter entitled "[Brake resistor monitoring \(I2xt\)](#)". ([□ 298](#))
- External interconnection using the thermal contact on the brake resistor (e.g. supply interruption via the mains contactor and activation of the mechanical brakes).

5.12.4 Control of multiple internal brake choppers in the DC-bus system

This function extension is available from version 12.00.00!

If an additional control signal is used, all internal brake choppers can be used in the DC-bus system to dissipate regenerative energy ("Master-slave operation").



Stop!

The integration of external brake choppers (e.g. brake chopper 9352) in the above-described "Master-slave operation" is not permissible since the voltage levels for the input and output of the external brake chopper are not suitable for the brake transistor control or, more precisely, for the output of the state of the brake transistor.

If the internal brake choppers of the DC-bus system are not sufficient, they should be replaced by an external brake chopper. It can be synchronised with other external brake choppers, if need be, so that simultaneous switch-on of all external brake choppers is ensured.



Note!

For trouble-free operation, the setting of the mains voltage in [C00173](#) must be identical for all controllers of the DC-bus system since this setting also influences the brake chopper threshold for switching on the brake chopper.

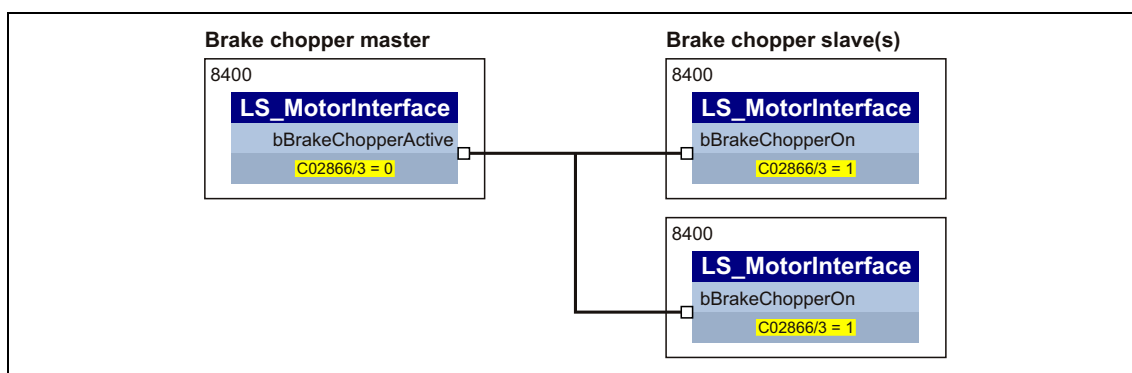
Functional principle

One of the controllers of the DC-bus system is assigned the role of the "brake chopper master".

- For logical reasons, the "brake chopper master" should be the most powerful controller.
- The "brake chopper master" controls its internal brake chopper via the DC-bus voltage as before. In addition, the "brake chopper master" transmits the *bBrakeChopperActive* status signal of its internal brake chopper control to the other controllers of the DC-bus system via fieldbus or digital output.

All other controllers of the DC-bus system are "brake chopper slaves".

- The "brake chopper slaves" have the *bBrakeChopperActive* status signal received from the "brake chopper master" connected to the *bBrakeChopperOn* control input.
- If the internal brake transistor of the "brake chopper master" is switched on, the internal brake transistors of the "brake chopper slaves" are switched on at the same time.



[5-32] Functional principle of the "Brake chopper master-slave operation" (simplified representation)

Procedure

1. Assign the role of the "brake chopper master" to one of the controllers of the DC-bus system.
2. Adapt the function block interconnection for the "brake chopper master" so that the *bBrakeChopperActive* status signal of the [LS_MotorInterface](#) SB is provided to the other controllers for controlling the internal brake chopper.
 - The *bBrakeChopperActive* signal can e.g. be output via port block to the fieldbus or via digital output.
 - A free output of the application block can be used to transfer the signal from application level to I/O level.
3. Configure all other controllers of the DC-bus system as "brake chopper slaves". Select "1: Yes" in [C2866/3](#) for these controllers.
 - With this setting, the brake chopper is not controlled via the DC-bus voltage anymore. Its control now depends on the *bBrakeChopperOn* control signal.
4. Adapt the function block interconnection for the "brake chopper slaves" so that the *bBrakeChopperActive* signal received from the "brake chopper master" is connected to the *bBrakeChopperOn* input of the [LS_MotorInterface](#) SB.
 - Depending on the output at the "brake chopper master", the signal must be read in e.g. via port block or digital input.
 - A free input of the application block can be used to transfer the signal from I/O level to application level.
 - If the digital inputs/outputs are used for transmitting the signal, they must be connected electrically accordingly.

**Note!**

If the brake chopper master-slave operation is activated, plausibility monitoring is carried out in the "brake chopper slaves":

- The brake transistor can only be switched on via the *bBrakeChopperOn* control signal if the DC-bus voltage is greater than the brake chopper threshold minus 40 V_{DC}.
- Exception: From a mains voltage of 513 V_{AC} (or 725 V_{DC}) and a mains voltage of 480 V or 500 V set in [C00173](#), the plausibility monitoring is not effective anymore.

Fast discharge of the DC bus

The *bBrakeChopperOn* control input of the "brake chopper master" can be optionally used for a fast discharge of the DC bus after the supply voltage has been switched off. The FB interconnection of the "brake chopper master" has to be adapted so that the *bBrakeChopperOn* control input of the SB [LS_MotorInterface](#) is connected to a digital bus or hardware signal (e.g. digital input on HIGH level).

**Note!**

Only the brake transistor of the "brake chopper master" is switched on with this function (max. 4 seconds, without interruption).

A complete discharge of the DC-bus cannot be achieved using this function!

From version 14.00.00, the limitation of the operating time can be deactivated to max. 4 seconds. For this purpose, set bit 1 to "1" in [C02864/1](#).

- We recommend this setting when this function is used in order to achieve a higher discharge of the DC bus - especially in case of high device power.

5.13 Monitoring

Many monitoring functions that are integrated into the controller can detect errors and thus protect the device/motor from damage or overload.

- Detailed information on the individual monitoring functions can be found in the following subchapters.

Monitoring	Response		Error message (with activated monitoring)
	Lenze setting	Configuration	
Device overload monitoring (Ixt)	Warning	C00604	oC5
Motor load monitoring (I2xt)	Warning	C00606	oC6
Motor overcurrent monitoring	Fault	-	oC7
Motor temperature monitoring (PTC)	Fault	C00585	oH3
Brake resistor monitoring (I2xt)	No Reaction	C00574	oC12
Motor phase failure monitoring	No Reaction	C00597	LP1
Motor phase error monitoring before operation	No Reaction	C02866/2	
Mains phase failure monitoring	Warning	C00565	Su02
Maximum current monitoring	No Reaction	C00609	oC10
Maximum torque monitoring	No Reaction	C00608	ot1
Motor speed monitoring	Fault	-	oS2

Parameterisable responses

If a monitoring function trips, the response set via the corresponding parameter is carried out. The following responses can be selected:

- "No response": Response/monitoring is deactivated.
- "Fault": Change of the operating status by a pulse inhibit of the power output stage.
- "Warning": Operating status of the controller remains unchanged. Only a message is entered into the Logbook of the controller.

Related topics:

- ▶ [Device state machine and device states](#) (📖 113)
- ▶ [Diagnostics & error management](#) (📖 673)
- ▶ [Basics on error handling in the controller](#) (📖 673)
- ▶ [Error messages of the operating system](#) (📖 696)

5.13.1 Device overload monitoring (Ixt)

[C00064/1...3](#) displays the device utilisation (ixt) in [%] in different time intervals:

Parameter	Info
C00064/1	Device utilisation (Ixt) <ul style="list-style-type: none"> Maximum value of pulse utilisation (C00064/2) and permanent utilisation (C00064/3).
C00064/2	Device utilisation (Ixt) 15s <ul style="list-style-type: none"> Pulse utilisation over the last 15 seconds (only for loads >160 %).
C00064/3	Device utilisation (Ixt) 3 min <ul style="list-style-type: none"> Permanent utilisation over the last 3 minutes.
Highlighted in grey = display parameter	

- If the device utilisation reaches the switch-off threshold set in [C00123](#):
 - The error response set in [C00604](#) will be carried out (Lenze setting: "Warning").
 - The "[oC5: Ixt overload](#)" error message will be entered into the Logbook.
 - The *bMctrlIxtOverload* status output of the [LS_DeviceMonitor](#) system block will be set to TRUE.
- A setting of [C00604](#) = "0: No Reaction" deactivates the monitoring.

5.13.2 Motor load monitoring (I2xt)

The Inverter Drives 8400 are provided with a simple, sensorless, thermal I²xt motor monitoring of self-ventilated standard motors which is based on a mathematical model.

- [C00066](#) displays the calculated motor load in [%].
- If the calculated motor load reaches the motor load setting ([C00120](#)):
 - The error response set in [C00606](#) will be carried out (Lenze setting: "Warning").
 - The "[oC6: I2xt motor overload](#)" error message will be entered into the Logbook.
 - The *bMctrlI2xtOverload* status output of the [LS DeviceMonitor](#) system block will be set to TRUE.
- A setting of [C00606](#) = "0: No Reaction" deactivates the monitoring.



Stop!

I²xt motor monitoring does not provide full motor protection!

As the motor utilisation calculated in the thermal motor model is lost after mains switching, for instance the following operating states cannot be detected correctly:

- Restarting (after mains switching) of a motor that is already very hot.
- Change of the cooling conditions (e.g. cooling air flow interrupted or too warm).

A full motor protection requires additional measures as e.g. the evaluation of temperature sensors that are located directly in the winding or the use of thermal contacts.

For the installation according to UL or UR, the safety instructions provided in the hardware manual must be observed! Among other things, the activation of the motor overload monitoring (I2xt) is required here.



Note!

From version 12.00.00, the thermal motor load displayed in [C00066](#) can be pre-initialised when the device is connected to the mains, optionally using a fixed value or the value used last at the time when the device was switched off. The desired initialisation is selected in [C00122](#). In the Lenze setting of [C00122](#), the behaviour remains unchanged (no initialisation).

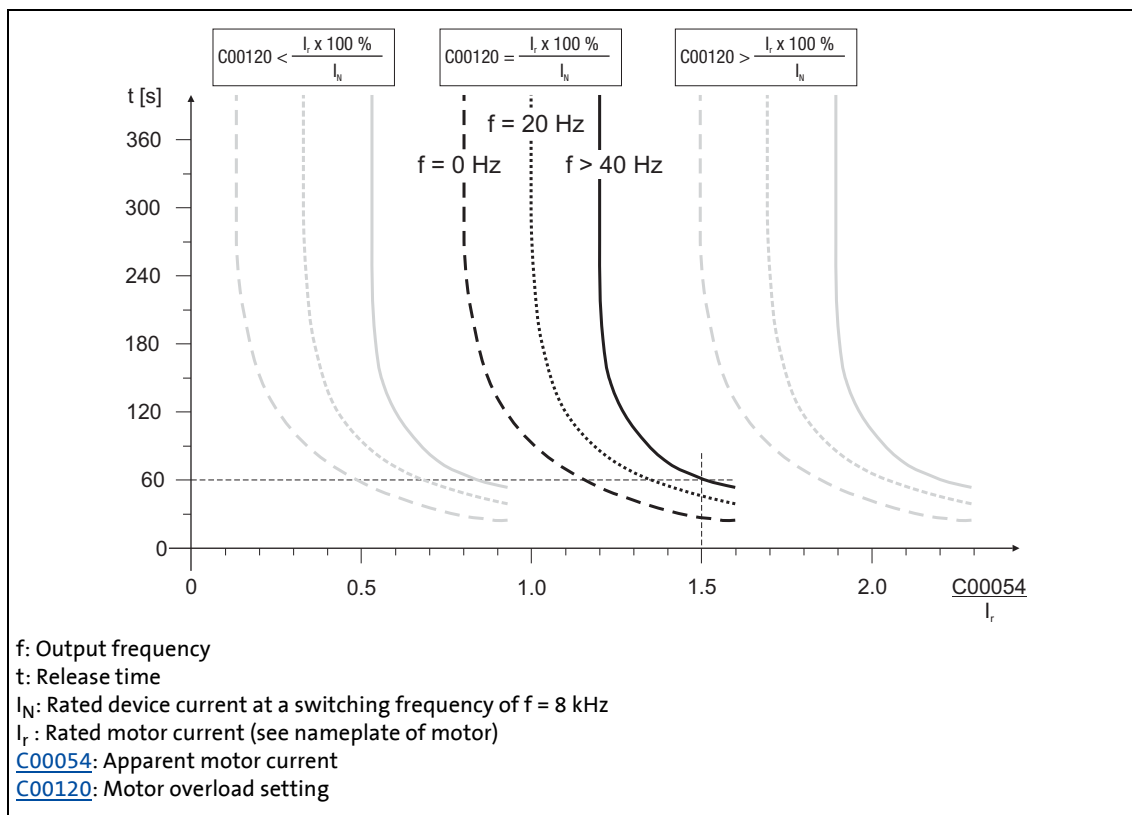
Adjustment of the motor utilisation meter

The motor utilisation meter for indicating the motor load in [C00066](#) begins to count when the apparent motor current ([C00054](#)) is greater than the motor overload setting ([C00120](#)).

The overload threshold ([C00120](#)) is to be set as follows:

$$C00120 = \frac{\text{Rated motor current (C00088)}}{\text{Rated device current (C00098)}} \cdot 100 \%$$

- If you reduce [C00120](#) starting from the calculated value, the motor utilisation meter will already be counted up before the rated overload threshold is reached.
- If you increase [C00120](#) starting from the calculated value, the motor utilisation meter will not be counted up until the rated overload threshold is reached.



[5-33] Tripping characteristic of the I^2xt monitoring

Example in Figure [5-33]:

$$C00120 = I_r / I_{\text{rated}} \times 100 \%$$

$$C00054 = 150 \% \text{ rated motor current}$$

- After approx. 60 seconds, [C00066](#) has reached the final value (100 %) at output frequencies $f > 40 \text{ Hz}$.
- The controller outputs the "[oC6: I2xt overload motor](#)" error message and triggers the response set in [C00606](#) (default setting: "Warning").

**Tip!**

- If forced ventilated motors are used, a premature response of the overload threshold can be avoided by deactivating this function if necessary ([C00606](#) = "0: No Reaction").
- The current limits set in [C00022](#) and [C00023](#) influence the I^2t calculation only in an indirect way. However, the operation of the motor at maximum possible load can be averted. ▶ [Defining current and speed limits](#) (□ 154)

5.13.3 Motor overcurrent monitoring

The ultimate motor current to be parameterised in [C00939](#) is a limit value to protect the motor from destruction, influence of the rated data and demagnetisation.

- This limit value must not be travelled cyclically in the drive process.
- If the instantaneous value of the motor current exceeds the limit value set in [C00939](#), the error response "Fault" occurs to protect the motor and the error message "[oC7: Motor overcurrent](#)" is entered into the logbook.
- The maximum currents to be parameterised in [C00022](#) and [C00023](#) should have a sufficient distance to this limit value.

**Note!**

If a Lenze motor is selected from the catalogue whose plant parameters are transferred into the controller, the setting of the maximum current in [C00022](#) and [C00023](#) will automatically be adapted to the selected motor.

Related topics:

- ▶ [Maximum current monitoring](#) (□ 303)

5.13.4 Motor temperature monitoring (PTC)

For detecting and monitoring of the motor temperature, a PTC thermistor (DIN 44081/DIN 44082) or a thermal contact (NC contact) can be connected to the terminals X106/T1 and X106/T2.



Stop!

- The controller can only evaluate one PTC thermistor!
Do not connect several PTC thermistors in series or parallel.
- If several motors are operated on one controller, use thermal contacts (NC contacts) connected in series.
- To achieve full motor protection, an additional temperature monitoring with separate evaluation must be installed.



Note!

- In the Lenze setting ([C00585](#) = "1: Fault"), motor temperature monitoring is activated!
- There is a wire jumper between the terminals X106/T1 and X106/T2 by default.
- Lenze three-phase AC motors are provided with a thermal contact on delivery.

- If $1.6\text{ k}\Omega < R < 4\text{ k}\Omega$ at the terminals X106/T1 and X106/T2, the monitoring will respond, see functional test below.
- If the monitoring responds:
 - The error response set in [C00585](#) is activated (Lenze setting: "Fault").
 - The "[oH3: Motor temperature \(X106\) triggered](#)" error message is entered into the Logbook.
 - The *bMctrlMotorPtc* status output of the [LS DeviceMonitor](#) system block is set to TRUE.
- A setting of [C00585](#) = "0: No Reaction" deactivates the monitoring.



Tip!

We recommend to always activate the PTC input when using motors which are equipped with PTC thermistors or thermostats. This prevents the motor from being destroyed by overheating.

Functional test

Connect a fixed resistor to the PTC input:

- $R > 4\text{ k}\Omega$: Fault message must be activated.
- $R < 1\text{ k}\Omega$: Fault message must not be activated.

5.13.5 Brake resistor monitoring (I²xt)

Due to the converted braking power, the brake resistor is thermally stressed and can even be thermally destroyed by excessive braking power.

The monitoring of the I²xt utilisation of the controller serves to protect the brake resistor. It acts in proportion to the converted braking power.



Danger!

In the Lenze setting ([C00574](#) = "0: No Reaction"), the response of the monitoring function does not stop the braking process!

In particular for applications such as hoists or applications with a DC-bus connection, it must be checked if a stopping of the braking process due to a setting of [C00574](#) = "1: Fault" is permissible.



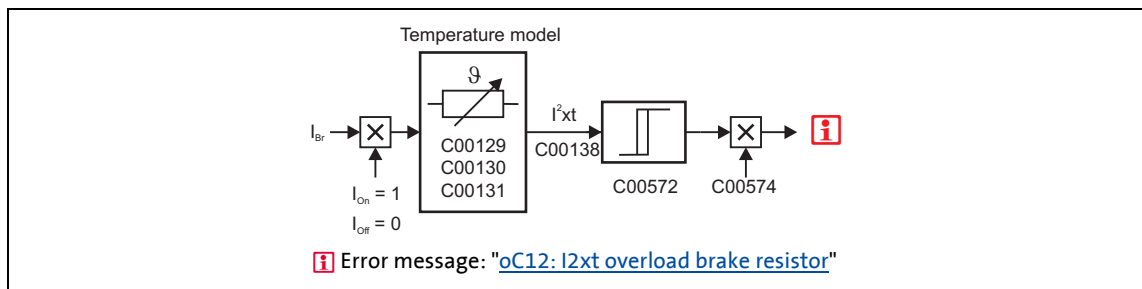
Stop!

Implement appropriate protective measures against thermal overload of the brake resistor!

Examples:

- Parameterisation of an error response in [C00574](#) and evaluation of the parameterised error message within the application or the machine control system.
 - Interruption of the mains supply by means of the temperature contact at the brake resistor and a simultaneous activation of the mechanical brake.
-
- If the I²xt utilisation reaches the switch-off threshold set in [C00572](#):
 - The error response set in [C00574](#) will take place.
 - The "[oC12: I2xt brake resistor overload](#)" error message is entered into the Logbook.
 - The *bMctrlBrakeChopperFault* status output of the [LS_DeviceMonitor](#) system block will be set to TRUE.
 - If the system is dimensioned correctly, the monitoring should not be activated. If individual pieces of rated data of the actually connected brake resistor are not known, they have to be identified.
 - If the DC-bus voltage exceeds the overvoltage threshold due to a braking energy that is too high, the monitoring for overvoltage in the DC bus is activated ("OU: DC-bus overvoltage" error message).
 - Apart from the threshold of the I²xt utilisation that can be set in [C00572](#), there is the switching threshold of the brake transistor which results from the mains voltage ([C00173](#)) and the reduced brake chopper threshold ([C00174](#)).

Temperature model



[5-34] Signal flow for monitoring the brake resistor

The monitoring function calculates the braking current I_{Br} from the current DC-bus voltage U_{DC_act} and the brake resistance parameterised in [C00129](#):

$$I_{Br} = \frac{U_{DC_act}}{C00129}$$

**Note!**

The monitoring function can also be triggered due to a value entered in [C00129](#) although a brake resistor is not even connected.

- The calculation considers the thermal utilisation of the brake resistor based on the following parameters:
 - Resistance value ([C00129](#))
 - Continuous power ([C00130](#))
 - Thermal capacity ([C00131](#))
- In the Lenze setting these parameters are preset with the corresponding power-adapted Lenze brake resistor.
- [C00133](#) indicates the calculated utilisation of the brake resistor in [%].
 - A utilisation of 100 % corresponds to the continuous power of the brake resistor depending on the maximally permissible temperature limit.

Related topics:

► [Braking operation/brake energy management](#) (281)

5.13.6 Motor phase failure monitoring

**Note!**

In the Lenze setting ([C00597](#) = "0: No Reaction"), the motor phase failure monitoring is not activated!

In the case of a synchronous motor,

- the motor phase failure monitoring is basically deactivated. (Due to the low no-load current, the monitoring would be permanently activated.)
- only the [Motor phase error monitoring before operation](#) is active (for Lenze setting [C2866/2](#) = "1: Yes").

In order to safely detect the failure of a motor phase, a certain motor current must flow for the current sensor system. Thus, the response set in [C00597](#) (Lenze setting: "No Reaction") is caused after a delay time of maximally 2 s after controller enable if a current-carrying motor phase U, V, W fails or if motor connection is missing. If the current threshold value set in [C00599](#) is already exceeded within the delay time, the motor phase failure monitoring starts from this point in time.

The monitoring mode checks the current flow for each motor phase as a function of the commutation angle. Monitoring is activated if a commutation angle of approx. 140° is covered without the current set in [C00599](#) being exceeded. Monitoring is activated at an output frequency of 0 Hz if none of the three motor phases reaches the threshold value set in [C00599](#).

- If the motor phase failure monitoring is tripped:
 - The response set in [C00597](#) will take place.
 - The error message "[LP1: Motor phase failure](#)" is entered into the logbook.
 - The *bMctrlMotorPhaseFault* status output of the [LS DeviceMonitor](#) system block is set to TRUE.

**Note!**

If an error response of "1: Fault" is set in [C00597](#), the *bMctrlMotorPhaseFault* status output of the [LS DeviceMonitor](#) SB will be set to TRUE for only 1 second in the event of a motor phase failure because it is no longer possible to detect a motor phase fault via the error response with a pulse inhibit. However, the Logbook and [C00561/3...5](#) still display the cause of the motor phase failure.

- The motor phase failure monitoring is inactive if
 - a controller inhibit is set,
 - connection to a rotating machine is carried out (flying restart circuit or connection to actual speed value),
 - an error is pending due to a DC-bus overvoltage ("[OU](#)"),
 - motor parameter identification is carried out,
 - DC-injection braking is active.

5.13.7 Motor phase error monitoring before operation

This function extension is available from version 02.00.00!

This extended motor phase failure monitoring can both detect a phase failure on the basis of test signals and check for the existence of the motor.

- The "motor phase error monitoring before operation" is only directly active after controller enable if
 - an error response is set in [C00597](#) **AND**
 - the motor phase error monitoring is switched on ([C2866/2](#) = "1: Yes").
- The following parameters show the cause of the motor phase failure:
 - [C00561/3](#): Motor phase U
 - [C00561/4](#): Motor phase V
 - [C00561/5](#): Motor phase W



Note!

The motor phase error monitoring before operation must not be connected to a rotating or coasting machine (high compensation currents and effect of the DC injection braking).

- In case of motor control with feedback, no motor phase error monitoring is executed if the actual speed value is > 10 rpm.
- In case of motor control without feedback, the user must ensure that the motor phase error monitoring will only be executed if the speed is 0.

If the motor is at quick stop and the brake is applied, no motor phase error monitoring is executed when quick stop is deactivated (same with "0" speed and applied brake).

If the rated current of the connected motor is lower than 10 % of the rated device current, the motor phase error monitoring can be activated although no motor phase error has occurred. In this case, the motor phase error monitoring must be switched off before operation ([C2866/2](#) = "0: No").

**Note!****With automatic brake control:**

In case of automatic brake control, the brake will only be released if no motor phase failure exists and the magnetisation of the field-oriented control types is completed.

With manual brake control:

In case of manual brake control and forced release of the brake, the brake will be controlled directly as before.

The user himself must ensure that the brake will only be opened if all of the following conditions are met:

- Motor phase failure monitoring ([C00597](#)) and motor phase error monitoring before operation ([C2866/2](#)) are active.
- The controller is enabled (controller enable).
- The *bMctrlMotorPhaseFault* status output of the SB [LS DeviceMonitor](#) is set to FALSE.
- Bit 10 of the *MCTRL_Status3* status word must be set to 0 before the brake opening is triggered.
 - When the controller is enabled, this bit is set to 1 and will not be set to 0 again before the "Motor phase error monitoring before operation" is successfully completed.
 - The *MCTRL_Status3* status word can be integrated in the application via configuration parameters (e.g. [C00620](#)) (*MCTRL_Status3* = selection 34906 in [Selection list - analog signals](#)).

5.13.8 Mains phase failure monitoring



Stop!

Under load, the mains input of a three-phase controller can be destroyed if the device is only supplied by two phases (e.g. if a mains phase fails).

The drive controller has a simple mains-phase failure detection function with which a mains phase failure can be detected under load.

- In the case of power-adapted machines, approx. 50 % of the rated motor power must be exceeded so that a main-phase failure can be detected.
- If the mains phase failure monitoring is tripped:
 - The error response set in [C00565](#) will be carried out (Lenze setting: "Warning").
 - The "[Su02: One mains phase is missing](#)" error message will be entered into the logbook.
 - The *bMctrlMainsFault* status output of the [LS_DeviceMonitor](#) system block will be set to TRUE.

5.13.9 Maximum current monitoring



Note!

In the Lenze setting ([C00609](#) = "0: No Reaction"), the maximum current monitoring is not activated!

If a Lenze motor is selected from the catalogue whose plant parameters are transferred into the controller, the setting of the maximum current in [C00022](#) and [C00023](#) will automatically be adapted to the selected motor.

If the parameterised maximum current is reached, the response set in [C00609](#) is triggered (Lenze setting: "0: No Reaction").

If the activated monitoring is tripped:

- The "[oC10: Maximum current reached](#)" error message is entered in the logbook.

Related topics:

► [Motor overcurrent monitoring](#) (📖 296)

5.13.10 Maximum torque monitoring



Note!

In the Lenze setting ([C00608](#) = "0: No Reaction"), the maximum torque monitoring is not activated!

If the maximum possible torque [C00057](#) is reached at the motor shaft, the response set in [C00608](#) will be carried out (Lenze setting: "0: No Reaction").

If the activated monitoring is tripped:

- The "[ot1: Maximum torque reached](#)" error message is entered into the logbook.
- The *bMctrlTorqueMax* status output of the [LS DeviceMonitor](#) system block will be set to TRUE.

5.13.11 Motor speed monitoring

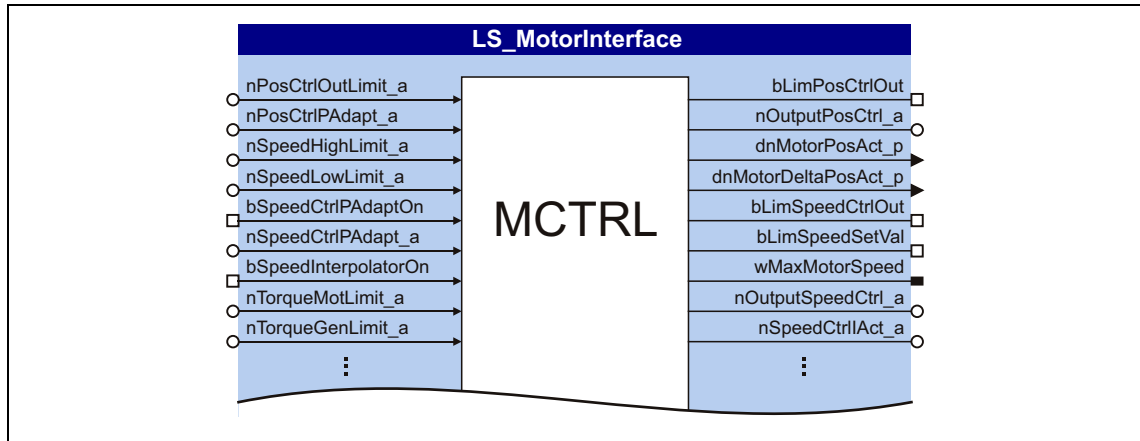
[This function extension is available from version 02.00.00!](#)

If the drive reaches the maximally permissible motor speed ([C00965](#)):

- The error response "Fault" occurs, i.e. the inverter is inhibited and the motor changes to torque-free operation (coasts down).
- The error message "[oS2: Max. motor speed reached](#)" is entered into the logbook.

5.14 Internal interfaces | System block "LS_MotorInterface"

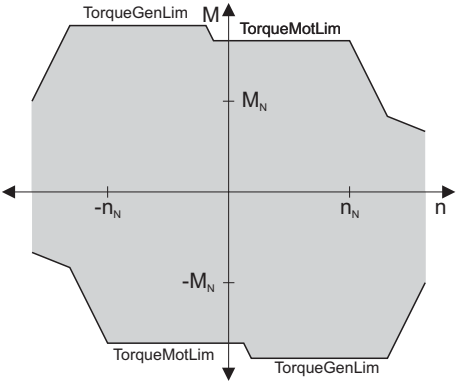
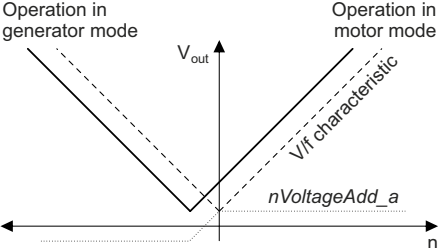
The **LS_MotorInterface** system block provides the internal interfaces to the driving machine in the function block editor.




[5-35] LS_MotorInterface system block (excerpt)

Inputs

Identifier DIS code data type	Information/possible settings				
nPosCtrlOutLimit_a C00830/21 INT	Limitation of the position controller output <ul style="list-style-type: none"> Scaling: 16384 \equiv 100 % reference speed (C00011) 				
nPosCtrlPAdapt_a C00830/20 INT	Adaptation of the position controller gain <ul style="list-style-type: none"> Scaling: 16384 \equiv 100 % Vp (C00254) 				
nSpeedHighLimit_a C00830/88 INT	Upper speed limit for the speed limitation <ul style="list-style-type: none"> During torque-controlled operation only (<i>bTorquemodeOn</i> = TRUE) Scaling: 16384 \equiv 100 % reference speed (C00011) <p>Note: For a correct function of the speed limitation in both direction, the following applies: The speed limitation operates with a internal hysteresis of 50 rpm. The upper or lower speed limit resulting from the settings has to be higher than this hysteresis!</p>				
nSpeedLowLimit_a C00830/23 INT	Lower speed limit for speed limitation <ul style="list-style-type: none"> During torque-controlled operation only (<i>bTorquemodeOn</i> = TRUE) Scaling: 16384 \equiv 100 % reference speed (C00011) <p>Note: For a correct function of the speed limitation in both direction, the following applies: The speed limitation operates with a internal hysteresis of 50 rpm. The upper or lower speed limit resulting from the settings has to be higher than this hysteresis!</p>				
bSpeedCtrlPAdaptOn C00833/69 BOOL	Adaptation of the speed controller gain <table border="1"> <tr> <td>FALSE</td><td>Deactivate adaptive adaptation.</td></tr> <tr> <td>TRUE</td><td>Activate adaptive adaptation.</td></tr> </table>	FALSE	Deactivate adaptive adaptation.	TRUE	Activate adaptive adaptation.
FALSE	Deactivate adaptive adaptation.				
TRUE	Activate adaptive adaptation.				
nSpeedCtrlPAdapt_a C00830/25 INT	Adaptation of the speed controller gain <ul style="list-style-type: none"> Scaling: 16384 \equiv 100 % Vp (C00070) 				
bSpeedInterpolatorOn C00833/28 BOOL	Speed setpoint interpolation <table border="1"> <tr> <td>FALSE</td><td>Deactivate interpolation</td></tr> <tr> <td>TRUE</td><td>Activate interpolation</td></tr> </table>	FALSE	Deactivate interpolation	TRUE	Activate interpolation
FALSE	Deactivate interpolation				
TRUE	Activate interpolation				

Identifier DIS code data type	Information/possible settings				
nTorqueMotLimit_a C00830/29 INT nTorqueGenLimit_a C00830/28 INT	<p>Torque limitation in motor mode and in generator mode</p> <ul style="list-style-type: none"> The drive cannot output a higher torque in motor/generator mode than set here. The applied values (any polarity) are internally interpreted as absolute values. If V/f characteristic control (VFCplus) is selected, limitation is <u>indirectly</u> performed via a so-called I_{max} controller. If sensorless vector control (SLVC) or servo control (SC) is selected, limitation has a <u>direct</u> effect on the torque-producing current component. Scaling: $16384 \equiv 100\% M_{max}$ (C00057) <p>Torque limits in motor and generator mode:</p> 				
bTorqueInterpolatorOn C00833/29 BOOL	<p>Torque setpoint interpolation</p> <table border="1"> <tr> <td>FALSE</td><td>Deactivate interpolation</td></tr> <tr> <td>TRUE</td><td>Activate interpolation</td></tr> </table>	FALSE	Deactivate interpolation	TRUE	Activate interpolation
FALSE	Deactivate interpolation				
TRUE	Activate interpolation				
nVoltageAdd_a C00830/31 INT	<p>Additive voltage impression</p> <ul style="list-style-type: none"> This process input serves to specify an additional setpoint for the motor voltage. If there are, for instance, different loads at the motor output end, it is possible to apply a voltage boost at the starting time. If the value is negative, the voltage is reduced. Scaling: $16384 \equiv 1000\text{ V}$ <p>This process signal also serves to implement a load adaptation. Example of V/f characteristic control (VFCplus): Adaptation of the voltage characteristic as a function of the load in motor mode/in generator mode in case of CW/CCW rotation</p>  <ul style="list-style-type: none"> CW rotation in motor mode: Increase voltage CCW rotation in generator mode: Reduce voltage <p>STOP Stop! Values selected too high may cause the motor to heat up due to the resulting current!</p>				
bAutoBoostOn C00833/32 BOOL	Reserved				

Identifier DIS code data type	Information/possible settings				
nBoost_a C00830/26 INT	<p>Process signal for the V_{\min} boost</p> <ul style="list-style-type: none"> This signal is added to C00016 and has thus an increasing or decreasing effect. This signal serves to implement a load-dependent Vmin boost to improve the torque behaviour in different load states, as for instance in case of operation in generator or motor mode. Scaling: $16384 \equiv 100\%$ rated device voltage V_{FU} (400 V or 230 V) <p>► Adapting the Vmin boost (166)</p>				
	<p> Stop!</p> <p>Values selected too high may cause the motor to heat up due to the resulting current!</p>				
bPosCtrlOn C00833/27 BOOL	<p>Position/angle control</p> <table> <tr> <td>FALSE</td><td>Deactivate position/angle control.</td></tr> <tr> <td>TRUE</td><td>Activate position/angle control.</td></tr> </table>	FALSE	Deactivate position/angle control.	TRUE	Activate position/angle control.
FALSE	Deactivate position/angle control.				
TRUE	Activate position/angle control.				
bDeltaPosOn C00833/35 BOOL	<p>Activate position difference as setpoint selection</p> <ul style="list-style-type: none"> In order to position the motor shaft, the position control function can work within the motor control function with the absolute position setpoint <i>dnPosSetValue_p</i> or alternatively with the speed setpoint <i>nSpeedSetValue_a</i> and the position difference <i>dnDeltaPos_p</i>. <table> <tr> <td>FALSE</td><td>Positioning with position setpoint <i>dnPosSetValue_p</i>.</td></tr> <tr> <td>TRUE</td><td>Positioning with speed setpoint <i>nSpeedSetValue_a</i> and position difference <i>dnDeltaPos_p</i>.</td></tr> </table>	FALSE	Positioning with position setpoint <i>dnPosSetValue_p</i> .	TRUE	Positioning with speed setpoint <i>nSpeedSetValue_a</i> and position difference <i>dnDeltaPos_p</i> .
FALSE	Positioning with position setpoint <i>dnPosSetValue_p</i> .				
TRUE	Positioning with speed setpoint <i>nSpeedSetValue_a</i> and position difference <i>dnDeltaPos_p</i> .				
dnDeltaPos_p C00834/4 DINT	<p>Position difference (following error input)</p> <ul style="list-style-type: none"> Difference between setpoint position and actual position in [increments] Is used for position control if <i>bDeltaPosOn</i> = TRUE. Scaling: $65535 \equiv 1$ revolution 				
dnPosSetValue_p C00834/5 DINT	<p>Absolute position setpoint in [increments]</p> <ul style="list-style-type: none"> Is used for position control if <i>bDeltaPosOn</i> = FALSE. Scaling: $65535 \equiv 1$ revolution 				
bPosDerivativeOn C00833/67 BOOL	<p>Create a setpoint for the speed controller from the position setpoint</p> <ul style="list-style-type: none"> For highly dynamic control systems, the setpoint for the speed controller can be created from the absolute position setpoint <i>dnPosSetValue_p</i> instead of the speed setpoint <i>nSpeedSetValue_a</i> ► Position control/additive speed specification <table> <tr> <td>TRUE</td><td> <p>Create a speed setpoint from the position setpoint.</p> <ul style="list-style-type: none"> The absolute position setpoint <i>dnPosSetValue_p</i> is differentiated and a speed value is created which is the setpoint for the speed controller. Internal limitation of 65536 increments/ms. </td></tr> </table>	TRUE	<p>Create a speed setpoint from the position setpoint.</p> <ul style="list-style-type: none"> The absolute position setpoint <i>dnPosSetValue_p</i> is differentiated and a speed value is created which is the setpoint for the speed controller. Internal limitation of 65536 increments/ms. 		
TRUE	<p>Create a speed setpoint from the position setpoint.</p> <ul style="list-style-type: none"> The absolute position setpoint <i>dnPosSetValue_p</i> is differentiated and a speed value is created which is the setpoint for the speed controller. Internal limitation of 65536 increments/ms. 				
bMotorRefOffsetOn C00833/68 BOOL	<p>Set home position ("referencing on the fly")</p> <table> <tr> <td>TRUE</td><td>Set home position to value <i>dnMotorRefOffset_p</i>.</td></tr> </table>	TRUE	Set home position to value <i>dnMotorRefOffset_p</i> .		
TRUE	Set home position to value <i>dnMotorRefOffset_p</i> .				
dnMotorRefOffset_p C00834/6 DINT	<p>Home position in [increments]</p> <ul style="list-style-type: none"> Scaling: $65535 \equiv 1$ revolution 				
bQspOn C00833/33 BOOL	<p>Quick stop</p> <table> <tr> <td>FALSE</td><td>Deactivate quick stop</td></tr> <tr> <td>TRUE</td><td>Activate quick stop</td></tr> </table>	FALSE	Deactivate quick stop	TRUE	Activate quick stop
FALSE	Deactivate quick stop				
TRUE	Activate quick stop				
nPWMAngleOffset_a C00830/32 INT	<p>Angle step change of output voltage phasor</p> <ul style="list-style-type: none"> Scaling: $65535 \equiv 1$ revolution 				
bSpeedCtrlOn C00833/31 BOOL	<p>Directly set the I-component of speed controller</p> <ul style="list-style-type: none"> In order to statically specify a minimum torque, e.g. when a load is being lifted. <table> <tr> <td>TRUE</td><td>Set the I-component of the speed controller to the value <i>nSpeedCtrlI_a</i>.</td></tr> </table>	TRUE	Set the I-component of the speed controller to the value <i>nSpeedCtrlI_a</i> .		
TRUE	Set the I-component of the speed controller to the value <i>nSpeedCtrlI_a</i> .				

Identifier DIS code data type	Information/possible settings				
nSpeedCtrlI_a C00830/24 INT	Value of the speed controller integrator <ul style="list-style-type: none"> Scaling depends on the selected motor control: <ul style="list-style-type: none"> V/f control (VFCplus + encoder): 16384 \equiv 100 % reference speed (C00011) Servo control (SC) or vector control (SLVC): 16384 \equiv 100 % M_{\max} (C00057) 				
nSpeedSetValue_a C00830/22 INT	Speed setpoint <ul style="list-style-type: none"> Scaling: 16384 \equiv 100 % reference speed (C00011) 				
bTorquemodeOn C00833/30 BOOL	Selection: Speed/Torque control <table> <tr> <td>FALSE</td><td>Speed control with torque limitation</td></tr> <tr> <td>TRUE</td><td>Torque control with speed limitation</td></tr> </table>	FALSE	Speed control with torque limitation	TRUE	Torque control with speed limitation
FALSE	Speed control with torque limitation				
TRUE	Torque control with speed limitation				
nTorqueSetValue_a C00830/27 INT	Torque setpoint / additive torque <ul style="list-style-type: none"> Scaling: 16384 \equiv 100 % M_{\max} (C00057) 				
bDcBrakeOn C00833/34 BOOL	Activate DC injection brake <table> <tr> <td>FALSE</td><td>Deactivate DC-injection braking</td></tr> <tr> <td>TRUE</td><td>Activate DC-injection braking</td></tr> </table>	FALSE	Deactivate DC-injection braking	TRUE	Activate DC-injection braking
FALSE	Deactivate DC-injection braking				
TRUE	Activate DC-injection braking				
bTorqueLimitAdaptOn C00833/98 BOOL	Adaptation of torque limitation <table> <tr> <td>TRUE</td><td>Activate adaptation of torque limitation.</td></tr> </table>	TRUE	Activate adaptation of torque limitation.		
TRUE	Activate adaptation of torque limitation.				
nTorqueLimitAdapt_a C00830/70 INT	Value for adaptation of torque limitation <ul style="list-style-type: none"> Scaling: 16384 \equiv 100 % $nTorqueMotLimit_a$ and $nTorqueGenLimit_a$ 				
nInertiaAdapt_a C00830/96 INT (from version 12.00.00)	Adaptation of the moment of inertia <ul style="list-style-type: none"> This process signal can be used during the process to dynamically control the percentage of the variable moment of inertia (e.g. a reel) set in C00919/1 which is to be considered for setpoint feedforward control. Scaling: 16384 \equiv 100 % moment of inertia - process (C00919/1) 				
bBrakeChopperOn C00833/130 BOOL (from version 12.00.00)	Switch on the internal brake chopper as "brake chopper slave" (C02866/3 = "1: Yes") when the controller is configured <p>► Control of multiple internal brake choppers in the DC-bus system (□ 289)</p> <table> <tr> <td>TRUE</td><td>Switch on internal brake chopper.</td></tr> </table>	TRUE	Switch on internal brake chopper.		
TRUE	Switch on internal brake chopper.				
nSpeedSetValueInertia_a C00830/97 INT (from version 12.00.00)	Input for differential setpoint feedforward control (torque feedforward control) <ul style="list-style-type: none"> If the selection "1: nSpeedSetValueInertia_a" is set in C00654/1, this process signal can be used to preselect any input value (e.g. setpoint of the position or process controller) for torque feedforward control. Scaling: 16384 \equiv 100 % reference speed (C00011) 				
bVfcEcoDisable C00833/131 BOOL (from version 13.00.00)	Deactivate energy optimisation for VFCplusEco <p>► Improving the behaviour at high dynamic load changes</p> <table> <tr> <td>FALSE</td><td>Activate energy optimisation.</td></tr> <tr> <td>TRUE</td><td>Deactivate energy optimisation.</td></tr> </table>	FALSE	Activate energy optimisation.	TRUE	Deactivate energy optimisation.
FALSE	Activate energy optimisation.				
TRUE	Deactivate energy optimisation.				

Outputs

Identifier DIS code data type	Value/meaning		
bLimPosCtrlOut BOOL	"Position controller output inside the limitation" status signal <table> <tr> <td>TRUE</td><td>The position controller output is internally limited</td></tr> </table>	TRUE	The position controller output is internally limited
TRUE	The position controller output is internally limited		
nOutputPosCtrl_a INT	Position controller output <ul style="list-style-type: none"> Scaling: 16384 \equiv 100 % reference speed (C00011) 		

Identifier DIS code data type	Value/meaning		
dnMotorPosAct_p DINT	Current position in [increments] <ul style="list-style-type: none"> If the gearbox factor position encoder (C01203/1..2) is equal to "1", the motor position is output. Otherwise, if the gearbox factor position encoder (C01203/1..2) is not equal to "1" and a position encoder has been set in C00490, a position referring to the position encoder is output. 		
dnMotorDeltaPosAct_p DINT	Current following error in [increments] <ul style="list-style-type: none"> Following error = Difference between set position and actual position If the gearbox factor position encoder (C01203/1..2) is equal to "1", the motor following error is output. Otherwise, if the gearbox factor position encoder (C01203/1..2) is not equal to "1" and a position encoder has been set in C00490, a following error referring to the position encoder is output. 		
bLimSpeedCtrlOut BOOL	"Speed controller or manipulating variable of the slip regulator inside the limitation" status signal <table> <tr> <td>TRUE</td><td>The speed controller output is internally limited</td></tr> </table>	TRUE	The speed controller output is internally limited
TRUE	The speed controller output is internally limited		
bLimSpeedSetVal BOOL	"Reduction or increase of the setpoint speed active" status signal <table> <tr> <td>TRUE</td><td>Reduction or increase of the setpoint speed by the I_{\max} controller is active</td></tr> </table>	TRUE	Reduction or increase of the setpoint speed by the I_{\max} controller is active
TRUE	Reduction or increase of the setpoint speed by the I_{\max} controller is active		
wMaxMotorSpeed C00011 BOOL	Reference speed (C00011)		
nOutputSpeedCtrl_a INT	Speed controller output <ul style="list-style-type: none"> Scaling: $16384 \equiv 100 \% M_{\max}$ (C00057) In case of the "VFC (+encoder)" motor control, this output is the output of the slip regulator. In this case, the scaling depends on the reference frequency (display in C00059): <ul style="list-style-type: none"> C00059 < 650 Hz: $16384 \equiv 327.68 \text{ Hz}$ ($24000 \equiv 480.00 \text{ Hz}$) C00059 > 650 Hz: $16384 \equiv 655.36 \text{ Hz}$ ($12000 \equiv 480.00 \text{ Hz}$) 		
nSpeedCtrlIntAct_a INT	Current value of speed controller integrator <ul style="list-style-type: none"> Scaling depends on the selected motor control: <ul style="list-style-type: none"> V/f control (VFCplus + encoder): $16384 \equiv 100 \% \text{ reference speed}$ (C00011) Servo control (SC) or vector control (SLVC): $16384 \equiv 100 \% M_{\max}$ (C00057) 		
nEffSpeedSetValue_a INT	Effective speed setpoint <ul style="list-style-type: none"> Scaling: $16384 \equiv 100 \% \text{ reference speed}$ (C00011) 		
nMotorSpeedAct_a C00051 INT	Actual speed value <ul style="list-style-type: none"> Scaling: $16384 \equiv 100 \% \text{ reference speed}$ (C00011) 		
nMotorSpeedAct_v INT	Actual speed value <ul style="list-style-type: none"> Scaling: $65535 \equiv 1 \text{ revolution}$ 		
nMotorFreqAct_a C00058 INT	Current field frequency <ul style="list-style-type: none"> Scaling depends on the reference frequency (display in C00059): <ul style="list-style-type: none"> C00059 < 650 Hz: $16384 \equiv 327.68 \text{ Hz}$ ($24000 \equiv 480.00 \text{ Hz}$) C00059 > 650 Hz: $16384 \equiv 655.36 \text{ Hz}$ ($12000 \equiv 480.00 \text{ Hz}$) 		
bLimTorqueSetVal BOOL	"Setpoint torque inside the limitation" status signal <table> <tr> <td>TRUE</td><td>The setpoint torque is internally limited</td></tr> </table>	TRUE	The setpoint torque is internally limited
TRUE	The setpoint torque is internally limited		
wMaxMotorTorque C00057	Maximum motor torque <ul style="list-style-type: none"> $wMaxMotorTorque = 10 * M_{\max}$ (C00057) 		
nInputTorqueCtrl_a INT	Input value of the torque control (torque setpoint) <ul style="list-style-type: none"> Scaling: $16384 \equiv 100 \% M_{\max}$ (C00057) 		
nMotorTorqueAct_a C00056/2 INT	Actual torque <ul style="list-style-type: none"> In the "VFC (+encoder)" motor control mode, this value is determined from the current motor current and only approximately corresponds to the actual torque value.. Scaling: $16384 \equiv 100 \% M_{\max}$ (C00057) 		

Identifier	Value/meaning
DIS code data type	
nInputJerkCtrl_a INT	Input value of the jerk limitation • Scaling: 16384 \equiv 100 % M_{\max} (C00057)
bLimCurrentSetVal BOOL	"Current setpoint inside the limitation" status signal TRUE The current setpoint is internally limited
nStatorCurrentIS_a INT	Current stator current/effective motor current • Scaling: 16384 \equiv 100 % I_{\max_mot} (C00022)
nEffCurrentIq_a INT	Current torque-producing cross current • Scaling: 16384 \equiv 100 % I_{\max_mot} (C00022)
nReaktCurrentId_a INT	Current field-producing direct-axis current • Scaling: 16384 \equiv 100 % I_{\max_mot} (C00022)
nActualFluxx_a INT	Current magnetising current • Scaling: 16384 \equiv 100 % I_{\max_mot} (C00022)
nDCVoltage_a INT	Actual DC-bus voltage • Scaling: 16384 \equiv 1000 V
nMotorVoltage_a INT	Current motor voltage/inverter output voltage • Scaling: 16384 \equiv 1000 V
bQspActive BOOL	"Quick stop active" status signal TRUE Quick stop is active
bAutoDCBActive BOOL	"Automatic DC-injection braking active" status signal ► DC-injection braking (□ 267) TRUE Automatic DC-injection braking is active
bIdentificationActive BOOL	"Motor parameter identification active" status signal ► Automatic motor data identification (□ 141) TRUE Motor parameter identification is active
bFlyingSyncActive BOOL	"Flying restart function active" status signal ► Flying restart function (□ 264) TRUE Flying restart function is active
bHlgLoad BOOL	Control signal for an additional loading function of the ramp function generator • → L_NSet_1.bExternalCINH • To enable the ramp function generator to follow automatically when the controller is inhibited, for jerk-free setpoint connection. TRUE Set the ramp function generator to a setpoint of nHlgSetValue_a
nHlgSetValue_a INT	Setpoint for an additional loading function of the ramp function generator • → L_NSet_1.nClnhVal_a • For speed-controlled drive tasks, the current actual speed value (e.g. in case of an active pulse inhibit, flying restart function, controller inhibit) is provided at this output. • Scaling: 16384 \equiv 100 % reference speed (C00011)
bHlgStop BOOL	Control signal for stopping the ramp function generator (L_NSet_1) TRUE Stop the ramp function generator
bBrakeChopperActive BOOL (from version 12.00.00)	Status signal of the internal brake chopper control ► Control of multiple internal brake choppers in the DC-bus system (□ 289) TRUE Internal brake chopper is switched-on.
nVoltageAngleAct_a INT (from version 13.00.00)	Current electrical voltage output angle of the controller • Scaling: 16384 \equiv 360°
bLimSpeedTorquemodeOn BOOL (from version 13.00.00)	Status signal of torque control with speed limitation TRUE Speed limitation for torque control is active.

5.15 Internal status signals | System block "LS_DeviceMonitor"

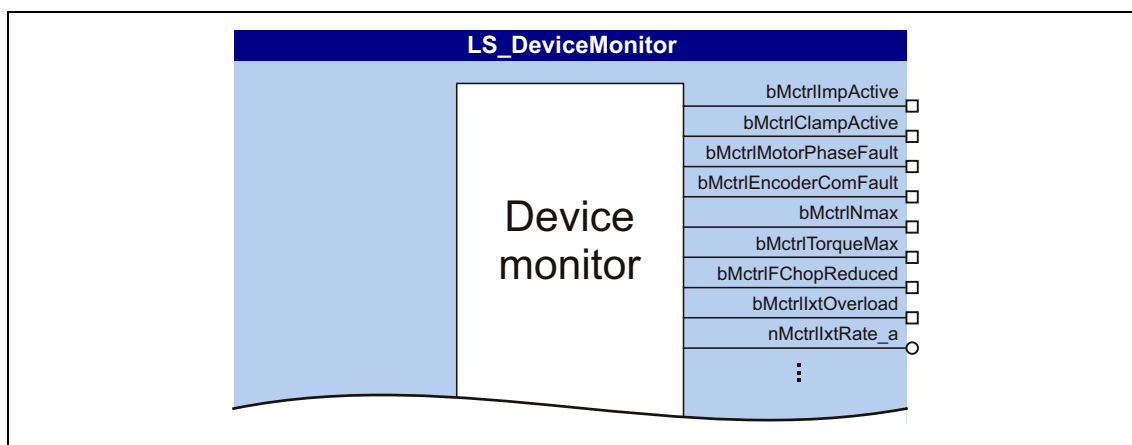
The **LS_DeviceMonitor** system block provides the status signals of the motor control in the function block editor.



Note!

The **LS_DeviceMonitor** system block can only be inserted on the application level.

If status signals of the motor control function are to be output via digital outputs or example, you can use the free *bFreeOut1* ... *bFreeOut8* outputs of the application block to transfer the desired status signals from the application level to the I/O level. On the I/O level, you can then establish the logical link to the digital output terminals.



[5-36] LS_DeviceMonitor system block (excerpt)

Outputs

Identifier	Data type	Value/meaning	
bMctrlImpActive	BOOL	TRUE	Pulse inhibit is active
bMctrlClampActive	BOOL	TRUE	Clamp current limitation is active
bMctrlMotorPhaseFault	BOOL	Status of the Motor phase failure monitoring	
		TRUE	Motor phase fault has been detected
bMctrlEncoderComFault	BOOL	TRUE	Encoder error has been detected
bMctrlNmax	BOOL	TRUE	Max. speed limitation is active
bMctrlTorqueMax	BOOL	Status of the Maximum torque monitoring	
		TRUE	Max. torque limitation is active
bMctrlFChopReduced	BOOL	TRUE	PWM frequency reduction is active
bMctrlIxtOverload	BOOL	Status of the Device overload monitoring (Ixt)	
		TRUE	Device utilisation (Ixt) ≥ device utilisation threshold (C00123) • Lenze setting: C00123 = 100 %
nMctrlIxtRate_a	INT	Current device utilisation (Ixt) • Scaling: 16384 ≙ 100 %	

Identifier	Data type	Value/meaning
bMctrlI2xtOverload	BOOL	Status of the Motor load monitoring (I2xt)
		TRUE Thermal motor overload (I^2_{xt}) \geq motor overload setting (C00120) • Lenze setting: C00120 = 100 %.
nMctrlI2xtRate_a	INT	Current thermal motor load (I2xt) • Scaling: 16384 \equiv 100 %
bMctrlMotorPTC	BOOL	Status of the Motor temperature monitoring (PTC)
		TRUE Temperature monitoring: An error has been detected.
bMctrlMotorTemp	BOOL	Status of the Motor temperature monitoring (KTY)
		TRUE Thermal motor overload • One of the following error messages is pending: "oH7: Motor temperature resolver > C121" "oH9: Motor overtemperature resolver" "oH6: Motor temperature MultiEncoder > C121" "oH12: Motor overtemperature MultiEncoder"
bMctrlHeatSinkTemp	BOOL	TRUE Thermal inverter overload • The heatsink temperature (display in C00061) has reached the maximally permissible temperature. The "oH1: Overtemperature heatsink" error message is pending and the "Fault" response is activated. • Furthermore, this output is set if the heatsink temperature has exceeded the maximally permissible temperature for the switching frequency set. A response with an "oH4: Heatsink temp.. > switch-off temp. -5°C" error message can be set in C00582 . In the Lenze setting, no response will be effected.
bMctrlMainsFault	BOOL	Status of the Mains phase failure monitoring
		TRUE Mains phase failure/Mains failure
bMctrlFanFault	BOOL	TRUE Fan monitoring: An error has been detected.
bMctrlNmaxForFChop	BOOL	TRUE The maximum field frequency for the respective switching frequency has been exceeded.
bMctrlShortCircuit	BOOL	TRUE Motor short circuit has been detected
bMctrlEarthFault	BOOL	TRUE Earth fault has been detected
bMctrlUVDetected	BOOL	TRUE An undervoltage has been detected
bMctrlOVDetected	BOOL	TRUE An overvoltage has been detected
bMctrlBrakeChopperFault	BOOL	Status of the Brake resistor monitoring (I2xt) • This output is set independent of the set error response of the monitoring function.
		TRUE The I^2_{xt} utilisation has reached the switch-off threshold set in C00572 . • Lenze setting: C00572 = 100 %.
wUB24V	WORD	Current 24 V supply voltage • Scaling: 1000 \equiv 1.000 V
nMctrlActiveOutputPower_a	INT	Current active output power • Scaling: 16384 \equiv double rated power of the controller (from version 14.00.00)
nMctrlApparentOutputPower_a	INT	Current apparent output power • Scaling: 16384 \equiv double rated power of the controller (from version 14.00.00)
nMctrlCosinePhiAct_a	INT	Current cosine phi • Scaling: 16384 \equiv cosine phi of 1.0 (from version 14.00.00)

Identifier	Data type	Value/meaning
bWirebreakUfLinearActive (from version 15.00.00)	BOOL	Status "V/f emergency operation due to encoder open circuit active" • The internal change-over to "V/f emergency operation" can be suppressed by setting bit 8 to "1" in C02864/1 .
		TRUE Due to an encoder open circuit, it is internally switched to the encoderless V/f characteristic control in order to avoid impermissible motor movements. This does not influence the setting in C00006 .

6 Encoder/feedback system

The 8400 TopLine uses various encoder/feedback systems for the motor controls with speed feedback and the position control:

- Resolver at X7
- Multi-Encoder at X8
 - Incremental TTL encoders
 - Incremental SinCos encoders
 - SinCos absolute value encoder with HIPERFACE® protocol
 - SSI absolute value encoder with Stegmann-SSI protocol
 - Digital frequency coupling ([from version 12.00.00](#))
- HTL encoder at the digital DI1/DI2 or DI6/DI7 input terminals



Danger!

- If the encoder/resolver is used as motor encoder:
Safe operation of the motor is no longer ensured in the event of an error!
- If servo control (SC) or V/f control (VFCplus + encoder) are used: For safety reasons, always select "Fault" (Lenze setting) in the following parameters as a response for the (open-circuit) monitoring of the encoder!
 - [C00586](#): Resp. open circuit HTL encoder
 - [C00603/1](#): Resp. open circuit MultiEncoder
 - [C00603/2](#): Resp. open circuit resolver
- If an HTL encoder is used at the digital input terminals:
Observe the maximum input frequencies of the digital inputs!
 - DI1/DI2: max. 200 kHz
 - DI6/DI7: max. 10 kHz
- To avoid interference when using an encoder, only use shielded motor and encoder cables!



Note!

Speed feedback is essential for the following motor control modes with feedback:

- [Servo control \(SC\)](#)
- [V/f control \(VFCplus + encoder\)](#)

**Note!**

The encoder position can be saved safe against mains failure in the controller.

- For this purpose, bit 0 must be set in [C02652](#). The actual position of the motor control is then saved in the controller (not in the memory module) and thus remains known to the drive control after mains switching.
 - ▶ [Option "Actual MCTRL position received at mains switch-off"](#) (📖 622)
- In case of a device replacement, this information gets lost and the home position might be approached or set again once. A device replacement can be recognised by using the SB [LS_RetainData](#) and a suitable function block interconnection.

If an absolute value encoder (Multiturn) is used, the actual position will always be reconstructed after mains switch-off/switch-on, no matter if the bit 0 in [C02652](#) has been set to "0" or "1".

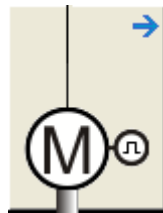


Wiring diagram, assignment and electrical data of the terminals for resolvers and multi encoders can be found in the **hardware manual 8400** in the chapter "technical data". The hardware manual is stored in electronic form on the data carrier supplied with the 8400 controller.

6.1**Encoder selection**

How to get to the parameterisation dialog of the encoder/feedback system:

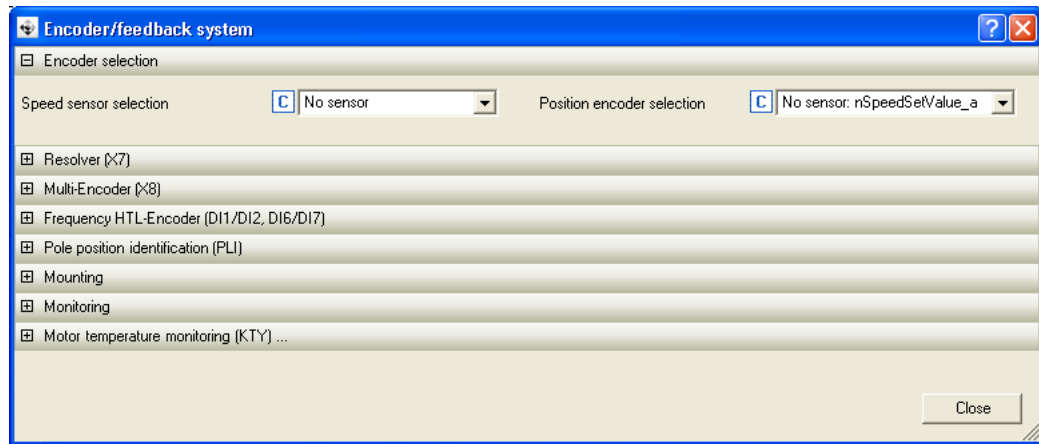
1. »Engineer« Go to the *Project view* and select the 8400 TopLine controller.
2. Select the **Application parameters** tab from the *Workspace*.
3. Go to the *Overview* dialog level and click the following button:



4. Go to the *Overview* → *Motor data* dialog level and click the **Encoder/Feedback system...** button to open the parameterisation dialog for the encoder/feedback system.

Parameterisation dialog in the »Engineer«

From the »Engineer« V2.19, the following parameterisation dialog is available for parameterising the encoder/feedback system. For a better overview, the parameterisation dialog contains different categories which can be expanded/collapsed by a simple click. First, only the "encoder selection" category is expanded:



Parameter	Info	Lenze setting
C00495	Speed sensor selection • Source of feedback signal for speed control.	0: No sensor
C00490	Position encoder selection • Source of feedback signal for position control.	0: no sensor: nSpeedSetValue_a



Go to the **Speed sensor selection** list field and select the connected speed sensor. After the selection, the respective category with the parameters relevant for the selected encoder is automatically expanded.



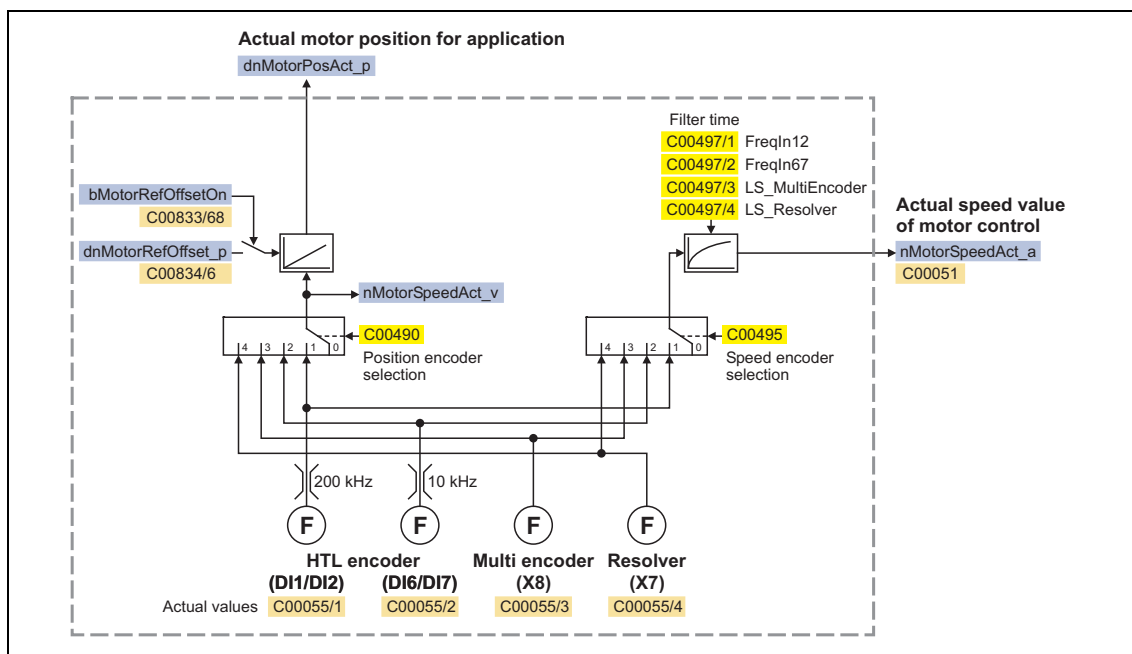
Detailed information on the parameters of the other categories can be found in the corresponding chapter:

- ▶ [Resolver \(X7\)](#) (319)
- ▶ [Multi-Encoder \(X8\)](#) (325)
- ▶ [Frequency HTL encoder \(DI1/DI2, DI6/DI7\)](#) (352)
- ▶ [Pole position identification \(PPI\)](#) (358)
- ▶ [Mounting](#) (367)
- ▶ [Monitoring](#) (368)
- ▶ [Motor temperature monitoring \(KTY\)](#) (373)

6 Encoder/feedback system

6.1 Encoder selection

6.1.1 Signal flow - encoder interface



[6-1] Signal flow - encoder interface

Generation of the actual speed value

...depending on the encoder selection and mounting direction:

Speed sensor (C00495)	Position encoder (C00490)	Motor mounting direction (C01206/1)	Direction of rotation of motor shaft (at setpoint = Cw)	Actual speed value (nAct_v)
<input type="checkbox"/>	<input type="checkbox"/>	not inverted	Cw	ΔSetPos
		inverted	Ccw	
<input checked="" type="checkbox"/>	<input type="checkbox"/>	not inverted	Cw	C00495
		inverted	Ccw	
<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	not inverted	Cw	C00490 \rightarrow ΔActPos
		inverted	Ccw	
<input type="checkbox"/>	<input checked="" type="checkbox"/>	not inverted	Cw	
		inverted	Ccw	

☐ no encoder ☒ Encoder set

Up to and including version 02.xx.xx the following applies:

- For motor control types without speed feedback ([C00495](#) = "0: No encoder") a speed-proportional unit is taken for calculating the *nMotorSpeedAct_v* speed signal. This derivation, however, is very imprecise so that in case of applications with synchronous motors without speed feedback it is not possible to calculate the current position from the current *nMotorSpeedAct_v* speed signal.
- If no position encoder is available ([C00490](#) = "0: No encoder"), the *dnMotorPosAct_p* position signal is always derived from the *nSpeedSetValue_a* speed setpoint. This derivation, however, is very imprecise since in this case, speed limitations (e.g. by overcurrent limitations) are not considered.

From version 12.00.00 the following applies:

- For applications with synchronous motors without speed feedback, an *nMotorSpeedAct_v* error-free speed signal is available. This is calculated from the electrical voltage output angle of the controller considering the number of pole pairs of the *nMotorSpeedAct_v* speed signal.
 - From version 13.00.00, the electrical voltage output angle is shown at the *nVoltageAngleAct_a* output of the [LS_MotorInterface](#) SB (scaling: $16384 \equiv 360^\circ$). This process signal can for instance be used in applications where a change-over from inverter to mains operation is to be carried out (synchronisation of the controller output voltage to the mains voltage).
- When synchronous or reluctance motors without feedback are used in the motor control types [V/f characteristic control \(VFCplus\)](#) and [Sensorless control for synchronous motors \(SLPSM\)](#), the *nMotorSpeedAct_v* speed signal can be used to create an error-free position signal via a control if the *nMotorSpeedAct_v* signal is read out by the control in a 1 ms cycle.
- If no position encoder is available ([C00490](#) = "0: No encoder"), the *dnMotorPosAct_p* position signal is continued to be derived from the *nSpeedSetValue_a* speed setpoint. The extended selection text "0: No encoder:nSpeedSetValue_a" in [C00490](#) refers to this behaviour.
- The new selection "10: No encoder: C495 or nMotorSpeedSetAct_v" in [C00490](#) is used to calculate the *dnMotorPosAct_p* position signal either from the set speed feedback (when [C00495](#) > 0) or from the *nMotorSpeedAct_v* speed signal (when [C00495](#) = 0).
 - For all motor control types without speed feedback, this selection serves to improve the creation of the *dnMotorPosAct_p* position signal.
 - When synchronous or reluctance motors without feedback are used, the *dnMotorPosAct_p* position signal can be created correctly.
 - In case of the motor control types with speed feedback, the *dnMotorPosAct_p* position signal is directly created from the speed feedback signal.

6.2

Resolver (X7)

**Danger!**

- If the resolver is used as motor encoder:
Safe operation of the motor is no longer ensured in the event of an error!
- If servo control (SC) or V/f control (VFCplus + encoder) are used:
For safety reasons, always select "Fault" (Lenze setting) in [C00603 2](#) as a response for the (open-circuit) monitoring of the resolver!

6.2.1

Parameterising the resolver

**Note!**

If a Lenze motor with resolver is used, the resolver is the only item that can be selected as speed sensor in [C00495](#). Further resolver parameter setting is not required.

Moreover, Lenze synchronous motors do not require a pole position identification (PLI) as the resolvers of the Lenze synchronous motors are pre-adjusted.

**Note!****Acceptance of the resolver pole position from a Servo Drive 9400**

The resolver pole position ([C00926/1](#)) cannot be simply accepted from a Servo Drive 9400 if the pole position (C58/1) considerably differs from -90 ° in the Servo Drive 9400.

- We always recommend a [pole position identification \(PLI\)](#). (□ 358)
- As an alternative, the following conversion has to be carried out for a transfer of the resolver pole position from a Servo Drive 9400 to the 8400 TopLine:
Pole position₈₄₀₀ ([C00926/1](#)) = - (pole position_{9400_C58/1} + 180 °)

Parameterisation dialog (cutout)

Resolver (X7)

Number of pole pairs:

Encoder filter time: ms

Activate resolver error comp.: ☒ Resolver error comp. act.

cos gain: %

sine gain: %

phase error: %

Parameter	Info	Lenze setting	
		Value	Unit
C00925	LS_Resolver: Number of pole pairs	1	
C00497/4	LS_Resolver: Encoder filter time	2.0	ms
C00417	Activate resolver error comp. ► Optimising resolver behaviour	0: Activate resolver error compensation	
C02862/1	Resolver: cos gain	100.00	%
C02862/2	Resolver: sine gain	100.00	%
C02863	Resolver: Phase error	0.00	%



How to parameterise the resolver:

1. If number of resolver pole pairs $\neq 1$:
Set number of pole pairs ([C00925](#)).
2. Select resolver as speed sensor ([C00495](#)) or/and as position encoder ([C00490](#)).
3. Adjust filter time of the actual speed value ([C00497/4](#)) if necessary.
 - Lenze setting: 2 ms
 - Lenze recommend a filter time between 1 ... 2 ms.
4. If you use the resolver as motor encoder and the servo control with synchronous motor of a original equipment manufacturer: Carry out [Pole position identification \(PPI\)](#). (📘 358)
5. For detecting and monitoring the motor temperature via the resolver cable:
Parameterise [Motor temperature monitoring \(KTY\) via resolver](#). (📘 374)
6. Optional: Parameterise [Resolver/multi-encoder open-circuit monitoring](#). (📘 369)
In the Lenze setting, the resolver cable and/or encoder cable are monitored with regard to open circuit as a function of the selected speed and position encoder.
7. For a permanent acceptance of the parameter settings:



Save parameter set.

6.2.2 Optimising resolver behaviour

Due to mounting and production tolerances as well as resolver material property leakage, errors may occur which, among other things, result in speed-dependent vibration of the actual speed. These errors are called resolver errors. Resolver errors typically occur in the form of the 1st and 2nd harmonic. They have two different causes:

1. The inductances of the sine and cosine track of the resolver have slightly different values.
2. Sine and cosine track do not magnetise orthogonally to each other.

Resolver errors due to cause 1 can be corrected by adjusting the gains of the digital/analog converters which feed the resolver tracks. In the Lenze setting, the gains of both resolver tracks are preset with identical values.

Resolver errors due to cause 2 can be compensated for by a slight correction of the angle via which both resolver tracks are fed relative to one another.

When the "Resolver error identification" device command ([C00002/25](#)) is executed, the gain of the resolver signals and the angular drift of both resolver tracks is corrected to minimise the resolver error.

- Select a speed-controlled operating mode (e.g. servo control) for your machine while you perform a resolver error identification run. During the identification run, speed must be constant and greater than 500 rpm.
- After a successful resolver error identification run, the resolver automatically uses the following resolver error parameters which have been identified during the procedure:

Parameter	Info	Lenze setting	
		Value	Unit
C02862/1	Resolver: cos gain	100.00	%
C02862/2	Resolver: sine gain	100.00	%
C02863	Resolver: Phase error	0.00	%

- The detected gain can have values from 80 ... 120 %. It makes sense to adjust only one of the two gains during a resolver error compensation. The other one remains at 100 % (Lenze setting).
- Save the parameter set afterwards to accept the identified resolver error parameters permanently (device command [C00002/11](#)).
- If the resolver error compensation is deactivated ([C00417](#) = "1: Resolver error comp. deact."), the resolver will resume work with the Lenze setting. However, the identified resolver error parameters remain saved.



How to perform a resolver error identification run:

1. Select a motor control mode with speed feedback in [C00006](#) and commission it. ▶ [Selecting the control mode](#)
 - Avoid a speed controller setting that is too tight (motor humming).
 - Set the speed ramps as well as the speed setpoint (> 500 rpm).
2. Inhibit the controller, e.g. via the [C00002/16](#) device command or via a LOW signal at terminal X5/RFR.
 - The controller must be in the "[SwitchedOn](#)" status for the resolver error identification run to be performed.
3. Activate resolver error identification via the [C00002/25](#) device command = "1: On / start".
4. Enable the controller again.
 - The controller changes to the "[Ident](#)" device status.
 - The resolver error identification run starts.
 - The progress of the identification run can be seen in [C00002/25](#).
 - During the resolver error identification run, the direction of rotation of the motor is not important.
 - We recommend to traverse at constant setpoint speed ($|\text{Inset}| > 500 \text{ rpm}$) until resolver error identification has finished.
 - If the application offers only limited space for traversing, reversing is also possible during active resolver error identification. In this case, ensure that the controller is not inhibited and that the speed profile is traversed for at least 1 second at constant setpoint speed ($|\text{Inset}| > 500 \text{ rpm}$).
 - The identification is completed if the "0: Off / ready" message is displayed in [C00002/25](#).
5. After the resolver error identification has been completed successfully, the controller can be inhibited again. (When the controller is inhibited, the "[Ident](#)" device state is quit again.)
6. In order to accept the identified resolver error parameters:



Save parameter set.



Tip!

Resolver error identification can be aborted any time by setting a controller inhibit.

**Note!**

Some applications require that the resolver error identification can also be carried out during operation.

From version V12.00.00, the resolver error identification can also be started in the "OperationEnabled" device status (controller enable) using the device command [C00002/25](#) = "1: on / start". Then there is no device state change, i.e. the device status remains at "OperationEnabled".

Furthermore, the following applies to the resolver error identification during operation:

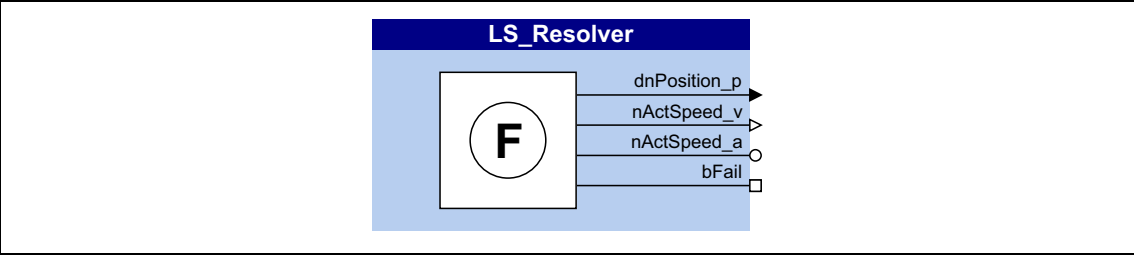
- The progress of the identification run can be seen in [C00002/25](#).
- During the resolver error identification run, the direction of rotation of the motor is not important.
- We recommend to traverse at constant setpoint speed ($|\text{nset}| > 500 \text{ rpm}$) until resolver error identification has finished.
- If the application offers only limited space for traversing, reversing is also possible during active resolver error identification. In this case, ensure that the controller is not inhibited and that the speed profile is traversed for at least 1 second at constant setpoint speed ($|\text{nset}| > 500 \text{ rpm}$).
- The identification is completed if the "0: Off / ready" message is displayed in [C00002/25](#).

Possible causes for resolver error identification failure:

- A controller inhibit was set during resolver error identification.
- A time-out occurred while the algorithm was processed.
 - This error may occur if more than 60 seconds pass by between the setting of the "Resolver error identification" device command and the enable of the controller.
- The setpoint speed was too small ($|\text{nset}| < 500 \text{ rpm}$).
- The setpoint speed was not traversed for at least 1 second.

6.2.3 Internal interfaces | "LS_Resolver" system block

The **LS_Resolver** system block provides the application with speed, position and error information from the resolver in the form of process signals.



Outputs

Identifier	Data type	Value/meaning
dnPosition_p	DINT	Actual encoder position in [increments]
nActSpeed_v	INT	Actual speed in [increments/ms]
nActSpeed_a	INT	Actual speed in [%] • Scaling: 16384 \equiv 100 % reference speed (C00011)
bFail	BOOL	TRUE Group error: There is an error (e.g. resolver wire breakage) according to the <i>bFail</i> configuration in C00432/1 . From version 14.00.00, the error type is displayed bit-coded in C00452/1 . ▶ Monitoring

6.3

Multi-Encoder (X8)

**Danger!**

- If the resolver is used as motor encoder:
Safe operation of the motor is no longer ensured in the event of an error!
- If servo control (SC) or V/f control (VFCplus + encoder) are used: For safety reasons, always select "Fault" (Lenze setting) in [C00603 1](#) as a response for the (open-circuit) monitoring of the encoder!

**Stop!**

Before connecting an encoder, ensure that the encoder supply voltage has the correct setting in [C00421](#):

- Lenze setting: 5 V (setting range: 5 ... 12 V)

If the set supply voltage exceeds the permissible supply voltage of the connected encoder, the encoder may be destroyed!

**Note!**

With regard to their position resolution, higher-level applications are based on the resolution of the encoder which is activated for position control.

The interface of the Multi-Encoder offers various ways in which the encoders can be used / evaluated:

- [Incremental TTL and SinCos encoder](#)
- [SinCos absolute value encoder with HIPERFACE® protocol](#)
- [SSI absolute value encoder with Stegmann-SSI protocol](#)
- [Digital frequency coupling \(from version 12.00.00\)](#)

6.3.1 Incremental TTL and SinCos encoder



Tip!

The use of a SinCos encoder instead of a TTL encoder enables a fine interpolation of the position within one encoder increment due to the analog representation of the track signals A and B. This serves to considerably increase the resolution of the position information of a SinCos encoder compared to a conventional TTL incremental encoder.

Parameterisation dialog (cutout)

Multi-Encoder (X8)

Encoder type: Incremental encoc

Supply voltage: 5.0 V

TTL encoder increment: 512 Incr./rev.

Encoder filter time: 1.0 ms

Position offset: 0.0000 units

Position value scaling... SSI configuration...

Further parameterisation dialogs: [Scaling of position value](#)

Parameter	Info	Lenze setting	
		Value	Unit
C00422	LS_MultiEncoder: Encoder type	0: Incremental encoder (TTL)	
C00421	LS_MultiEncoder: Supply voltage	5.0	V
C00420/3	LS_MultiEncoder: Encoder increment	512	Incr./rev.
C00497/3	LS_MultiEncoder: Encoder filter time	1.0	ms
C01112/1	LS_MultiEncoder: Position offset	0.0000	units



How to parameterise the incremental TTL or SinCos encoder:

1. As encoder type ([C00422](#)), select "0: Incremental encoder (TTL)" or "1: Sin/Cos encoder" (depending on the type of the connected encoder).
2. Adapt supply voltage ([C00421](#)) depending on the cable length if required (see the following section "[Voltage setting as a function of the cable length](#)").
3. Set encoder increment ([C00420/3](#)).
4. Adjust filter time of the actual speed value ([C00497/3](#)) if necessary.
 - Lenze setting: 1 ms
 - Lenze recommend a filter time between 1 ... 2 ms.
5. If you use the encoder as motor encoder and synchronous motor:
Carry out [Pole position identification \(PPI\)](#). ([358](#))
6. For detecting and monitoring the motor temperature via the Encoder cable:
Parameterise [Motor temperature monitoring \(KTY\) via encoder](#). ([375](#))
7. Optional: Parameterise [Resolver/multi-encoder open-circuit monitoring](#). ([369](#))
In the Lenze setting, the resolver cable and/or encoder cable are monitored with regard to open circuit as a function of the selected speed and position encoder.
8. For a permanent acceptance of the parameter settings:



Save parameter set.

Voltage setting as a function of the cable length

The following table shows the settings required for different incremental encoder types as a function of the cable length. The given values apply when Lenze system cables are used at typical ambient temperatures. Other cables, cable cross-sections or extreme ambient temperatures may require metrologically detected adaptations.

Encoder type Product key	Rated voltage V _{rated}	Encoder increment (C00420/3)	Voltage setting in C00421 with a cable length of			
			0 - 30 m	30 - 70 m	70 - 100 m	100 - 150 m
Incremental TTL encoders						
IG2048-5V-T	5 V ±5 %	2048	5.0 V	5.1 V	5.2 V	5.3 V
IG4096-5V-T		4096				
IK2048-5V-T		2048				
IK4096-5V-T		4096				
Incremental SinCos encoders						
IG1024-5V-V	5 V ±5 %	1024	5.0 V	5.1 V	5.2 V	5.3 V
IG2048-5V-S		2048				

6.3.2 SinCos absolute value encoder with HIPERFACE® protocol

SinCos absolute value encoders with HIPERFACE® protocol are feedback systems which transmit an absolute position on request. Moreover, they permanently provide an incremental signal via a sin/cos evaluation. The analog evaluation of the sin/cos tracks provides for a high resolution.

The absolute position is transmitted via an RS485 data interface with 9600 Baud (standard value). This bidirectional parameter channel also serves to request and transmit error codes, encoder data and other information. The analog process data channel is created by a differential transmission of sin/cos signals. The resolutions of these two information channels are generally not identical, thus the channels have to be parameterised independently of each other in the controller.



Note!

If the RS485 cable is interrupted, a communication to the encoder is permanently tried to be built up. After the maximum initialisation time set in [C00430/1](#) has expired, the error "[Sd7: Error encoder communication](#)" is triggered. This error is cancelled if a communication could be built up successfully and the encoder initialisation has been executed.

The selection of an error response in [C00603/4](#) serves to optionally monitor the communication between absolute value encoder and controller.

If the monitoring is tripped:

- The error response set in [C00603/4](#) is triggered.
- The "[Sd7: Encoder communication error](#)" error message is entered into the logbook.

6.3.2.1 Initialisation

A connected SinCos absolute value encoder with HIPERFACE® protocol is initialised in the following cases:

- When the device is switched on after the waiting time of approx. 1 s has expired.
- After the encoder wire breakage has been removed.

In case of an encoder wire breakage, a speed and position detection cannot be carried out correctly. A renewed initialisation after removing the encoder wire breakage serves to connect to the correct absolute position.

- After describing one of the following parameters as the setting has an impact on the internal scaling of the encoder position:

Parameter	Name	Parameter	Name
C00420/3	LS_MultiEncoder: Encoder increment	C00495	Speed sensor selection
C00422	LS_MultiEncoder: Encoder type	C01110	LS_MultiEncoder: Solid measure
C00490	Position encoder selection	C01111/1..3	LS_MultiEncoder: Encoder constant
C00494/1..2	Hiperface: Resolutions	C01204	MCK: Feed constant

Initialisation process

During initialisation, the controller requests different information from the encoder. The process of this data transfer is as follows:

1. Reading the encoder status

The encoder can provide up to 4 error codes which are displayed in [C00491/1...4](#) from [version 14.00.00](#).

2. Reading the encoder type (display of the TypeCode in [C00492](#))

3. Reading the absolute position

A constant encoder position is assumed to initiate the position value correctly. An initialisation is not permissible when the encoder is rotating.

4. Processing the read position data and linking the SinCos-based position and speed detection to the absolute position of the encoder.

Encoders detected automatically

The following encoder types are detected and set automatically by the controller:

Type	Increments/ revolution	Absolute revolutions	Bits Singleturn	Bits Multiturn	Bits SinCos track	Type code
AM1024-8V-H (SRM50)	1024	4096 (Multiturn)	15	12	10	0x27
AM1024-8V-H (SRM60)						
AM1024-8V-H (SRM64)						
AM512-8V-H (SCM60)	512		14	12	9	0x07
AM512-8V-H (SCM70)						
AM128-8V-H (SKM36)	128		12	12	7	0x37
AM16-8V-H (SEL37)	16		9	12	4	0x47
AM16-8V-H (SEL52)						
AS1024-8V-H (SRS50)	1024	1 (Singleturn)	15	0	10	0x22
AS1024-8V-H (SRS60)						
AS1024-8V-H (SRS64)						
AS512-8V-H (SCS60)	512		14	0	9	0x02
AS512-8V-H (SCS70)						
AS128-8V-H (SKS36)	128		12	0	7	0x32
AS16-8V-H (SEK37)	16		9	0	4	0x42
AS16-8V-H (SEK52)						

- Regarding the saving of position information, it is distinguished between:
Singleturn: Saving within one revolution
Multiturn: Saving within a number of revolutions
- In case of encoders with an extended electronic nameplate (TypeCode = "0xFF"), the encoder settings currently cannot be read automatically out of the encoder and thus have to be executed manually. See the instruction "[How to parameterise an absolute value encoder with an unknown type code](#)" in the following "Parameter setting" subchapter.
- The encoder settings for all other encoders (TypeCode = "0x00") have to be made manually as well. See the instructions "[How to parameterise an absolute value encoder with an unknown type code](#)" in the following "Parameter setting" subchapter.

6.3.2.2 Parameterising the encoder

Parameterisation dialog (cutout)

Further parameterisation dialogs: [Scaling of position value](#)

Parameter	Info	Lenze setting	
		Value	Unit
General settings			
C00422	LS_MultiEncoder: Encoder type	0: Incremental encoder (TTL)	
C00421	LS_MultiEncoder: Supply voltage	5.0	V
C00420/3	LS_MultiEncoder: Encoder increment • Setting is relevant for process data channel (incremental SinCos track).	512	Incr./rev.
C00497/3	LS_MultiEncoder: Encoder filter time	1.0	ms
C01112/1	LS_MultiEncoder: Position offset	0.0000	units
Settings for SinCos absolute value encoder with HIPERFACE® protocol			
C00492	Hiperface: Detected TypCode	-	
C00494/1	Hiperface: Number of revolutions • Number of resolved revolutions of the Hiperface track. • Setting is relevant for parameter channel.	0	
C00494/2	Hiperface: Steps per revolution • Resolution of the Hiperface track. • Setting is relevant for parameter channel.	0	
C00499/1	Hiperface: Advanced settings	0x0	
Highlighted in grey = display parameter			



How to parameterise the SinCos absolute value encoder:

1. Set the supply voltage ([C00421](#)) of the used encoder.
2. As encoder type ([C00422](#)), select "2: Absolute value encoder (Hiperface)".
 - From version 14.00.00, the selection "6: Position encoder (Hiperface)" is possible as well.

When the encoder has already been connected, a change of [C00422](#) causes a renewed [Initialisation](#) of the connected encoder.

- After the initialisation and with a known encoder, the read-out values are displayed in [C00494/1..2](#) and cannot be overwritten.
 - If the value "0xFF" is displayed as TypeCode in [C00492](#), it is an encoder with an extended nameplate. Currently, the settings for this encoder cannot be automatically read out of the encoder yet and thus have to be carried out manually. See the following instructions "[How to parameterise an absolute value encoder with an unknown type code](#)".
 - If the value "0x00" is displayed as type code, the encoder has not been detected automatically. In this case, make the settings manually as well. See the following instructions "[How to parameterise an absolute value encoder with unknown type code](#)".
3. **Only for version 01.xx.xx:** Set the number of sine/cosine periods per revolution as "increment" of the encoder in [C00420/3](#).
 - This value can be obtained from the encoder data sheet.
 - This point must be executed last since it initiates a renewed readout of the encoder.
 - From version 02.00.00, this setting will be obtained and set automatically.
 4. If you use the encoder as motor encoder and synchronous motor of a third party manufacturer:
Carry out [Pole position identification \(PPI\)](#). ([□ 358](#))
 5. For detecting and monitoring the motor temperature via the Encoder cable:
Parameterise [Motor temperature monitoring \(KTY\) via encoder](#). ([□ 375](#))
 6. Optional: Parameterise [Resolver/multi-encoder open-circuit monitoring](#). ([□ 369](#))
In the Lenze setting, the resolver cable and/or encoder cable are monitored with regard to open circuit as a function of the selected speed and position encoder.
 7. For a permanent acceptance of the parameter settings:



Save parameter set.



How to parameterise a SinCos absolute value encoder with unknown type code:

If the encoder is not detected automatically, the value "0x00" is displayed in [C00492](#) as TypeCode. In this case, make the settings manually:

1. Set the number of steps per revolution in [C00494/2](#).
2. Set the number of revolutions for a multiturn encoder in [C00494/1](#).
3. Set the number of sine/cosine periods per revolutions as "increment" of the encoder in [C00420/3](#).
 - This value can be obtained from the encoder data sheet.
 - This point must be executed last since it initiates a renewed readout of the encoder.
4. If you use the encoder as motor encoder and synchronous motor of a third party manufacturer:
Carry out [Pole position identification \(PPI\)](#). (📖 358)
5. For detecting and monitoring the motor temperature via the Encoder cable:
Parameterise [Motor temperature monitoring \(KTY\) via encoder](#). (📖 375)
6. Optional: Parameterise [Resolver/multi-encoder open-circuit monitoring](#). (📖 369)
In the Lenze setting, the resolver cable and/or encoder cable are monitored with regard to open circuit as a function of the selected speed and position encoder.
7. For a permanent acceptance of the parameter settings:



Save parameter set.

6.3.2.3 Display of the current position

In [C01119/1](#), the current actual position of the motor shaft is displayed in [units]. It is calculated from the actual value of the encoder selected in [C00422](#):

$$C01119/1 = \left(\text{Pos} \cdot C01204 \cdot \frac{C01202/2}{C01202/1} \cdot \frac{C01203/1}{C01203/2} \right) + C01112/1$$

Pos = encoder position in increments

- For rotative encoders, the following applies: 65536 increments = 1 revolution
- For linear encoders, the following applies: 65536 increment = 1 increment path

[6-2] Actual position calculation

As the term "revolution" does not make any sense in case of linear encoders, the distance covered is defined as the path in which the increments or SinCos periods parameterised in [C00420/3](#) are completely run through once. In of rotative encoders, this corresponds to exactly one encoder revolution.

Internal conversion of the encoder information on the motor shaft position

In the controller, the information of the Hiperface track are factorised so that a revolution of the encoder corresponds to 65536 increments which means a passage of the increments or SinCos periods parameterised in [C00420/3](#). The same applies to linear encoders.

The factor is automatically calculated from the encoder data ([C00494/1..2](#)) that have either been saved in the device or manually configured.

Example: 4096 Hiperface increments per revolution → Factor = 65536/4096 = 16

In case of linear encoders, a conversion to one revolution of the motor or gearbox output shaft is made, too. This conversion is made considering the traversing path set in [C01111/3](#) which is covered during a passage of the increments and sin/cos periods parameterised in [C00420/3](#):

$$\text{Pos}_{\text{Mot}} = \text{Pos}_{\text{In}} \cdot \frac{C01111/3}{C01204}$$

[6-3] Conversion to one revolution of the motor or gearbox output shaft in case of linear encoders

Related topics:

- ▶ [Scaling of position value](#)

6.3.2.4 Notes on evaluating absolute value encoder of SEL37 and SELxx types by SICK

For version 02.xx.xx the following applies:

- The 8400 TopLine controller recognises these encoder types, but sporadically reports the error "[Sd4: open circuit MultiEncoder](#)" error if the open-circuit monitoring is activated in [C00603/1](#) (Lenze setting).
 - The reason for this is a faulty open-circuit monitoring during the initialisation of the controller.
 - The error can be acknowledged so that the controller is able to start correctly.
- Moreover, the initialisation time of the encoder is critical. This is the time needed internally by the encoder to respond to a read request of the controller.
 - The maximum initialisation time in the controller is permanently set to 5.2 s. Depending on the encoder used, it may be possible that this time is not sufficient (see data sheet for the encoder manufacturer)!
- If the monitoring (e.g. die open-circuit monitoring) triggers with the "Fault" error response due to an encoder error during operation, the position is not valid anymore in case of absolute value encoders and must be reread from encoder.
 - After the error message is reset, this does not take place automatically which may cause a wrong position!
 - **Remedy:** After the error message is reset with the SB [LS_ParReadWrite_1](#), rewrite the code [C00422](#) and thus enforce a re-initialisation of the encoder. Then enable the application.

From version 12.00.00 the following applies:

- The initialisation time of the encoder is not critical anymore since the maximum initialisation time can now be adjusted in [C00430/1](#) (to max. 20 seconds).
 - During the set initialisation time, the controller remains in the "Init" device state and cannot be enabled.
 - The open-circuit monitoring is also suppressed during the set initialisation time so that the error behaviour of the version 02.xx.xx is remedied as well.
- If the monitoring (e.g. die open-circuit monitoring) triggers with the "Fault" error response due to an encoder error during operation, the position is not valid anymore in case of absolute value encoders and must be reread from encoder.
 - After the error message is reset, this takes place automatically.

6.3.2.5 Configuration example 1: Absolute wire draw encoder "XKS09-HTBM0527" by SICK

Data

- Wire length: 5 m
- Hiperface resolution: 4096 digits x 4184 "revolutions"
- SinCos resolution: 128 increments (1 period \equiv 1.1953 mm \rightarrow 153 mm \equiv one "revolution")
- 1 [unit] = 1 mm
- Feed of the mechanics = 4 mm/revolution

Scaling of the position value

In order to scale the evaluation of the SinCos track, the traverse path in [units] has to be entered in [C01111/3](#) which is covered in order to pass through once the SinCos increment of the encoder ([C00420/3](#)) (here 128 increments x 1.1953 mm period length = 153 mm).

The absolute Hiperface track is scaled by the setting of the "steps per revolution" in [C00494/2](#). Here, a revolution is equated to the path which corresponds to the SinCos number of increments of the encoder ([C00420/3](#)).

Required settings

Parameter	Info	Setting for example
C00494/1	Hiperface: Number of revolutions	4184
C00494/2	Hiperface: Steps per revolution	4096
C01110	LS_MultiEncoder: Solid measure	1: linearly unipolar
C01111/3	LS_MultiEncoder: Traverse path - encoder increment	153

In "[Machine parameters](#)", the feed constant and the gearbox factors for motors and position encoders must be set as follows:

- The position encoder gearbox factor must be set to 1:1.
- When the motor gearbox factor is set to 1:1, the path covered at one motor revolution has to be entered as feed constant in [C01204](#) in [units].
- In case of a different motor gearbox factor, the path covered at one defined "drive roll" revolution has to be entered as feed constant in [C01204](#) in [units].

The feed of the mechanics entered in [C01204](#) (here: 4 mm) is displayed with 65536 increments.

6.3.2.6 Configuration example 2: Distance sensor "DME5000-117" by SICK

Data

from DME5000 operating instructions (8009813/US35/2012-07-02):

Period Length (mm)	Type code	Resolution RS-485 (mm)	Resolution sin/cos when zero crossings are counted (mm)
1	90h	1/32	0.25
2	91h	1/16	0.5
4	92h	1/8	1
8	93h	1/4	2
16	94h	1/2	4

- Maximum distance: 70 m
- Default setting of parameter "Period Length": 1 mm
(4 zero crossings while passing one period * 0.25 mm = 1 mm)
- Default setting of parameter "Resolution": 125 µm (must not be changed)

These default settings result in the following resolutions:

- 1 "encoder revolution" = 10 mm
- Hiperface resolution: 1/32 mm → 320 digits per "revolution" x 7000 "revolutions"
- Sin/cos resolution: 10 increments per "revolution"
(1 period ≡ 1 mm → 10 mm ≡ one "revolution" = 10 periods or increments)
- 1 [unit] = 1 mm

Scaling of the position value

In order to scale the evaluation of the SinCos track, the traverse path in [units] has to be entered in [C01111/3](#) which is covered in order to pass through once the SinCos increment of the encoder ([C00420/3](#)) (here 10 increments x 1 mm period length = 10 mm).

The absolute Hiperface track is scaled by the setting of the "steps per revolution" in [C00494/2](#). Here, a revolution is equated to the path which corresponds to the SinCos number of increments of the encoder ([C00420/3](#)).

Required settings

Parameter	Info	Setting for example
C00494/1	Hiperface: Number of revolutions	7000
C00494/2	Hiperface: Steps per revolution	320
C01110	LS_MultiEncoder: Solid measure	1: linearly unipolar
C00420/3	LS_MultiEncoder: Encoder increment	10
C01111/3	LS_MultiEncoder: Traverse path - encoder increment	10

6.3.3 SSI absolute value encoder with Stegmann-SSI protocol

All SSI encoders which use the Stegmann SSI protocol are supported.

- Supported bit rates for SSI communication: 100 ... 1000 kbits
- Supported data word widths: 1 ... 31 bits (effective)
- Supported output code of the SSI encoder: Gray or binary
- The SSI encoder can be used as position encoder or master encoder with a minimum cycle time of 1 ms.
- The SSI encoder can be supplied via X8 up to a maximum voltage of 12 V and a maximum current of 0.25 A.
- The received SSI data words are provided to the application via the [LS MultiEncoder](#) system block for further processing in the function block editor.



Note!

For some SSI encoder types it is common that despite a high data transfer rate a slow position detection (e.g. every 5, 10 or 20 ms) takes place. In this case, the position control, working in a 1-ms cycle, only functions with low gain and thus low dynamics since the values of the SSI encoder are only updated every x ms.

When an external SSI laser position encoder is used at X8:

Also observe the [Notes for using an SSI laser position encoder](#) at the end of this chapter. (341)

6.3.3.1 Parameterising the encoder

Parameterisation dialog (cutout)

Multi-Encoder (X8)

Encoder type	<input type="text" value="C"/> Absolute value en	
Supply voltage	<input type="text" value="5.0"/>	V
TTL encoder increment	<input type="text" value="512"/>	Incr./rev.
Encoder filter time	<input type="text" value="1.0"/>	ms
Position offset	<input type="text" value="0.0000"/>	units

Position value scaling... SSI configuration...

Further parameterisation dialogs: [Scaling of position value](#) [SSI configuration](#)

Parameter	Info	Lenze setting	
		Value	Unit
C00422	LS_MultiEncoder: Encoder type	0: Incremental encoder (TTL)	
C00421	LS_MultiEncoder: Supply voltage	5.0	V
C01112/1	LS_MultiEncoder: Position offset	0.0000	units

SSI configuration

Press the **SSI configuration...** button to get to the parameterisation dialog for configuring the SSI encoder:

Parameter	Info	Lenze setting	
		Value	Unit
General			
C00428	SSI encoder: Coding	0: Binary code	
C00427	SSI encoder: Bit rate	1: 100 kbps	
C00426/1	SSI encoder: Data word length	25	
C00426/7	SSI encoder: Shift of raw value	0	
C00426/6	SSI encoder: Status bit 1	0	
C00426/8	SSI encoder: Status bit 2	0	
C00426/9	SSI encoder: Status bit 3	0	
Partword 2: Multiturn			
C00426/5	SSI encoder: Start bit Multiturn	13	
C00426/4	SSI encoder: Bits Multiturn	12	
Partword 1: Singleturn			
C00426/3	SSI encoder: Start bit Singleturn	0	
C00426/2	SSI encoder: Bits SingleTurn	13	



How to parameterise the SSI encoder:

1. Set the supply voltage ([C00421](#)) of the used SSI encoder.
In case of a higher supply power of encoders, e.g. with laser-based length measuring systems, an external supply of the encoders must be provided.
2. As encoder type ([C00422](#)), select "4: Absolute value encoder (SSI)".
3. Set the bit rate ([C00427](#)) for SSI communication.
 - For SSI protocols, the permissible baud rate is reduced if the cable length is increased. A safe bit rate must be set, depending on the length of the used encoder cable and the electromagnetic interference level.
4. Set the partitioning of the SSI data word in [C00426/1...5](#) according to the used SSI encoder (see [Configuration example 1](#)).
5. If an SSI encoder with Gray coding is used:
Select "1: Gray code" in [C00428](#) to convert from Gray to binary.
 - In the Lenze setting "0: Binary code", no conversion takes place, i.e. an SSI encoder with binary coding is expected.
6. If a linear SSI encoder is used instead of a rotative encoder or the encoder value is to be interpreted with or without sign:
Set the corresponding standard in [C01110](#). ▶ [Scaling of position value](#)

SSI encoder coding "Position Gray"

From version 14.00.00 onwards, also SSI encoders are supported that transfer the position data in Gray coding and the status bit in binary mode (uncoded). For an encoder with this coding, select "2:Position Gray" in [C00428](#). Then, only the pure position data are converted from Gray to binary code, and status bits provided by the encoder are directly evaluated. The position data converted to binary format are then added to the status bits again and provided as raw value at the outputs *wHighWord* and *wLowWord* of the [LS MultiEncoder](#). This takes place as a provision of the position raw value in gray code would not make any sense; the value, in case of a linear encoder, would feature jumps instead of a linear characteristic.

Evaluation of further status bits

From version 14.00.00 onwards, two more status bits of the SSI encoder can be evaluated. The bits to be evaluated in the SSI data current have to be set in [C00426/8..9](#).

If the evaluation of a status bit shall be deactivated completely, the value "32" has to be entered into the corresponding code. Thus, the status bit always has the value "0".

Left shift of raw value

The data read-in by the encoder is processed via the settings of the start bits for singleturn and multiturn and the number of bits in such a way that a position signal suitable for the controller is created that can be fed into the function block interconnection.

The raw value of the received data coming from the SSI encoder is provided at the outputs *wHighWord* and *wLowWord* of the [LS MultiEncoder](#). It is always provided in binary format, i.e. in case of Gray code encoders after the received data is decoded. The MSB of the data is positioned at bit 16 of the *wHighWord* output.

In order to receive a standard data format (LSB at the lowest position) an offset can be set in [C00426/7](#). The setting [C00426/7](#) = 32 - data word length serves to display the raw value of the received data telegram so that the LSB is at bit 0 of the *wLowWord* output:

Clarification of the data sequence when the data word length is = 26 bits																																	
wHighWord																wLowWord																	
15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0		
Data sequence without offset (C00426/7 = 0):																																	
25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0								
Data sequence with an offset by 6 bits (C00426/7 = 6):																																	
								25	24	23	22	21	20	19	18	17	16	15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0

6.3.3.2 Important notes for using an SSI laser position encoder

If you are using an SSI laser position encoder at X8 and, deviating from the Lenze setting, you have activated the position control for quick stop ([C00104/1](#) - bit 0 and/or bit 1 set), please note the following:

If the laser beam is interrupted, due to the "TroubleQuickStop" following error standard response, the drive may move unexpectedly.

- A drive that had already reached the position-controlled standstill can execute a movement.
- A drive that is ramping down can continue running.

Possible countermeasures:

- Do not use the controller with the above-described parameter setting.
- By implementing suitable other measures, ensure that, in terms of safety aspects, the response described is acceptable for the specific application case.
- Monitor the valid position:
 - Use parameters [C01112/2](#) and [C01112/3](#) to define a value range for valid positions.
 - Configure the [LS MultiEncoder.bFail](#) output so that controller inhibit is set when the output at the drive is active. Take other requirements relating to the application into consideration (e.g. application of brake).
 - Resulting drive behaviour: If the value range set is exited, the [LS MultiEncoder.bFail](#) output activates controller inhibit. ▶ [Encoder value monitoring](#)

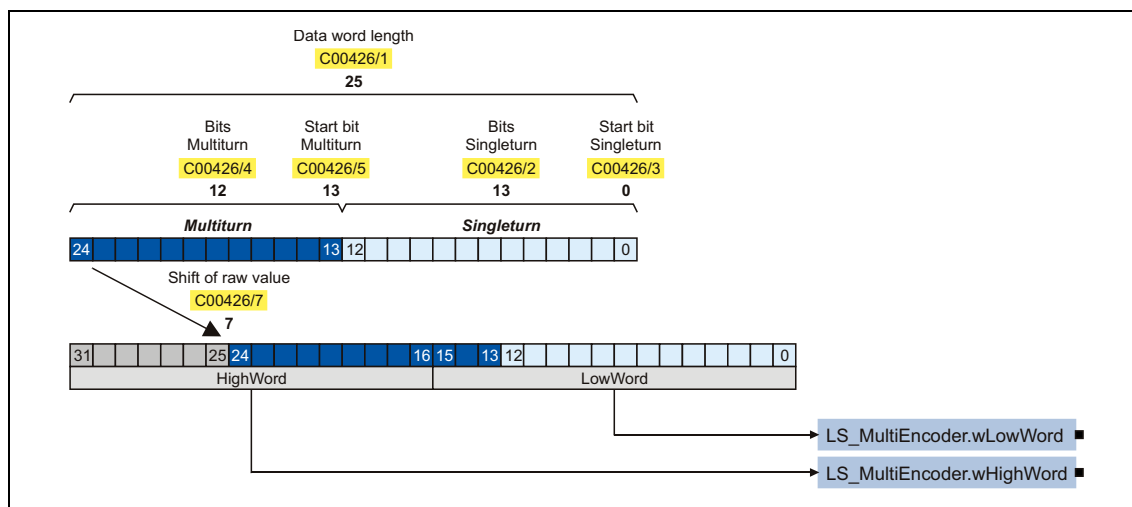


Note!

The response of the drive to interruptions of the laser beam is always part of the error scenarios to be checked during commissioning.

6.3.3.3 Configuration example 1: Optical multi-turn rotary encoder "G0M2H Z04" by Baumer

Coding: Gray code with 25 bit data word length (8192x4096)



Parameter	Info	Setting for example 1
C00426/1	SSI encoder: Data word length	25
C00426/2	SSI encoder: Bits SingleTurn	13
C00426/3	SSI encoder: Start bit Singleturn	0
C00426/4	SSI encoder: Bits Multiturn	12
C00426/5	SSI encoder: Start bit Multiturn	13
C00426/6	SSI encoder: Status bit 1	0 (32)*
C00426/7	SSI encoder: Shift of raw value	7
C00426/8	SSI encoder: Status bit 2	0 (32)*
C00426/9	SSI encoder: Status bit 3	0 (32)*
C00428	SSI encoder: Coding	1: Gray code
C01110	LS_MultiEncoder: Solid measure	0: rotatively unipolar

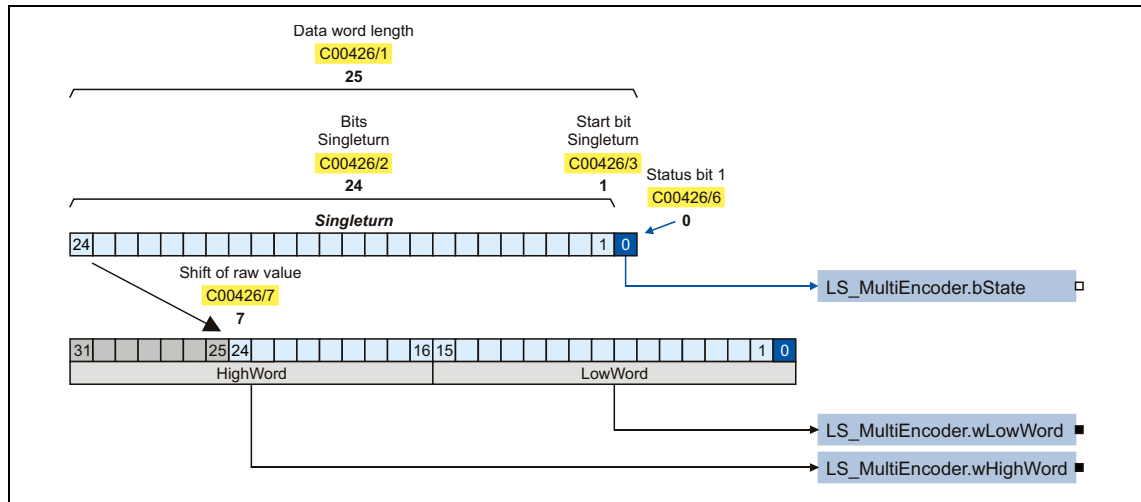
* As the encoder data word in this example does not contain any status bits, you the evaluation of the status bits can also be deactivated completely by entering the value "32" in [C00426/6](#), [C00426/8](#) and [C00426/9](#). Thus, the three status bit outputs of the [LS_MultiEncoder](#) always have the value "0".

- In "[Machine parameters](#)", the feed constant and the gearbox factors for motor and position encoder must be set correctly. ([582](#))
- One encoder revolution is displayed with 65536 increments.

6.3.3.4 Configuration example 2: Distance sensor "DME5000-111" by SICK

Coding: Gray code with 25 bits of data word length

(Bit 0 = status bit in binary format, bit 1 ...24 = position, resolution 1 bit = 0.1 mm)



Parameter	Info	Setting for example 2
C00426/1	SSI encoder: Data word length	25
C00426/2	SSI encoder: Bits SingleTurn	24
C00426/3	SSI encoder: Start bit Singleturn	1
C00426/4	SSI encoder: Bits Multiturn	0
C00426/5	SSI encoder: Start bit Multiturn	0
C00426/6	SSI encoder: Status bit 1	0
C00426/7	SSI encoder: Shift of raw value	7
C00426/8	SSI encoder: Status bit 2	0 (32)*
C00426/9	SSI encoder: Status bit 3	0 (32)*
C00428	SSI encoder: Coding	2: Position Gray
C01110	LS_MultiEncoder: Solid measure	1: linearly unipolar

* As the encoder data word in this example contains only one status bit, the evaluation can be deactivated completely by entering the value "32" in [C00426/8](#) and [C00426/9](#). Thus, the status bit outputs *bState2* and *bState3* of the *LS_MultiEncoder* always have the value "0".

In "[Machine parameters](#)", the feed constant and the gearbox factors for motors and position encoders must be set as follows:

- The position encoder gearbox factor must be set to 1:1.
- When the motor gearbox factor is set to 1:1, the path covered at one motor revolution has to be entered as feed constant in [C01204](#) in [units].
- In case of a different motor gearbox factor, the path covered at one defined "drive roll" revolution has to be entered as feed constant in [C01204](#) in [units].
- The feed of the mechanics entered in [C01204](#) is displayed with 65536 increments.

Scaling of the position value

In order to scale the position change provided by the position encoder at this feed to 65536 as well, enter the traverse path in [units] in [C1111/1](#) and the corresponding difference of the raw value provided by the encoder in [C1111/2](#).

- Only the bits that contain the position data may be taken from the data word for the raw value. If e.g. the bit 0 contains status information, the raw value must be shifted to the right by this bit since only then the SLB of the position value is positioned correctly.

Example for scaling

1 [unit] = 1 mm

Feed constant ([C01204](#)) = 4 mm/revolution

Encoder resolution = 50 µm → raw value difference = 20 [digit]/1 [unit]

→ Difference - traverse path ([C1111/1](#)) = 1 [unit]

→ Difference - encoder value ([C1111/2](#)) = 20 [digit]

Thus, at a feed of the mechanics of 4 mm, the encoder provides a position difference of 65536 increments.

$$\begin{aligned} \text{Position} &= \text{Raw value} \cdot \frac{\text{Encoder feed constant}}{65536} \\ \text{with encoder feed constant} &= \frac{C01111/1 \cdot 65536^2}{C01111/2 \cdot C01204} \\ \text{Position} &= \text{Raw value} \cdot \frac{C01111/1 \cdot 65536}{C01111/2 \cdot C01204} \end{aligned}$$

6.3.4 Digital frequency coupling

This function extension is available from version 12.00.00!

The multi-encoder interface (X8) can also be reconfigured for the output of encoder signals with TTL level (0 ... 500 kHz) in order to realise a "digital frequency coupling".

- The "digital frequency coupling" term describes a digital setpoint transmission and evaluation path between a setpoint source and one or several controllers.



Note!

When the digital frequency coupling is used, the multi-encoder interface is not available anymore for further encoder functions! Only encoder signals with TTL level are permissible as input signals at X8!

Parameterisation dialog (cutout)

Further parameterisation dialogs: [Scaling of position value](#)

Parameter	Info	Lenze setting	
		Value	Unit
C00422	LS_MultiEncoder: Encoder type	0: Incremental encoder (TTL)	
C00421	LS_MultiEncoder: Supply voltage	5.0	V
C00420/3	LS_MultiEncoder: Encoder increment	512	Incr./rev.
C00497/3	LS_MultiEncoder: Encoder filter time	1.0	ms
C01112/1	LS_MultiEncoder: Position offset	0.0000	units
C00030/1	LS_DFOut: number of increments	2048	
C00540	LS_DFOut: Function	2: DFln	

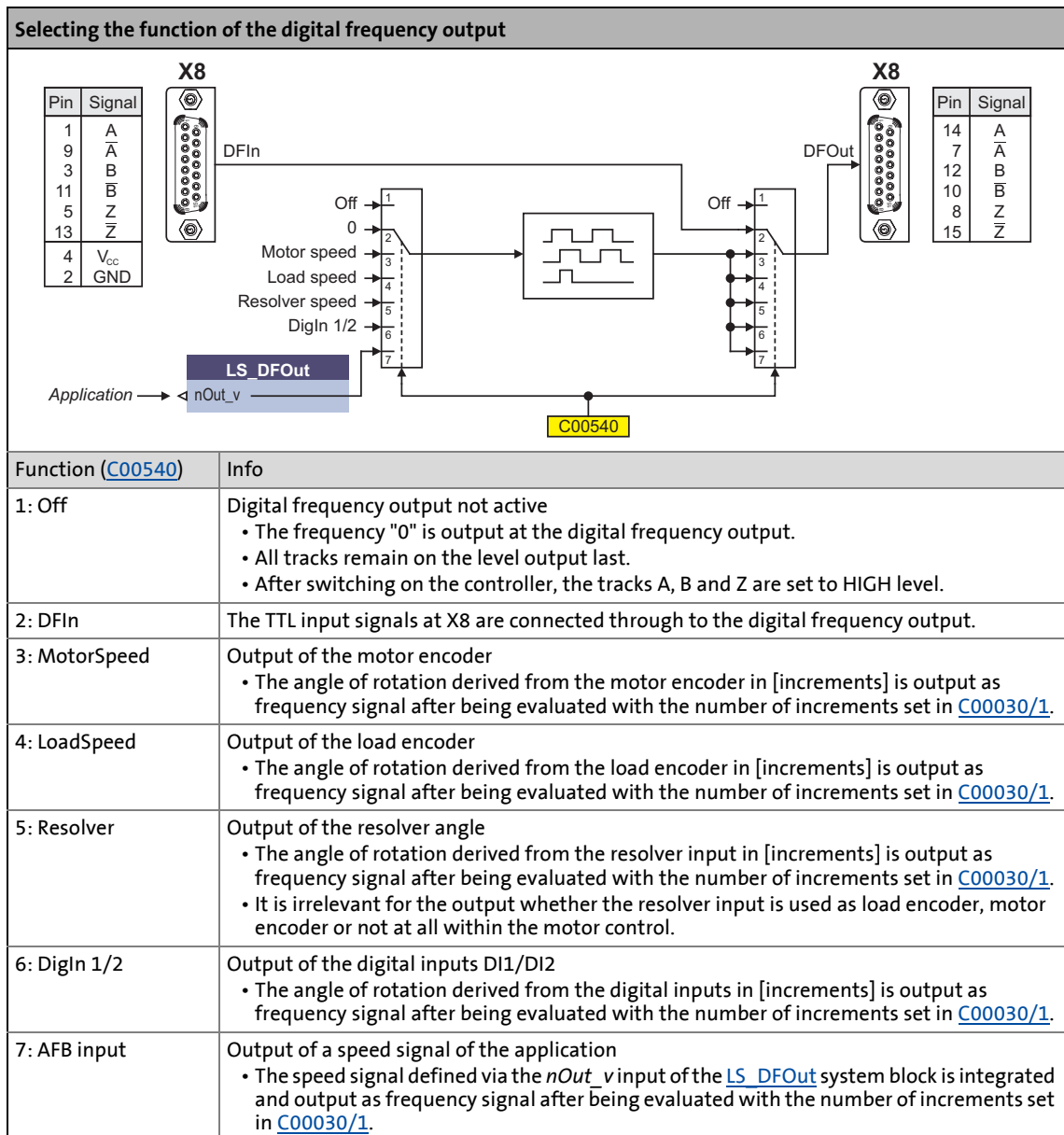


How to parameterise the master frequency output:

1. As encoder type ([C00422](#)), select "5: LF In/Out" to activate the master frequency output.
2. Set the number of increments for the digital frequency output in [C00030/1](#).

The number of increments determines after how many output increments a zero pulse will be generated. Each zero pulse defines a covered "revolution" of the rotary transducer simulated by the digital frequency output.

3. Set the desired function of the digital frequency output in [C00540](#) (see the following section).



6.3.4.1 Problem description - speed variations

As digital frequency, rectangular encoder signals are processed. The speed can be determined by counting edges and a defined time interval (1 ms). This defined time interval of 1 ms and a finite number of encoder increments per revolution cause the calculated speed signal to only accept discrete values. This gives the impression of a very disturbed and incorrect signal. This effect increases with a lower number of increments.

Example: An encoder with 2048 increments at a speed of 60 rpm is to be simulated via the digital frequency output.

- Setpoint speed $n_{Out_v} = 60 \text{ rpm} = 1 \text{ Hz}_{\text{mech.}}$
- Simulated encoder: 2048 increments
(by 4-fold evaluation, $4 * 2048 = 8192$ edges are counted per revolution)
- Output frequency = $n_{Out_v} * \text{number of increments}$ ([C00030/1](#)) = $1 \text{ Hz}_{\text{mech.}} * 2048 = 2048 \text{ Hz}$

At a measurement time of 1 ms, 8,192 edges per ms are achieved. As only integer counting processes can occur, sometimes 8 and sometimes 9 increments are counted. Hence, the speed is calculated as follows:

$$n_{\text{mess_1}} = 60 \text{ rpm} \cdot \frac{8}{8.192} = 58.59 \text{ rpm}$$

or

$$n_{\text{mess_2}} = 60 \text{ rpm} \cdot \frac{9}{8.192} = 65.91 \text{ rpm}$$

The perceived speed variation amounts to:

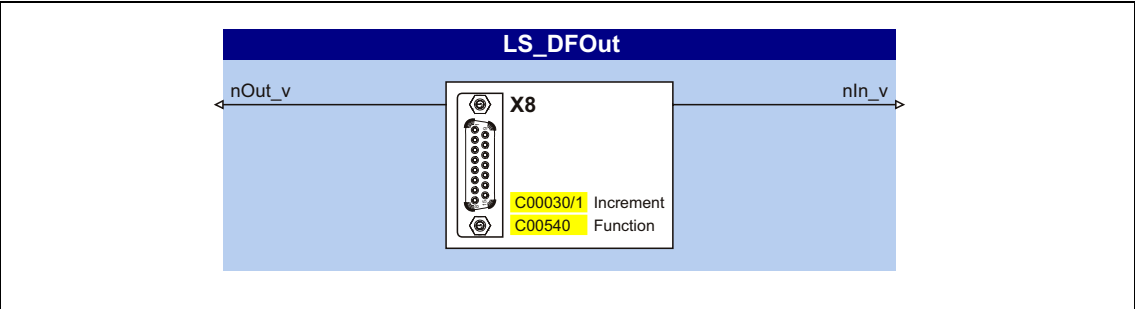
$$\Delta n_{\text{mess}} = n_{\text{mess_2}} - n_{\text{mess_1}} = 7.32 \text{ rpm}$$

General formula for calculating the expected speed variation

$$\Delta n_{\text{mess}} = \frac{15000}{\text{Number of increments}}$$

6.3.4.2 Internal interfaces | System block "LS_DFOut"

The LS_DFOut system block maps the digital frequency output in the FB Editor:



Inputs

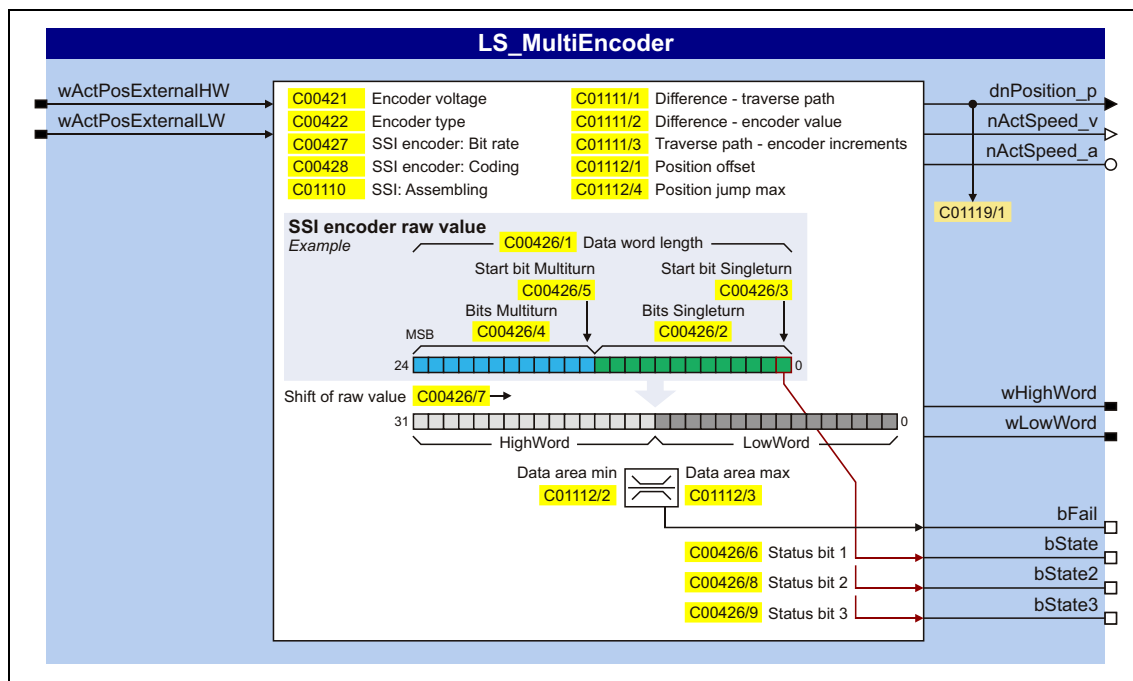
Identifier	Data type	Information/possible settings
nOut_v	INT	Speed in [increments/ms] from the application which is to be output via the digital frequency output X8 in the form of encoder signals with TTL levels. <ul style="list-style-type: none">• Scaling: 16384 \equiv 15000 rpm• For selecting this signal source, C00540 must be set to "7: AFB input".

Outputs

Identifier	Data type	Value/meaning
nIn_v	INT	Speed in [increments/ms] that has been detected via the digital frequency input X8 in the form of encoder signals with TTL levels. <ul style="list-style-type: none">• Scaling: 16384 \equiv 15000 rpm

6.3.5 Internal interfaces | System block "LS_MultiEncoder"

The **LS_MultiEncoder** system block provides the application with speed, position and error information from the encoder connected to the multi encoder interface X8 in the form of process signals.



Inputs

Identifier	Data type	Information/possible settings
wActPosExternalHW wActPosExternalLW	WORD	These inputs serve to feed in the position signal of an external encoder (e.g. via CAN or another fieldbus) and use it as position signal. Scaling: LW = 1 revolution, HW = number of revolutions Thus, an encoder revolution is displayed with 65536 increments.
(from version 14.00.00)		

Outputs

Identifier	Data type	Value/meaning
dnPosition_p	DINT	Actual position value from the encoder in [increments]
nActSpeed_v	INT	Actual speed from the encoder in [increments/ms]
nActSpeed_a	INT	Actual speed from the encoder in [%] • 100 % ≡ reference speed (C00011)
wHighWord wLowWord	WORD	32-bit data telegram from the encoder (raw data) ▶ SSI absolute value encoder with Stegmann-SSI protocol (337) The output is always made in binary format, i.e. in case of Graycode encoders after the received data is decoded. The MSB of the data is at bit 16 of the <i>wHighWord</i> output. In order to obtain a standard data format (LSB at the lowest position), an offset can be set in C00426/7 . ▶ Left shift of raw value (340)

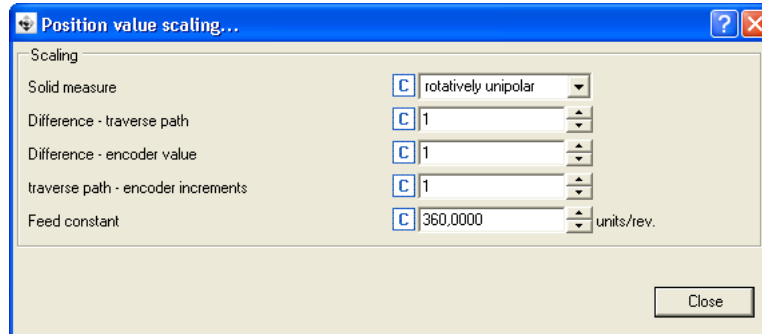
Identifier	Data type	Value/meaning
bFail	BOOL	TRUE Group error: There is an error (e.g. encoder wire breakage) according to the <i>bFail</i> configuration in C00431/1 . From version 14.00.00, the error type is displayed bit-coded in C00451/1 . ▶ Monitoring
bState (from version 02.00.00)	BOOL	Status bit 1 of the encoder <ul style="list-style-type: none"> The bit position of the status bit within the 32-bit data telegram can be set in C00426/6. If C00426/6 = "32", the evaluation of the status bit 1 is deactivated and FALSE is always output at <i>bState</i>.
bState2 (from version 14.00.00)	BOOL	Status bit 2 of the encoder <ul style="list-style-type: none"> The bit position of the status bit within the 32-bit data telegram can be set in C00426/8. If C00426/8 = "32", the evaluation of the status bit 2 is deactivated and FALSE is always output at <i>bState2</i>.
bState3 (from version 14.00.00)	BOOL	Status bit 3 of the encoder <ul style="list-style-type: none"> The bit position of the status bit within the 32-bit data telegram can be set in C00426/9. If C00426/9 = "32", the evaluation of the status bit 3 is deactivated and FALSE is always output at <i>bState3</i>.

Display parameter

Parameter	Info	Lenze setting	
		Value	Unit
C01119/1	LS_MultiEncoder: Current position	-	units
C01119/2	LS_MultiEncoder: Maximum travel distance	-	units
Highlighted in grey = display parameter			

6.3.5.1 Scaling of position value

If you click the **Scaling of position value...** button in the parameterisation dialog for the encoder/feedback system in the category "Multi-Encoder (X8), you get to the respective parameterisation dialog:



Short overview of the relevant parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C01110	LS_MultiEncoder: Solid measure • Setting of rotative or linear encoders. Note: The selection "rotative" or "linear" only has an impact if the encoder has not been detected automatically or the encoder data definitely are to be taken from the codes (bit 0 in C00499/1 is set to "1"). The "unipolar" or "bipolar" selection definitely has an impact.	0: rotatively unipolar	
Settings for linear SinCos absolute value encoder with HIPERFACE® protocol			
C01111/1	LS_MultiEncoder: Difference - traverse path • Specification of the traverse path while passing through the step number of the Hiperface track given in C01111/2 . • Setting is relevant for parameter channel.	1	units
C01111/2	LS_MultiEncoder: Difference - encoder path • Step number of the Hiperface track. • Setting is relevant for parameter channel.	1	Steps
C01111/3	LS_MultiEncoder: Traverse path - encoder increment • Specification of the traverse path while passing through the number of increments of the SinCos track given in C00420/3 . • Setting is relevant for process data channel (incremental SinCos track).	1	units
Further settings			
C01204	MCK: Feed constant	360.0000	units/rev.

6.3.5.2 Setting of a static position offset

If, for example, the encoder cannot be mounted mechanically in order that the supplied position matches the mechanics or if for other reasons, a static position offset is required, this value can be set in [C01112/1](#).

6.4

Frequency HTL encoder (DI1/DI2, DI6/DI7)

Parameterisation dialog (cutout)

☐ Frequency HTL-Encoder (DI1/DI2, DI6/DI7)

Frequency input DI1/DI2		Frequency input DI6/DI7	
Fct. DI 1/2 200kHz	<input type="text" value="C"/> <input type="text" value="DI1(6)=In / DI2(7)"/> ▾	Fct. DI 6/7 10kHz	<input type="text" value="C"/> <input type="text" value="DI1(6)=In / DI2(7)"/> ▾
FreqIn12: Encoder increment	<input type="text" value="C"/> <input type="text" value="128"/> ▴ ▾ Incr./rev.	FreqIn67: Encoder increment	<input type="text" value="C"/> <input type="text" value="128"/> ▴ ▾ Incr./rev.
FreqIn12: Encoder filter time	<input type="text" value="C"/> <input type="text" value="1.0"/> ▴ ▾ ms	FreqIn67: Encoder filter time	<input type="text" value="C"/> <input type="text" value="1.0"/> ▴ ▾ ms
FreqIn12: Encoder scanning time	<input type="text" value="C"/> <input type="text" value="10 ms"/> ▴ ▾	FreqIn67: Encoder scanning time	<input type="text" value="C"/> <input type="text" value="10 ms"/> ▴ ▾
Encoder evaluation method DigIn12	<input type="text" value="C"/> <input type="text" value="comb. encoder p"/> ▾		

Note:
A rotary transducer (C115=2) or a two-track encoder (C115=3) can be connected via the "DI1/6 and DI2/7 function assignment" parameter (C115) when two digital inputs are used. The digital inputs are configured via the "Terminal assignment" tab.

Parameter	Info	Lenze setting	
		Value	Unit
Settings for HTL encoder at DI1/DI2			
C00115/1	Fct. DI 1/2 200kHz • Function of the digital inputs DI1 and DI2	0: DI1(6)=In / DI2(7)=In	
C00420/1	FreqIn12: Encoder increment • If the digital inputs DI1 and DI2 are used as encoder inputs.	128	Incr./rev.
C00497/1	FreqIn12: Encoder filter time • If the digital inputs DI1 and DI2 are used as encoder inputs.	1.0	ms
C00425/1	FreqIn12: Encoder scanning time • If the digital inputs DI1 and DI2 are used as encoder inputs.	10	ms
C00496	► Encoder evaluation method DigIn12 (□ 355)	2: Comb. encoder method	
Settings for HTL encoder at DI6/DI7			
C00115/2	Fct. DI 6/7 10kHz • Function of the digital inputs DI6 and DI7	0: DI1(6)=In / DI2(7)=In	
C00420/2	FreqIn67: Encoder increment • If the digital inputs DI6 and DI7 are used as encoder inputs.	128	Incr./rev.
C00497/2	FreqIn67: Encoder filter time • If the digital inputs DI6 and DI7 are used as encoder inputs.	1.0	ms
C00425/2	FreqIn67: Encoder scanning time • If the digital inputs DI6 and DI7 are used as encoder inputs.	10	ms

6.4.1 Parameterising digital inputs as encoder inputs

The function of the digital inputs DI1/DI2 and DI6/DI7 is defined via [C00115/1...2](#).

To be able to use the digital inputs as encoder inputs, select 2, 3, or 4 (Lenze recommendation: 2) in [C00115/1](#) or [C00115/2](#), depending on the input terminals used.

Selection in C00115/1...2	Function
2: DI1(6)&DI2(7)=FreqIn (2-track)	DI1/6 and DI2/7 = 2-track frequency input • Permits a two-track evaluation of the encoder including correct detection of the direction of rotation.
3: DI1(6)=FreqIn / DI2(7)=Direction	DI1/6 = 1-track frequency input DI2/7 = specification of direction
4: DI1(6)=CountIn / DI2(7)=In	DI1/6 = counter input DI2/7 = digital input



Danger!

- For single-track evaluation, make sure that the sign is correctly specified. Otherwise, the motor may overspeed.
- If servo control (SC) or V/f control (VFCplus + encoder) are used: For safety reasons, always select "Fault" (Lenze setting) in [C00586](#) as a response for the (open-circuit) monitoring of the encoder!
- If an HTL encoder is used at the digital input terminals:
Observe the maximum input frequencies of the digital inputs!
 - DI1/DI2: max. 200 kHz
 - DI6/DI7: max. 10 kHz



Note!

If the digital inputs are parameterised as encoder inputs, the corresponding output signals (*bln1/bln2* and *bln6/bln7*) at the [LS DigitalInput](#) system block are automatically set to FALSE.



Wiring diagram, assignment and electrical data of the digital input terminals can be found in the **hardware manual 8400** in the chapter "technical data". The hardware manual is stored in electronic form on the data carrier supplied with the 8400 controller.

General procedure

(if the encoder is connected to the digital inputs DI1 and DI2)

1. Define the function of the digital inputs DI1 and DI2 in [C00115/1](#).
2. Set the encoder increments in [C00420/1](#).
3. Select "1: Encoder signal FreqIn12" in [C00495/1](#).
4. Adapt the filter time of the speed measurement in [C00497/1](#).
5. In the case of encoders with a very low resolution (number of increments < 120 increments):
Change the encoder evaluation procedure in [C00496](#) if necessary.

Related topics:

- ▶ [Digital input terminals](#) (📖 377)
- ▶ [Using DI1\(6\) and DI2\(7\) as frequency inputs](#) (📖 381)

6.4.2 HTL encoder at DI1/DI2



Note!

At the digital terminals DI1 and DI2, only encoders with HTL level can be used.

In spite of the selected operating mode without encoder feedback, the actual speed value ([C00051](#)) is calculated if an encoder is connected and "1: Encoder signal FrqIn12" is selected in [C00495](#).

Encoder evaluation method DigIn12

Depending on the encoder used at the digital inputs DI1 and DI2, the following table specifies which evaluation method should be selected in [C00496](#):

Selection in C00496	Encoder evaluation method
0: High-resolution encoder	<p>High-precision procedure for high-resolution encoders (≥ 512 increments)</p> <ul style="list-style-type: none"> • Method for speed measurement with automatic scan time setting (0.5 ... 500 ms). • Evaluation with automatic scanning time minimisation for an optimum dynamic performance. • Particularly suited for high-resolution encoders (≥ 1024 inc) with good signal quality, i.e. <ul style="list-style-type: none"> • good scanning ratio 1:1 • exactly 90°-phase offset between track A and B (error $\leq \pm 10^\circ$) • Not suited for encoders with poor signal quality. • Wiring according to EMC (e.g. motor and encoder cable shielding) is required!
1: Low-resolution encoder (StateLine)	<p>High-precision procedure for low-resolution encoders (≤ 128 increments)</p> <ul style="list-style-type: none"> • Exact method for speed measurement with automatic scanning time setting (0.5 ... 500 ms) for low-resolution encoders in the range of 4 ... 128 increments. • Evaluation with automatic scanning time minimisation for an optimum dynamic performance. • Method is also suited for encoders with poor signal quality, e.g. for encoders with high error rate in scanning ratio and phase offset. • This method requires an equidistant period length per encoder increment. • Wiring according to EMC (e.g. motor and encoder cable shielding) is required!
2: Comb. encoder method (Lenze setting)	<p>Combination of the first two procedures as a function of the speed (recommended procedure)</p> <ul style="list-style-type: none"> • For a high-precision speed measurement suited for encoders with an arbitrary number of increments (4 ... 1024 increments). • Low input frequencies at the encoder inputs: The method is used for low-resolution encoders. • High input frequencies at the encoder inputs: The method is used for high-resolution encoders. • This method is suited for encoders with average to good signal quality. • Evaluation with automatic scanning time minimisation for an optimum dynamic performance. • This method requires an equidistant period length per encoder increment. • Wiring according to EMC (e.g. motor and encoder cable shielding) is required!
3: Edge-counting procedure	<p>Simple edge counting procedure with adjustable scanning time (C00425)</p> <ul style="list-style-type: none"> • Speed measurement by means of the edges of tracks A and B measured per scanning interval. • Integrated correction algorithm for EMC interference. • Limited suitability for systems with unshielded encoder and/or motor cable. • Limited suitability for encoders with poor signal quality, i.e. high error rate in scanning ratio and phase offset.

**Tip!**

- We recommend to use the preset combined encoder method ([C00496](#) = 2).
- Use one of the first three procedures ([C00496](#) = 0, 1, or 2) for dynamic applications (e.g. operating mode: servo control).
- For dynamic speed control or positioning processes, use an HTL encoder with 1024 increments.

Low speeds (except for edge counting)

For the first three methods ([C00496](#) = 0, 1, or 2), the minimum speed that can be measured depends on the encoder resolution.

The quantisation error

- is independent of the encoder resolution,
- exclusively depends on the encoder quality (encoder errors).
- at least amounts to 0.5 rpm.

Internal arithmetic operations automatically maintain the minimally required value of the scanning time in order to achieve maximum dynamics.

Encoder resolution (Number of increments)	Min. measurable speed in [rpm]
8	16
16	8
32	4
64	2
128	1
256	0.5
≥ 512	0.25

Low speeds with edge counting

The minimum speed that can be measured and the quantisation error of speed measurement in the edge-counting procedure ([C00496](#) = 3) depend on the scanning time that can be set in [C00425/1](#) and the encoder resolution.

Depending on accuracy and the requirements with regard to the dynamic performance, the respective scanning time must be selected and set in [C00425/1](#):

Encoder resolution (Number of increments)	Scanning time [ms]									
	1	2	5	10	20	50	100	200	500	1000
	Min. measurable speed in [rpm]									
8	1875	938	375	188	93.8	37.5	18.8	9.4	3.8	1.9
16	938	469	188	94	46.9	18.8	9.4	4.7	1.9	0.9
32	469	234	94	46.9	23.4	9.4	4.7	2.3	0.9	0.5
64	234	117	46.9	23.4	11.7	4.7	2.3	1.2	0.5	0.2
128	117	58.6	23.4	11.7	5.9	2.3	1.2	0.6	0.2	0.12
256	58.6	29.3	11.7	5.9	2.9	1.2	0.6	0.3	0.12	0.06
512	29.3	14.6	5.9	2.9	1.5	0.6	0.3	0.15	0.06	0.03
1024	14.6	7.3	2.9	1.5	0.7	0.3	0.15	0.07	0.03	0.01

6.4.3 HTL encoder at DI6/DI7



Note!

Single-track evaluation of the digital DI6/DI7 terminals as speed feedback ([C0115/2](#) = 1 or 3) is not possible. Hence, a single-track encoder cannot be used for speed control at the digital DI6 terminal!

Low speeds with edge counting

The speed measurement is evaluated at the digital terminals DI6/DI7 with the edge-counting procedure and a fixed scanning time that can be set in [C00425/2](#).

The minimum speed that can be measured and the quantisation error of speed measurement in the edge-counting procedure depend on the scanning time that can be set in [C00425/2](#) and the encoder resolution.

Depending on accuracy and the requirements with regard to the dynamic performance, the respective scanning time must be selected and set in [C00425/2](#):

Encoder resolution (Number of increments)	Scanning time [ms]									
	1	2	5	10	20	50	100	200	500	1000
	Min. measurable speed in [rpm]									
8	1875	938	375	188	93.8	37.5	18.8	9.4	3.8	1.9
16	938	469	188	94	46.9	18.8	9.4	4.7	1.9	0.9
32	469	234	94	46.9	23.4	9.4	4.7	2.3	0.9	0.5
64	234	117	46.9	23.4	11.7	4.7	2.3	1.2	0.5	0.2
128	117	58.6	23.4	11.7	5.9	2.3	1.2	0.6	0.2	0.12
256	58.6	29.3	11.7	5.9	2.9	1.2	0.6	0.3	0.12	0.06
512	29.3	14.6	5.9	2.9	1.5	0.6	0.3	0.15	0.06	0.03
1024	14.6	7.3	2.9	1.5	0.7	0.3	0.15	0.07	0.03	0.01

Maximum speeds with edge counting

Due to the lower input frequency (max. 10 kHz) compared to the terminals DI1/DI2, operation with maximum speed at the terminals DI6/DI7 is limited. ▶ [Digital input terminals](#) (📖 377)

Encoder resolution (Number of increments)	Max. measurable speed in [rpm]
8	No restrictions
16	37500
32	18750
64	9375
128	4688
256	2344
512	1172
1024	586

6.5

Pole position identification (PPI)

**Note!**

Only required:

- For [servo control \(SC\)](#) with synchronous motor of a third-party manufacturer.
- For [servo control \(SC\)](#) with synchronous motor and use of incremental encoders (TTL or sin/cos encoders as well as multi-pole pair resolvers).
- After changes of the motor feedback system, e.g. encoder exchange.

For the sensorless control of synchronous motors (SLPSM), a pole position identification is not required.

**Note!****Acceptance of the resolver pole position from a Servo Drive 9400**

The resolver pole position ([C00926/1](#)) cannot be simply accepted from a Servo Drive 9400 if the pole position (C58/1) considerably differs from -90 ° in the Servo Drive 9400.

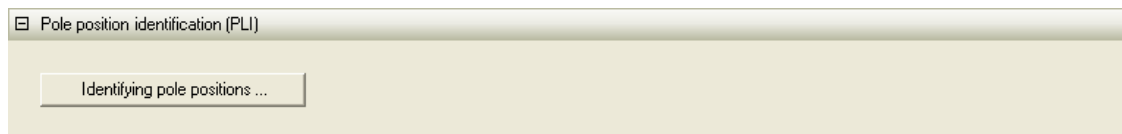
- We always recommend a pole position identification (PLI).
- As an alternative, the following conversion has to be carried out for a transfer of the resolver pole position from a Servo Drive 9400 to the 8400 TopLine:

$$\text{Pole position}_{8400} (\text{C00926/1}) = - (\text{pole position}_{9400_C58/1} + 180^\circ)$$

For the control of permanent-magnet synchronous machines, the pole position – the angle between the motor phase U and the field axis of the rotor – must be known.

- For Lenze motors with absolute value encoder or resolver, the pole position is already set correctly in [C00926/1...2](#).
- When incremental encoders (TTL or sin/cos encoders) are used, a pole position identification (PPI) is always required after mains switching, even with Lenze motors.
- The controller can also evaluate multi-pole-pair resolvers.
 - When the number of motor pole pairs is an integer multiple of the number of pole pairs of the resolver, a pole position identification must only be executed once.
 - When the number of motor pole pairs is no integer multiple of the number of pole pairs of the resolver, a pole position identification must be executed after every mains switching.

Parameterisation dialog (cutout)



Parameter	Info	Lenze setting
C00002/34	Pole position identification (360°)	0: Off / ready

The **Identify pole position...** button or the "pole position identification (360°)" device command serve to detect the pole position for the motor encoder currently activated in [C00495](#).



Detailed information on the process and execution of the pole position identification can be found in the following subchapter "[Pole position identification 360°](#)".

6.5.1 Pole position identification 360°

Procedure for "pole position identification 360°"

If all conditions are met, the motor is energised with a direct current corresponding to the lower of the following two values:

$$\sqrt{2} \cdot \text{Rated device current}$$

or

$$\sqrt{2} \cdot \text{Rated motor current}$$

- The rotor is aligned through the current flow. This is absolutely necessary for the procedure.
- To ensure that the torque-neutral axis is not accidentally energised and the rotor stops, a 45° current vector is (electrically) generated for a short instant and then (electrically) switched back to 0° (≡ phase U).
 - Then a DC current of the above-mentioned value could be measured in this motor phase.
- If a resolver or an optical encoder without absolute track is used, the difference between the preselected current angle and the mechanical rotor angle is determined. After this, the current vector is (electrically) turned by another 22.5° and the difference between current angle and rotor angle is determined once again.
 - The procedure is repeated 16 times. This corresponds to one electrical revolution. The machine rotates by 360° (mech.)/pole pair number.
 - Take the average value of the 16 measurements to compensate for asymmetries.

Adjustment of the pole position identification 360°

The pole position identification can be adjusted to the respective machine and the prevailing moments of inertia by means of the parameters described below:

Parameter	Info	Lenze setting	
		Value	Unit
C00644/1	PLI 360° traversing direction	right rotating field	
C00645/2	PLI 360° max. error tolerance	0.0	°
C00646/2	PLI 360° current amplitude	100	%
C00647/2	PLI 360° ramp time	100	%

- The current amplitude can be adjusted proportionally in [C00646/2](#).
 - For large machines and high mass inertia values or for linear direct drives, the current amplitude usually has to be increased.
 - The Lenze setting "100 %" corresponds to the smaller of the two following values:

$$\sqrt{2} \cdot \text{Rated device current}$$

or

$$\sqrt{2} \cdot \text{Rated motor current}$$



Stop!

If there is no temperature monitoring in the motor and/or the I2xt motor monitoring and the maximum current monitoring are not parameterised correctly, the motor may be permanently damaged when the current amplitude is set too high (e.g. to the maximum value)!

▶ [Motor load monitoring \(I2xt\)](#) (📖 294)

▶ [Maximum current monitoring](#) (📖 303)



Note!

If the current amplitude is set to > 100 % in [C00646/2](#), the device utilisation (Ixt) monitoring and/or one of the motor monitoring functions may respond and cause the abort of the pole position identification.

- The ramp time can be adjusted proportionally in [C00647/2](#).
 - For large machines and high mass inertia values, the ramp time usually has to be increased.
 - For small machines, a reduction of the ramp time can speed up the pole position identification process.
- In some situations it may be helpful to reverse the travel direction in [C00644/2](#) for the pole position identification (e.g. for linear motor at the end stop).
- The "pole position identification 360°" procedure comprises a plausibility check. If the rotor position determined via the encoder system does not correspond to the controlled output position:
 - the pole position identification procedure is aborted.
 - the response parameterised in [C00643/1](#) (Lenze setting: "Fault") is activated.
 - the error message "[Id5: Pole position identification error](#)" is entered into the logbook.
- The preset fault tolerance for the plausibility check can be changed in [C00645/2](#).

Execute pole position identification 360°**Danger!**

The machine must not be braked or blocked during the pole position identification! For this reason, the pole position identification is not permitted for hanging loads!

During the pole position identification the rotor aligns itself. The motor shaft moves by max. one electrical revolution which causes the corresponding movement of the connected mechanical components!

**Stop!**

Check the correct parameterisation of the max. motor current monitoring before carrying out the pole position identification to prevent the motor from being permanently damaged.

► [Maximum current monitoring](#) (📖 303)

**Note!**

By means of controller inhibit, the procedure started can be cancelled anytime, if required, without carrying out a change in [C00926](#).

If the pole position identification is aborted, the response parameterised in [C00643/1](#) is activated (Lenze setting: "Fault").

- If this behaviour is not wanted, deactivate the monitoring by selecting "0: No response" in [C00643/1](#).

Preconditions for the execution

- A synchronous motor has been selected.
- No other identification is active.
- No error has occurred.



How to execute the pole position identification:

1. Inhibit the controller if it is enabled, e.g. via the [C00002/16](#) device command or a LOW signal at the X5/RFR terminal.
2. Start the pole position identification with the device command [C00002/34](#) = "1: On / start".
3. Enable the controller again.
 - The pole position identification starts.
 - The progress of the identification run can be seen in [C00002/34](#).
 - The identification is completed if the "0: Off / ready" message is displayed in [C00002/34](#).
4. Inhibit controller again.

After successful completion...

...the controller is inhibited automatically and the pole position determined for the activated feedback system is set in the corresponding subcode of [C00926](#).

- For a permanent acceptance of the identified pole position, the parameter set must be saved ([C00002/11](#) = "1: On / start").
- The next controller inhibit and subsequent controller enable serve to cancel the controller inhibit automatically set by the procedure (e.g. by first executing the device command [C00002/16](#) = "0: Off / ready" and then executing the device command [C00002/16](#) = "1: On / start").

In the event of a fault

If an error occurs during the procedure or the pulse inhibit gets active (e.g. due to short-time undervoltage), the procedure is terminated with controller inhibit without making a change in [C00926](#).

If the machine was braked or blocked during the procedure, this will be recognised at the end of the measurement and no change is made in [C00926](#).

- If the pole position identification is aborted:
 - the response parameterised in [C00643/1](#) (Lenze setting: "Fault") is activated.
 - the error message "[Id5: Pole position identification error](#)" is entered into the logbook.

6.5.2 Pole position identification without motion

This function extension is available from version 02.00.00!



Note!

Function only possible with:

- [Servo control \(SC\) for synchronous motors](#)
- [Sensorless control for synchronous motors \(SLPSM\)](#)

From version 02.00.00, a pole position identification without motion is also possible in case of servo control and sensorless control.

- For sensorless control of synchronous motors (SLPSM), this function is already activated in the Lenze setting, i.e. with every controller enable the rotor displacement angle is identified and thus jerks in the machine after controller enable can be avoided.
 - In order to achieve the same behaviour as before, set bit 0 to "0" in [C02874](#).
- For servo control (SC), this function can be activated for various events in [C02874](#) via the bits 1 ... 3:
 - Bit 1: Pole position identification after mains connection
 - Bit 2: Pole position identification after controller enable
 - Bit 3: Pole position identification after error acknowledgement



Note!

- The "Pole position identification without motion" cannot completely replace the "pole position identification 360°"!
 - The electrical rotor displacement angle can only be electrically identified with an error of up to 10°. This inaccuracy can cause a worse torque accuracy and a worse energy efficiency.
- The identification takes motor-dependent 1 ... 15 ms. The setpoint enabling of the device is reduced by this time.
- In the Lenze setting, the function is preset so that in most of the cases no further settings have to be made.



Tip!

In case of servo control (SC), it is generally sufficient to activate this function only once after mains connection of the device ([C02874](#): Bit 1 = "1").

Typical application case: A speed sensor with an unknown pole position is used (e.g. encoder). The pole position identification 360°, however, cannot be used since, e.g. the motor is locked, the application does not permit it or the identification takes too long.

Short overview of the relevant parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C02874	PLI without motion	0x1 (bit coded)	
C02872	PLI without motion: Adaptation of time duration	0	
C02875	PLI without motion: Adaptation of ident angle	0	°
C02870	PLI without motion: Optimisation factor	-	%
C02871	PLI without motion: Running time	-	ms
C02873	PPI without motion: Identified rotor displacement angle	-	°
Highlighted in grey = display parameter			

**Note!**

In case of synchronous motors with a stator time constant < 1 ms, the pole position identification is not executed since the resulting test current pulse could exceed the permissible motor current.

- This, however, only affects very few synchronous motors with very low power (e.g. Lenze motor MDSKS-020-13-300 with rated power of 40 W).
- A non-executed pole position identification can be recognised by the display [C02870](#) = 0 % and [C02871](#) = 0 ms.

- The stator time constants can be calculated based on the following formula:

$$T_s[\text{ms}] = \frac{L_{ss}[\text{mH}]}{R_s[\Omega]}$$

T_s = stator time constant

L_{ss} = Motor stator leakage inductance ([C00085](#))

R_s = Motor stator resistance ([C00084](#))

Optimising the pole position identification



Stop!

In case of a too high setting in [C02872](#), an impermissible motor current may occur during pole position identification. In this case, the "Fault" error response occurs and the "Id5: Pole position identification error" error message entered in the logbook.

In case of a considerably too high setting in [C02872](#):

- The following current monitoring functions can be triggered:
 - oC7: Motor overcurrent
 - oC11: Clamp operation active
 - oC1: Power section - short circuit
- The optimisation degree "0 %" is displayed in [C02870](#).
- The time "0 ms" is displayed in [C02871](#).

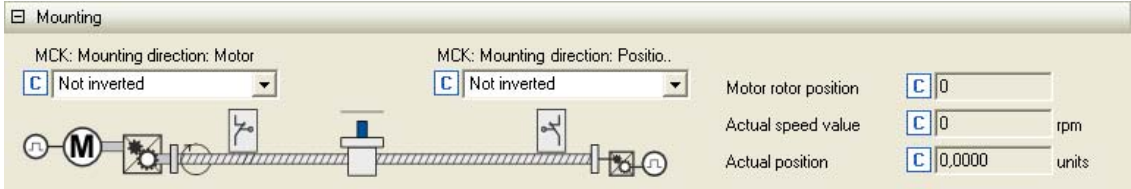


How to optimise the pole position identification without motion:

1. For optimisation, enable the controller for various rotor displacement angles.
2. After every controller enable, check the optimisation degree displayed in [C02870](#).
The pole position identification is set optimally if an optimisation degree in the range 70 ... 130 % is displayed in [C02870](#) after every controller enable.
3. When the optimisation degree is > 130 %:
Reduce the setting in [C02872](#) step by step and execute controller enable for various rotor displacement angles until an optimisation degree < 130 % is displayed.
4. When the optimisation degree is < 70 %:
Increase setting in [C02872](#) step by step and execute controller enable for various rotor displacement angles until an optimisation degree > 70 % is displayed.
5. Optionally: [C02875](#) serves to increase or reduce the identified electrical rotor displacement angle. This can prevent e.g. a reversing of the motor due to the accuracy of identification if applications require it.

6.6 Mounting

In case of an inverted mounting direction of the speed sensor and/or position encoder, the following parameters have to be adapted accordingly:



Parameter	Info	Lenze setting	
		Value	Unit
C01206/1	MCK: Mounting direction: Motor	0: Not inverted	
C01206/2	MCK: Mounting direction: Position encoder	0: Not inverted	
C00927	Motor rotor position	-	°
C00051	MCTRL: Actual speed value	-	rpm
C01210/3	MCK: Actual position	-	units
Highlighted in grey = display parameter			

Related topics:
▶ [Machine parameters](#)

6.7

Monitoring

Parameterisation dialog (cutout)

Monitoring

Open-circuit monitoring ☒ Speed and position e

Resp. to encoder open circuit HTL ☒ Fault

Resp. to MultiEncoder open circuit ☒ Fault

Resp. to resolver open circuit ☒ Fault

Resp. to encoder angular drift monit. ☒ No Reaction

Resp. to encoder comm. error ☒ Fault

Resp. to hiperface status ☒ Information

Resp. to hiperface position invalid ☒ Information

Resp. to inaccuracy SinCos ☒ Information

Resp. to max freq. feedb. DIG12/67 ☒ Fault

Monitoring encodervalue (LS_MultiEncoder: bFail)

LS_MultiEncoder: Data area min ☒ -214748,3647 units

LS_MultiEncoder: Data area max ☒ 214748,3647 units

LS_MultiEncoder: Position jump max ☒ 0,0000 units

LS_MultiEncoder: Information bFail ☒ 0x0 ...

Monitoring encodervalue (LS_Resolver: bFail)

LS_Resolver: Information bFail ☒ 0x0 ...

Parameter	Info	Lenze setting	
		Value	Unit
C00498	Open-circuit monitoring	0: Speed encoder and position encoder	
C00586	Resp. open circuit HTL encoder	1: Fault	
C00603/1	Resp. to MultiEncoder open circuit	1: Fault	
C00603/2	Resp. to resolver open circuit	1: Fault	
C00603/3	Up to and including version 02.xx.xx: Resp. to encoder comm. error	1: Fault	
	From version 12.00.00: Resp. to encoder pulse deviation	0: No Reaction	
C00603/4	Up to and including version 02.xx.xx: Resp. to encoder pulse deviation	1: Fault	
	From version 12.00.00: Resp. to encoder comm. error	1: Fault	
C00603/5	Resp. to Hiperface status	6: Information	
C00603/6	Resp. to invalid Hiperface position	6: Information	
C00603/7	Resp. to SinCos inaccuracy	6: Information	
C00607	Resp. to max. freq. feedb. DIG12/67	1: Fault	
Monitoring of encoder value (LS_MultiEncoder: bFail)			
C01112/2	LS_MultiEncoder: Data area min	-214748.3647	units
C01112/3	LS_MultiEncoder: Data area max	214748.3647	units
C01112/4	LS_MultiEncoder: Max. position jump	0.0000	units
C00451/1	LS_MultiEncoder: Information bFail	-	
Monitoring of encoder value (LS_Resolver: bFail)			
C00452/1	LS_Resolver: Information bFail	-	

Highlighted in grey = display parameter

6.7.1 Resolver/multi-encoder open-circuit monitoring

In the Lenze setting, the resolver cable and/or encoder cable are monitored with regard to open circuit as a function of the selected speed and position encoder.



Danger!

- For safety reasons, always select "Fault" (Lenze setting) as a response for the (open-circuit) monitoring of the resolver/encoder!
- To avoid interference when using an encoder, only use shielded motor and encoder cables!



Tip!

We recommend the Lenze setting "0: Speed sensor and position encoder" for open-circuit monitoring ([C00498](#)). Further possible settings make sense if the respective encoder is not used as speed sensor or position encoder but for other tasks in the application. Moreover, a selective switch-off of the monitoring is possible if other settings are made.

Open-circuit monitoring (C00498)	Function
0: Speed encoder and position encoder (Lenze setting)	Open-circuit monitoring is active for the speed encoder selected in C00495 and the position encoder selected in C00490 . <ul style="list-style-type: none"> • Depending on whether a speed encoder or position encoder has been selected, the monitoring mode for the resolver and/or encoder is activated. • If no speed encoder and position encoder have been selected, open-circuit monitoring is deactivated.
1: Resolver only	Open-circuit monitoring is only active for the resolver, independent on the selection of the speed encoder and position encoder. <ul style="list-style-type: none"> • Open-circuit monitoring for the encoder is deactivated.
2: Encoder only	Open-circuit monitoring is only active for the encoder, independent on the selection of the speed encoder and position encoder. <ul style="list-style-type: none"> • Open-circuit monitoring for the resolver is deactivated.
3: Resolver and encoder	Open-circuit monitoring is active for the resolver and encoder, independent on the selection of the speed encoder and position encoder.

When does the open-circuit monitoring system respond?

Resolver	Multi encoder
<ul style="list-style-type: none"> • In case of open circuit in the encoder cable. • If the resolver impedance is too high. • In case of EMC interferences. 	<ul style="list-style-type: none"> • In case of open circuit in the encoder cable.

Response to open circuit

Resolver	Multi encoder
The error response set in C00603/2 is triggered (Lenze setting: "0: No Reaction"). Logbook entry: " Sd2: Open circuit - resolver "	The error response set in C00603/1 is triggered (Lenze setting: "0: No Reaction"). Logbook entry: " Sd4: Open circuit - MultiEncoder "

6.7.2 Open-circuit monitoring HTL encoder

Open-circuit monitoring is available for the HTL encoder cable.



Danger!

For safety reasons, always select "Fault" (Lenze setting) as a response for the (open-circuit) monitoring of the HTL encoder!



Note!

If you do not use an HTL encoder, deactivate the monitoring ([C00586](#) = "0: No Reaction").

When does the open-circuit monitoring system respond?

The open-circuit monitoring will trigger if

- an open circuit occurs in the encoder cable.
- an extreme overload (e.g. blocked motor shaft) occurs during the start-up phase of the motor.
- highly dynamic reversion of the motor occurs.
- the motor still rotates at high speed in the "SC servo control ASM" mode when the controller enabled.

Which measured values lead to an actuation of the open-circuit monitoring system?

The following measured values checked for plausibility lead to an actuation of the open-circuit monitoring system:

1. If the total deviation between actual speed and setpoint speed is higher than $f = 40 \text{ Hz}$ for a time $> 0.1 \text{ s}$.
2. If the actual speed detected is $f = 0 \text{ Hz}$ or $n = 0 \text{ rpm}$ and the I_{\max} controller or the torque limitation for servo control (SC) is active for $t \geq 0.1 \text{ s}$.
3. If the sign of the injected frequency and the actual speed is not the same, the I_{\max} controller is active and this status is active for 0.1 s . Usually this is the case when A/B tracks are reversed.

Response to open circuit

- If the open-circuit monitoring is tripped:
 - The error response set in [C00586](#) is activated (Lenze setting: "Fault").
 - The "[Sd3: Open circuit - feedback system](#)" is entered into the Logbook.
 - The `bMctrlEncoderComFault` status output of the [LS DeviceMonitor](#) SB is set to TRUE.
- A setting of [C00586](#) = "0: No Reaction" deactivates the monitoring.

6.7.3 Encoder - angular drift monitoring

This function extension is available from version 12.00.00!



Note!

The encoder angular drift monitoring is implemented for encoders without absolute information.

In the Lenze setting ([C00603/3](#) = "0: No response"), the angular drift monitoring of the encoder is not activated!

The encoder angular drift monitoring monitors a possible deviation of the real encoder angle from the angle calculated by counting increments in the encoder evaluation.

- If a deviation higher than 45° (electrical) is recognised when monitoring is activated:
 - The error response set in [C00603/3](#) is triggered.
 - The "[Sd8: Encoder angular drift monit.](#)" error message is entered into the logbook.
 - The "Reference known" status of the "Homing" basic drive function is reset (if this status was set before)



Tip!

A deviation may occur, for instance, by incorrect parameter setting of the encoder increments, by lines in the form of interferences caused by EMC or loss of lines caused by EMC.

Functional principle

For an encoder without absolute information, the number of incoming encoder lines between two zero pulses (one revolution) is monitored. This value must equal the encoder increments set in [C00420/3](#).



Note!

After mains switching, monitoring is only active after second incoming zero pulse since the first line difference to be used can only be calculated with the second and first zero pulse.

When the motor (and thus the encoder) is replaced, it is very likely that a angular drift error occurs within the first revolution after acknowledging the encoder error since the monitoring function cannot recognise that the encoder has been replaced.

Due to the type of monitoring, accuracy (distance of Z pulse to the detected position) can only be detected while the machine is running. As a permanently pending error would prevent the error cause to be removed, a detected error will be automatically reset by the controller after a short time. In order that the motor does not continue to rotate in this case, an engaging error response (e.g. "Fault" or "TroubleQSP") has to be set. If an error is detected again, it is entered again into the logbook.

6.7.4 Encoder value monitoring

For detecting invalid encoder values, a value range can be defined via the parameter [C01112/2](#) and [C01112/3](#). When the encoder signal leaves the set value range, the *bFail* status signal of the SB [LS MultiEncoder](#) is set to TRUE and the corresponding information is displayed bit-coded in [C00451/1](#).

- **Example 1: SSI laser distance meter**

The *bFail* status signal can be used to detect an interruption of the laser beam or a dirty mirror.

- **Example 2: SSI bar code scanner**

In an application, an SSI bar code scanner is used to detect the workpiece ID and the workpiece position. A setting of sensible limit values serves to use the *bFail* status signal to determine whether the ID or the position of the SSI bar code scanner has been detected.

6.7.5 Motor temperature monitoring (KTY)

The motor temperature can also be detected and monitored via the resolver cable and/or the encoder cable.

- The feedback system to be used for the motor temperature is selected in [C01193](#).
- The respective motor temperature monitoring includes an early warning stage as well as an open-circuit monitoring for the thermal sensor.



Note!

In the Lenze setting of [C00583/1...6](#), the motor temperature monitoring functions are switched on! These monitoring functions are only active with speed encoder selection "3: Multi encoder" or "4: Resolver" in [C00495](#).

From version V02.00.00 with servo control (SC), the temperature compensation within the motor control is activated in the Lenze setting of [C02878/1](#). However, temperature compensation is only active with speed sensor selection "3: Multi encoder" or "4: Resolver" in [C00495](#) as well as error-free KTY temperature detection (display in [C00063/1](#) $\neq 255$ °C).

Parameterisation dialog (cutout)

Motor temperature monitoring (KTY) ...

Feedback system motor temperature	<input type="text" value="C"/> Speed feedback	Motor temperature	<input type="text" value="C"/> 25 °C
-----------------------------------	---	-------------------	--------------------------------------

Resolver		Encoder	
Motor temperature via resolver	<input type="text" value="C"/> 25	Motor temperature via MultiEncoder	<input type="text" value="C"/> 25
Warning threshold motor temperature resolver	<input type="text" value="C"/> 120	Warning threshold motor temperature MultiEn..	<input type="text" value="C"/> 120
Resp. to motor overtemp. KTY resolver	<input type="text" value="C"/> Fault	Resp. to motor overtemp. KTY MultiEncoder	<input type="text" value="C"/> Fault
Resp. to motor temp. > C00121 resolver	<input type="text" value="C"/> Warning	Resp. to motor temp. > C00121 encoder	<input type="text" value="C"/> Warning
Resp. to temp. sensor error KTY resolver	<input type="text" value="C"/> Fault	Resp. to temp. sensor error KTY MultiEncoder	<input type="text" value="C"/> Fault
Type of motor temperature sensor resolver	<input type="text" value="C"/> KTY83-110	Type of motor temperature sensor MultiEncod..	<input type="text" value="C"/> KTY83-110

User characteristic (sensor type selection)

1 Grid point	
PTC characteristic: Temperature 1	<input type="text" value="C"/> 100
PTC characteristic: Resistance 1	<input type="text" value="C"/> 1070
2 Grid point	
PTC characteristic: Temperature 2	<input type="text" value="C"/> 150
PTC characteristic: Resistance 2	<input type="text" value="C"/> 2225

Parameter	Info	Lenze setting	
		Value	Unit
C01193	Motor temp. feedback system	0: Speed feedback	
C00063/1	Motor temperature	-	°C
Resolver			
C00063/2	Motor temperature via resolver	-	°C
C00121/1	Warning threshold motor temperature resolver	120	°C
C00583/1	Resp. to motor overtemp. KTY resolver	1: Fault	
C00583/3	Resp. to motor temp. > C00121 resolver	5: Warning	
C00583/5	Resp. to temp. sensor error KTY resolver	1: Fault	
C01190/1	Type of motor temperature sensor resolver	0: KTY83-110	°C
Multi encoder			
C00063/2	Motor temperature via MultiEncoder	-	°C
C00121/2	Warning threshold motor temperature MultiEncoder	120	°C
C00583/2	Resp. to motor overtemp. KTY MultiEncoder	1: Fault	
C00583/4	Resp. to motor temp. > C00121 encoder	5: Warning	
C00583/6	Resp. to temp. sensor error KTY MultiEncoder	1: Fault	
C01190/2	Type of motor temperature sensor MultiEncoder	0: KTY83-110	°C
User characteristics (sensor type selection)			
C01191/1	PTC characteristic: Temperature 1	100	°C
C01191/2	PTC characteristic: Temperature 2	150	°C
C01192/1	PTC characteristic: Resistance 1	1070	Ohm
C01192/2	PTC characteristic: Resistance 2	2225	Ohm
Highlighted in grey = display parameter			

Motor temperature monitoring (KTY) via resolver

The sensor type has to be selected in [C01190/1](#).

- If the winding temperature detected via the motor temperature sensor reaches the limit value set in [C00121/1](#) (Lenze setting: 120 °):
 - An advance warning in the form of the error response set in [C00583/3](#) is issued.
 - The "[oH7: Motor temperature - resolver > C121](#)" error message is entered into the logbook.
- If the fixed limit value of 150 °C is reached:
 - The error response set in [C00583/1](#) is triggered.
 - The "[oH9: Motor temperature - resolver](#)" error message is entered into the logbook.
- If open circuit is detected for the motor temperature sensor:
 - The error response set in [C00583/5](#) is triggered.
 - The "[Sd6: Thermal detector error - resolver](#)" error message is entered into the logbook.

Motor temperature monitoring (KTY) via encoder

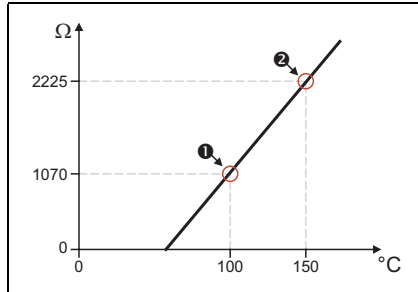
The sensor type has to be selected in [C01190/2](#).

- If the winding temperature detected via the motor temperature sensor reaches the limit value set in [C00121/2](#) (Lenze setting: 120 °):
 - An advance warning in the form of the error response set in [C00583/4](#) is issued.
 - The "[oH6: Motor temperature - MultiEncoder > C121](#)" error message is entered into the logbook.
- If the fixed limit value of 150 °C is reached:
 - The error response set in [C00583/2](#) is triggered.
 - The "[oH12: Motor overtemperature - MultiEncoder](#)" error message is entered into the logbook.
- If open circuit is detected for the motor temperature sensor:
 - The error response set in [C00583/6](#) is triggered.
 - The "[Sd12: Thermal detector error - MultiEncoder](#)" error message is entered into the logbook.

Specific characteristic for the motor temperature sensor

A specific characteristic can be defined and activated for the motor temperature sensor if required.

- The specific characteristic is defined on the basis of two grid points which must be set in [C01191](#) and [C01192](#). Those two points define a line which is extrapolated to the right and to the left.
- The specific characteristic can be activated by selecting "1: Spec. characteristic" in [C01190/1](#) for the resolver and in [C01190/2](#) for the encoder.
- In the Lenze setting, the specific characteristic is defined as follows:



[6-4] Lenze setting of the specific characteristic

- Interpolation point ❶
 - [C01191/1](#) = 100 °C
 - [C01192/1](#) = 1070 Ω
- Interpolation point ❷
 - [C01191/2](#) = 150 °C
 - [C01192/2](#) = 2225 Ω



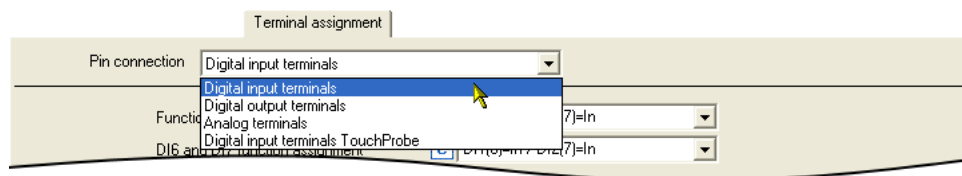
Note!

If a motor is selected from the motor catalogue, parameters [C01190](#), [C01191](#), and [C01192](#) are overwritten!

7 I/O terminals

This chapter provides information on the function, possible parameter settings, and technical data of the input/output terminals of the controller.

In the »Engineer«, the input and output terminals are parameterised on the **Terminal assignment** tab. To do this, go to the **Control terminals** list field and select the terminals that you wish to parameterise:



You can find further information in the respective subchapter:

- ▶ [Digital input terminals](#) (📖 377)
- ▶ [Digital output terminals](#) (📖 398)
- ▶ [Analog terminals](#) (📖 401)
- ▶ [Touch probe detection](#) (📖 411)

**Note!**

The input and output terminals of the drive controller have already been functionally assigned in the default setting ("Lenze setting"). The preconfigured assignment depends on the technology application selected in [C00005](#) and the control mode selected in [C00007](#):

- TA "Actuating drive speed": [Terminal assignment of the control modes](#) (📖 441)
- TA "Table positioning": [Terminal assignment of the control modes](#) (📖 504)
- TA "Switch-off positioning": [Terminal assignment of the control modes](#) (📖 530)



Wiring diagram, assignment and electrical data of the input and output terminals can be found in the **hardware manual 8400** in the chapter "technical data". The hardware manual is stored in electronic form on the data carrier supplied with the 8400 controller.

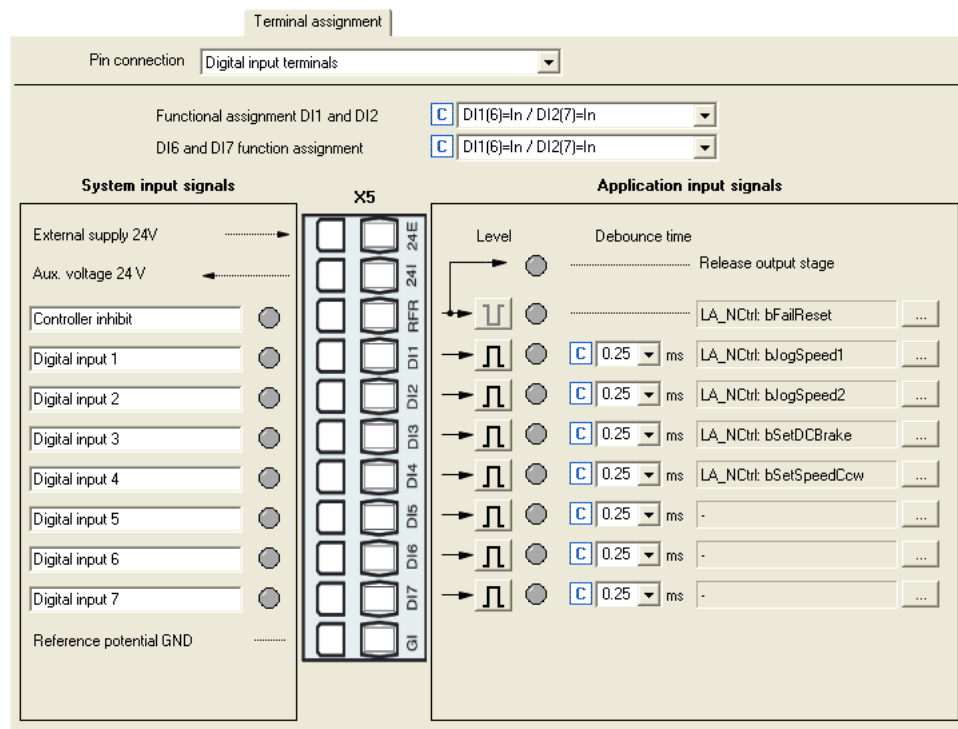
**Tip!**




How you can alter the preconfigured assignment of the input and output terminals is described in the chapter entitled "[User-defined terminal assignment](#)". (📖 421)

7.1 Digital input terminals

The drive controller has 7 parameterisable input terminals (DI1 ... DI7) for detecting digital signals. The RFR control input for enabling the controller is permanently connected to the device control unit.

Parameterisation dialog in the »Engineer«:



Button	Function
	Indicates the polarity of the input is HIGH active. The polarity can be changed from HIGH active to LOW active by clicking this button.
	Indicates that the polarity of the input is LOW active. The polarity can be changed from LOW active to HIGH active by clicking this button.
	Open the parameterising dialog for assigning application inputs to the digital input. ▶ Changing the terminal assignment with the »Engineer« (425)

Short overview of parameters for the digital input terminals:

Parameter	Info	Lenze setting	
		Value	Unit
C00115/1	Fct. DI 1/2 200kHz ▶ Change function assignment (📖 379)	0: DI1(6)=In / DI2(7)=In	
C00115/2	Fct. DI 6/7 10kHz ▶ Change function assignment (📖 379)	0: DI1(6)=In / DI2(7)=In	
Digital inputs DI1 ... DI7			
C00114	DigInX: Inversion	Bit coded	
C02830/1...7	DI1...DI7: Debounce time	1: 0.25	
C00443/1	Dlx: Terminal level	-	
C00443/2	Dlx: Output level	-	
Highlighted in grey = display parameter			

Related topics:

- ▶ [Touch probe detection](#) (📖 411)
- ▶ [User-defined terminal assignment](#) (📖 421)

7.1.1 Change function assignment

The internal processing function of the digital input terminals DI1/DI2 and DI6/DI7 can be reconfigured in [C00115](#) if necessary. In this way, these input terminals can alternatively be used as frequency or counting inputs in order to implement the following functions:

- Detection of the input frequency
- Detection and processing of two unipolar input frequencies to one bipolar frequency
- Counting of input pulses
- Evaluation of the speed feedback (HTL encoder) for the motor control (speed-controlled operation)

C00115/1: Function assignment DI1 and DI2 C00115/2: Function assignment of DI6 and DI7		Function assignment	
		DI1 / DI6	DI2 / DI7
0	DI1(6)=In / DI2(7)=In	Digital input	Digital input
1	DI1(6)=FreqIn / DI2(7)=In	Frequency input	Digital input
2	DI1(6)&DI2(7)=FreqIn (2-track)	Frequency input (2-track)	
3	DI1(6)=FreqIn / DI2(7)=direction	Frequency input (speed)	Frequency input (direction)
4	DI1(6)=CountIn / DI2(7)=In	Count input	Digital input



Note!

- In the Lenze setting of [C00115](#), the digital input terminals DI1/DI2 and DI6/DI7 have been configured as "normal" digital inputs.
- The digital input terminals DI3 ... DI5 are basically designed as "normal" digital inputs.
- Very high pulse frequencies can be measured at the DI1/DI2 and DI6/DI7 input terminals if the latter have been configured as frequency or counting inputs in [C00115](#). Scanning is then carried out within less than μs instead of the otherwise usual scanning rate of 1 kHz (1 ms).

You can find detailed information on the respective function assignment in the following subchapters:

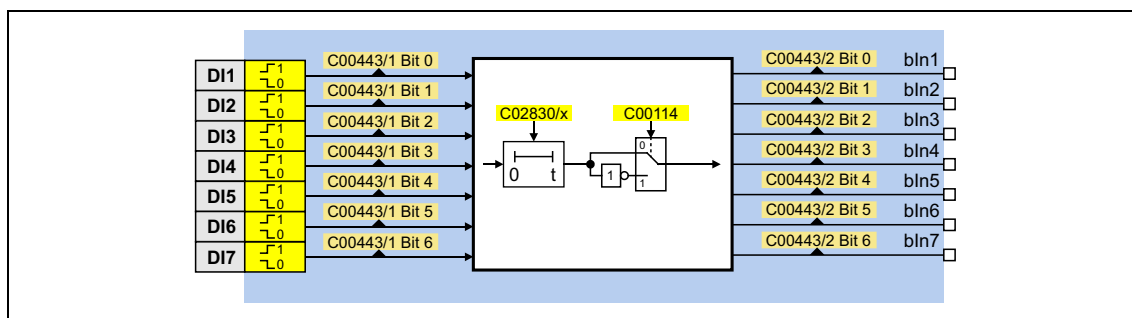
- ▶ [Using DI1\(6\) and DI2\(7\) as digital inputs](#) (380)
- ▶ [Using DI1\(6\) and DI2\(7\) as frequency inputs](#) (381)
- ▶ [Using DI1\(6\) as counting input](#) (386)

7.1.1.1 Using DI1(6) and DI2(7) as digital inputs

Function assignment 0: DI1(6)=In / DI2(7)=In

With this setting in [C00115](#), the digital input terminals have been configured as "normal" digital inputs.

- For each digital input, the debounce time ([C02830/1...7](#)) and the terminal polarity ([C00114](#)) can be set individually.
- The current terminal level at the input of the internal processing function is shown in [C00443/1](#) in bit-coded form.
- The output level for the application is shown in [C00443/2](#) in bit-coded form.



Internal interfaces to the application

- Relevant outputs at the [LS_DigitalInput](#) system block:

Output	Value/meaning
DIS code data type bIn1 ... bIn7 C00443/2 BOOL	Digital input DI1 ... DI7

Related topics:

- ▶ [Using DI1\(6\) and DI2\(7\) as frequency inputs](#) (381)
- ▶ [Using DI1\(6\) as counting input](#) (386)
- ▶ [Internal interfaces | System block "LS_DigitalInput"](#) (390)

7.1.1.2 Using DI1(6) and DI2(7) as frequency inputs

General information on using the input terminals as frequency inputs

The frequency inputs serve to detect HTL encoders with any number of increments and single-track and two-track signals. Single-track signals can be evaluated with or without rotation signal.



Note!

- Make sure that, when motor control with speed feedback is in use, the maximum input frequency of the respective input terminal is not exceeded.
 - DI1/DI2: $f_{\max} = 100 \text{ kHz}$ (from version 02.00.00: $f_{\max} = 200 \text{ kHz}$)
 - DI6/DI7: $f_{\max} = 10 \text{ kHz}$
- If the encoder signal is used as an actual speed value:
Number of encoder pulses / revolution $\leq 8192!$

Example of DI6/DI7 (in accordance with the preceding note):

- Encoder increment: 512 pulses / motor revolution
- Reference speed (C00011): 1500 rpm
- Speed setpoint: 100 %

$$\text{Input frequency} = \frac{1500 \text{ rpm}}{60 \text{ s}} \times 512 \text{ pulses} = 12800 \text{ pulses/s} = 12.8 \text{ kHz}$$

- Result: The speed or the number of increments is too high!

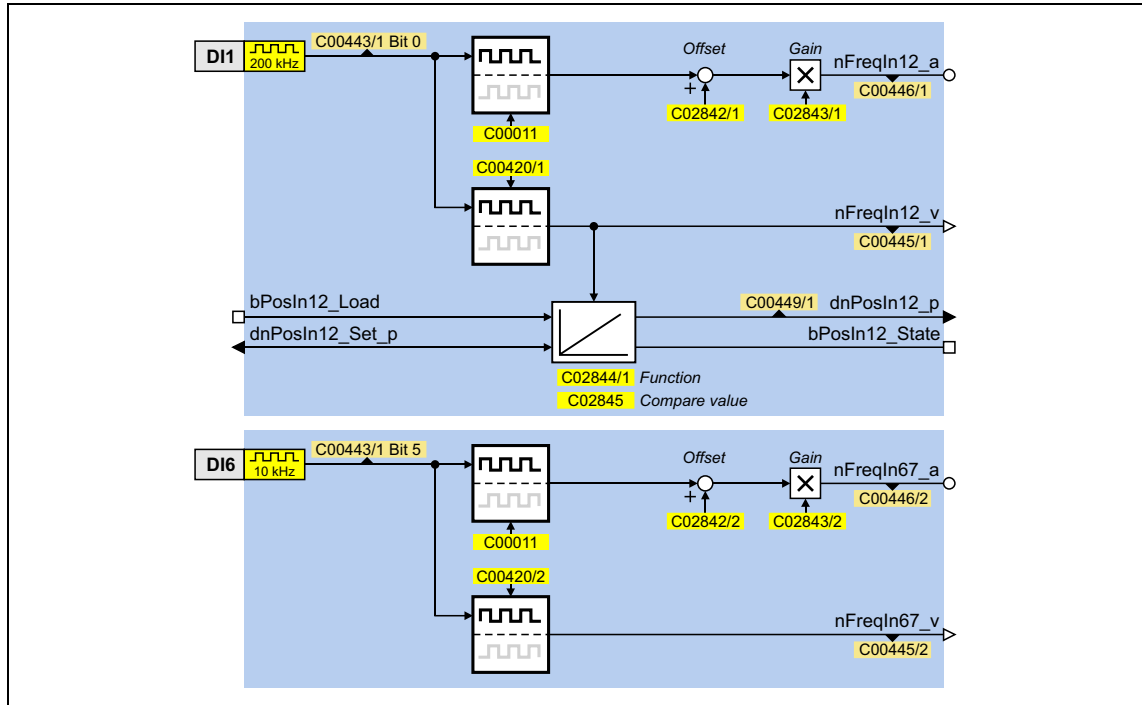


Tip!

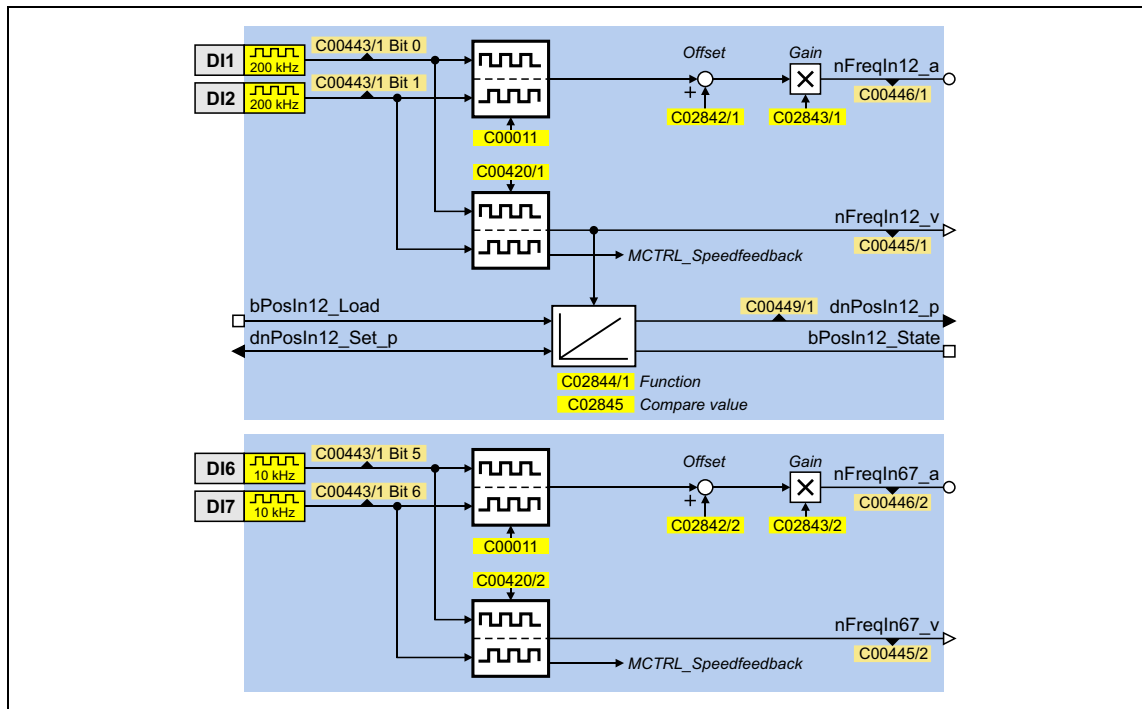
The [LS_DigitalInput](#) system block can also provide the encoder position. Detailed information on this topic is provided in chapter "[Output of the encoder position of the DI1/DI2 frequency input](#)". (📖 393)

Function assignment 1: DI1(6)=FreqIn / DI2(7)=In

This setting in [C00115](#) configures the input terminal DI1 or DI6 as frequency input. The input terminal DI2 or DI7 remains configured as "normal" digital input..

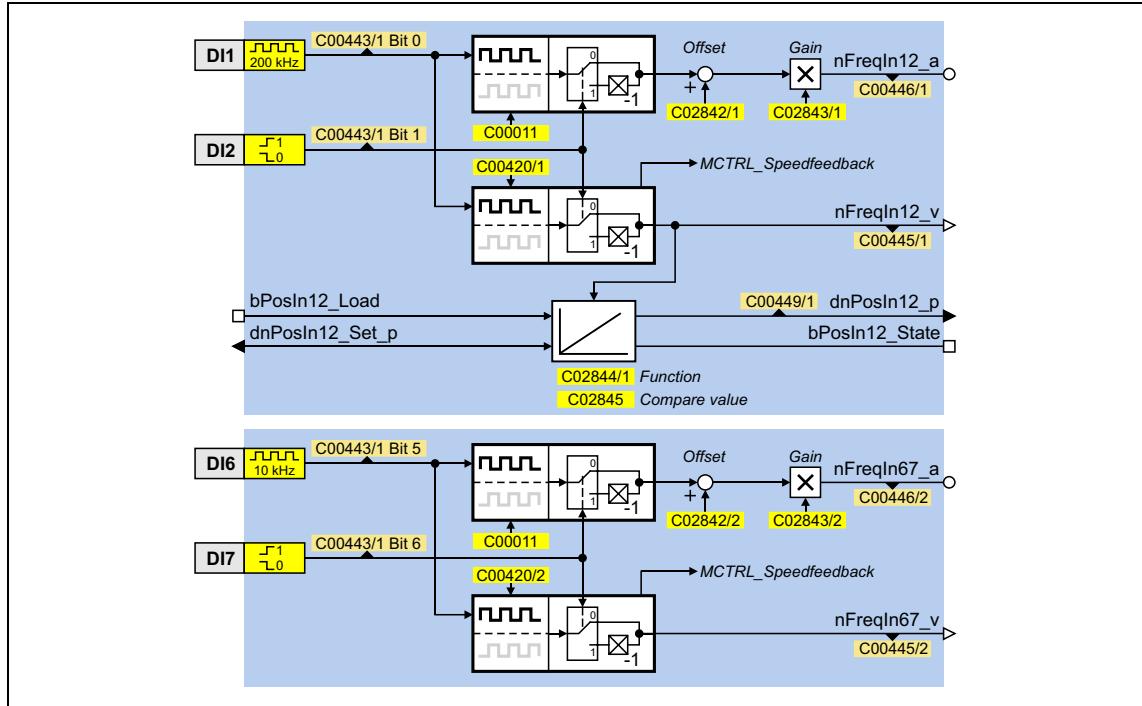
**Function assignment 2: DI1(6)&DI2(7)=FreqIn (2-track)**

This setting in [C00115](#) can be used to connect a two-track encoder to the DI1/DI2 or DI6/DI7 terminals.



Function assignment 3: DI1(6)=FreqIn / DI2(7)=Direction

This setting in [C00115](#) can be used to connect a single-track encoder to terminals DI1/DI2 or DI6/DI7. For this purpose, the rotation speed is evaluated via terminal DI1(6) and the direction of rotation of the encoder (LOW level \equiv CW direction of rotation) is evaluated via the DI(7) terminal.



Short overview of the parameters for the frequency inputs:

Parameter	Info	Lenze setting	
		Value	Unit
C00011	Appl.: Reference speed	1500	rpm
Frequency input DI1/DI2			
C00115/1	Fct. DI 1/2 200kHz	0: DI1(6)=In / DI2(7)=In	
C00420/1	Encoder increments at FreqIn12	128	Incr./rev.
C02842/1	FreqIn12: Offset	0.00	%
C02843/1	FreqIn12: Gain	100.00	%
C02844/1	PosIn12: Function	Loading with level	
C02845	PosIn12: Comparison value	0	
C00443/1	Dlx: Terminal level	-	
C00445/1	FreqIn12_nOut_v	-	Incr/ms
C00446/1	FreqIn12_nOut_a	-	%
C00449/1	FreqIn12_dnOut_p	-	Incr
Frequency input DI6/DI7			
C00115/2	Fct. DI 6/7 10kHz	0: DI1(6)=In / DI2(7)=In	
C00420/2	Encoder increments at FreqIn67	128	Incr./rev.
C02842/2	FreqIn67: Offset	0.00	%
C02843/2	FreqIn67: Gain	100.00	%
C00443/1	Dlx: Terminal level	-	
C00445/2	FreqIn67_nOut_v	-	Incr/ms
C00446/2	FreqIn67_nOut_a	-	%
Highlighted in grey = display parameter			

Internal interfaces to the application

- Relevant inputs at the [LS_DigitalInput](#) system block:

Input	Data type	Information/possible settings
Frequency input DI1/DI2		
bPosIn12_Load	BOOL	Load angle integrator with starting value and reset status signal
		TRUE Angle integrator is loaded with the value at <i>dnPosIn12_Set_p</i> and <i>bPosIn12_State</i> is reset to FALSE.
dnPosIn12_Set_p	DINT	Starting value for angle integrator

- Relevant outputs at the [LS_DigitalInput](#) system block:

Output	Data type	Value/meaning
Frequency input DI1/DI2		
nFreqIn12_a	C00446/1 INT	Output frequency as scaled analog signal in [%]
nFreqIn12_v	C00445/1 INT	Output frequency as speed signal in [inc/ms]
dnPosIn12_p	DINT	Angle output signal <ul style="list-style-type: none"> 65536 [incr.] \equiv 1 encoder revolution Overflow is possible (display via <i>bPosIn12_State</i>)
bPosIn12_State	BOOL	Status signal "Overflow occurred/distance processed" <ul style="list-style-type: none"> Status signal can be reset via <i>bPosIn12_Load</i>.
		TRUE Overflow has occurred or distance is processed.
Frequency input DI6/DI7		
nFreqIn67_a	C00446/2 INT	Output frequency as scaled analog signal in [%]
nFreqIn67_v	C00445/2 INT	Output frequency as speed signal in [inc/ms]

Related topics:

- ▶ [Output of the encoder position of the DI1/DI2 frequency input](#) (📖 393)
- ▶ [Using DI1\(6\) and DI2\(7\) as digital inputs](#) (📖 380)
- ▶ [Using DI1\(6\) as counting input](#) (📖 386)
- ▶ [Internal interfaces | System block "LS_DigitalInput"](#) (📖 390)

7.1.1.3 Using DI1(6) as counting input

General information on use as a counting input

The counting input is used for counting fast edges. A 32-bit counter counts from a parameterisable starting value up to a parameterisable comparison value and then outputs a corresponding status signal.

- Possible counting range: $0 \dots 2^{31} - 1$ ($0 \dots 2147483647$)

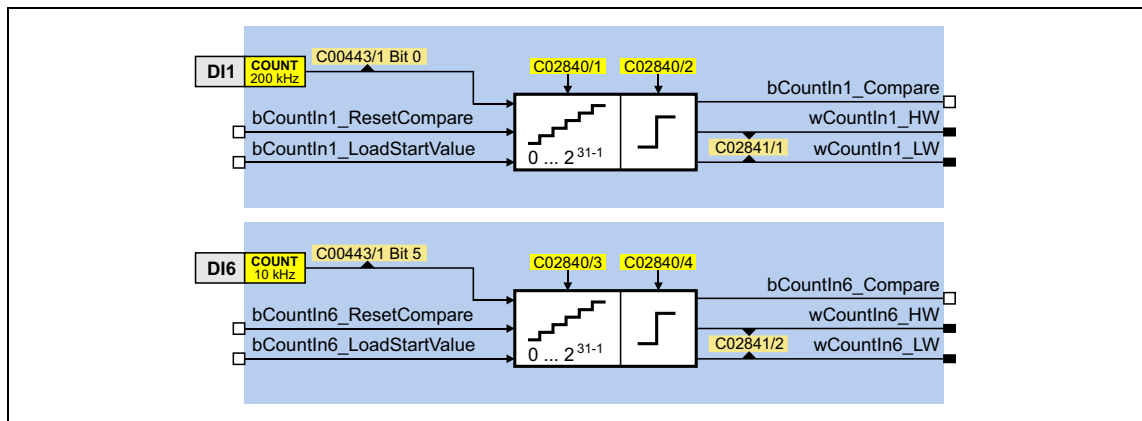


Note!

- The starting value must have been set so that it is smaller than the comparison value. Otherwise, the counter will be kept at the starting value because the condition "Count value \geq Comparison value" has been satisfied.
- Note the maximum input frequency of the respective input terminal:
 - DI1: $f_{\max} = 200 \text{ kHz}$
 - DI6: $f_{\max} = 10 \text{ kHz}$

Function assignment 4: DI1(6)=CountIn / DI2(7)=In

This setting in [C00115](#) configures the input terminal DI1 or DI6 as counting input. The input terminal DI2 or DI7 remains configured as "normal" digital input..



Short overview of parameters for the counting inputs:

Parameter	Info	Lenze setting	
		Value	Unit
Counting input DI1			
C00115/1	Fct. DI 1/2 200kHz	0: DI1(6)=In / DI2(7)=In	
C00621/3	LS_DigitalInput: bCountIn1_Reset	0: Not connected	
C00621/4	LS_DigitalInput: bCountIn1_LoadStartValue	0: Not connected	
C02840/1	CountIn1: Starting value	0	incr
C02840/2	CountIn1: Comparison value	65535	incr
C02841/1	CountIn1: Counter content	-	incr
C00443/1	Dlx: Terminal level	-	
Counting input DI6			
C00115/2	Fct. DI 6/7 10kHz	0: DI1(6)=In / DI2(7)=In	
C00621/97	LS_DigitalInput: bCountIn6_Reset	0: Not connected	
C00621/98	LS_DigitalInput: bCountIn6_LoadStartValue	0: Not connected	
C02840/3	CountIn6: Starting value	0	incr
C02840/4	CountIn6: Comparison value	65535	incr
C02841/2	CountIn6: Counter content	-	incr
C00443/1	Dlx: Terminal level	-	
Highlighted in grey = display parameter			

Internal interfaces to the application

- Relevant inputs at the [LS_DigitalInput](#) system block:

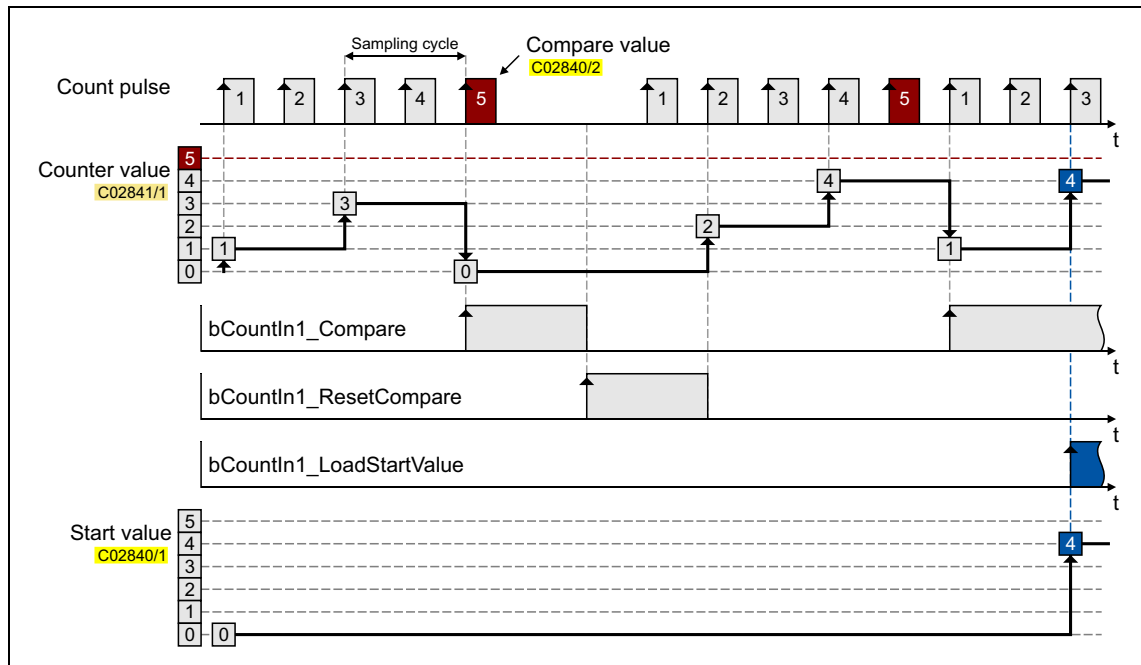
Identifier DIS code data type	Information/possible settings	
Counting input DI1		
bCountIn1_ResetCompare BOOL	Reset status signal "Comparison value reached"	
	FALSE→TRUE	The output <i>bCountIn1_Compare</i> is reset to FALSE.
bCountIn1_LoadStartValue BOOL	Load starting value into counter	
	FALSE→TRUE	The starting value set in C02840/1 is accepted as the current count value.
Counting input DI6		
bCountIn6_ResetCompare BOOL	Reset status signal "Comparison value reached"	
	FALSE→TRUE	The output <i>bCountIn6_Compare</i> is reset to FALSE.
bCountIn6_LoadStartValue BOOL	Load starting value into counter	
	FALSE→TRUE	The starting value set in C02840/3 is accepted as the current count value.

- Relevant outputs at the [LS_DigitalInput](#) system block:

Identifier DIS code data type	Value/meaning	
Counting input DI1		
bCountIn1_Compare BOOL	Status signal "Comparison value reached"	
	FALSE	Current count value < comparison value (C02840/2)
	TRUE	Current count value ≥ comparison value (C02840/2)
wCountIn1_HW wCountIn1_LW C02841/1 WORD	Current count value <ul style="list-style-type: none">• Output as High and Low word (without sign)• Possible counting range: 0 ... 2³¹ - 1	
Counting input DI6		
bCountIn6_Compare BOOL	Status signal "Comparison value reached"	
	FALSE	Current count value < comparison value (C02840/4)
	TRUE	Current count value ≥ comparison value (C02840/4)
wCountIn6_HW wCountIn6_LW C02841/2 WORD	Current count value <ul style="list-style-type: none">• Output as High and Low word (without sign)• Possible counting range: 0 ... 2³¹ - 1	

Counting behaviour

The following temporal characteristic shows the counting process depending on the signals of the interfaces described before:



[7-1] Transient characteristic of a quick counter block, sampling cycle = 1 ms

- The counter starts with the parameterised starting value.
- If the comparison value is reached or exceeded:
 - The counter jumps back to its starting value.
 - The output *bCountIn1(6)_Compare* is set to TRUE.
- If there is a FALSE-TRUE edge at the input *bCountIn1(6)_ResetCompare*, the output *bCountIn1(6)_Compare* can be reset to FALSE.
- If there is a FALSE-TRUE edge at the input *bCountIn1(6)_LoadStartValue*, the current counter content can be reset to the parameterised starting value.

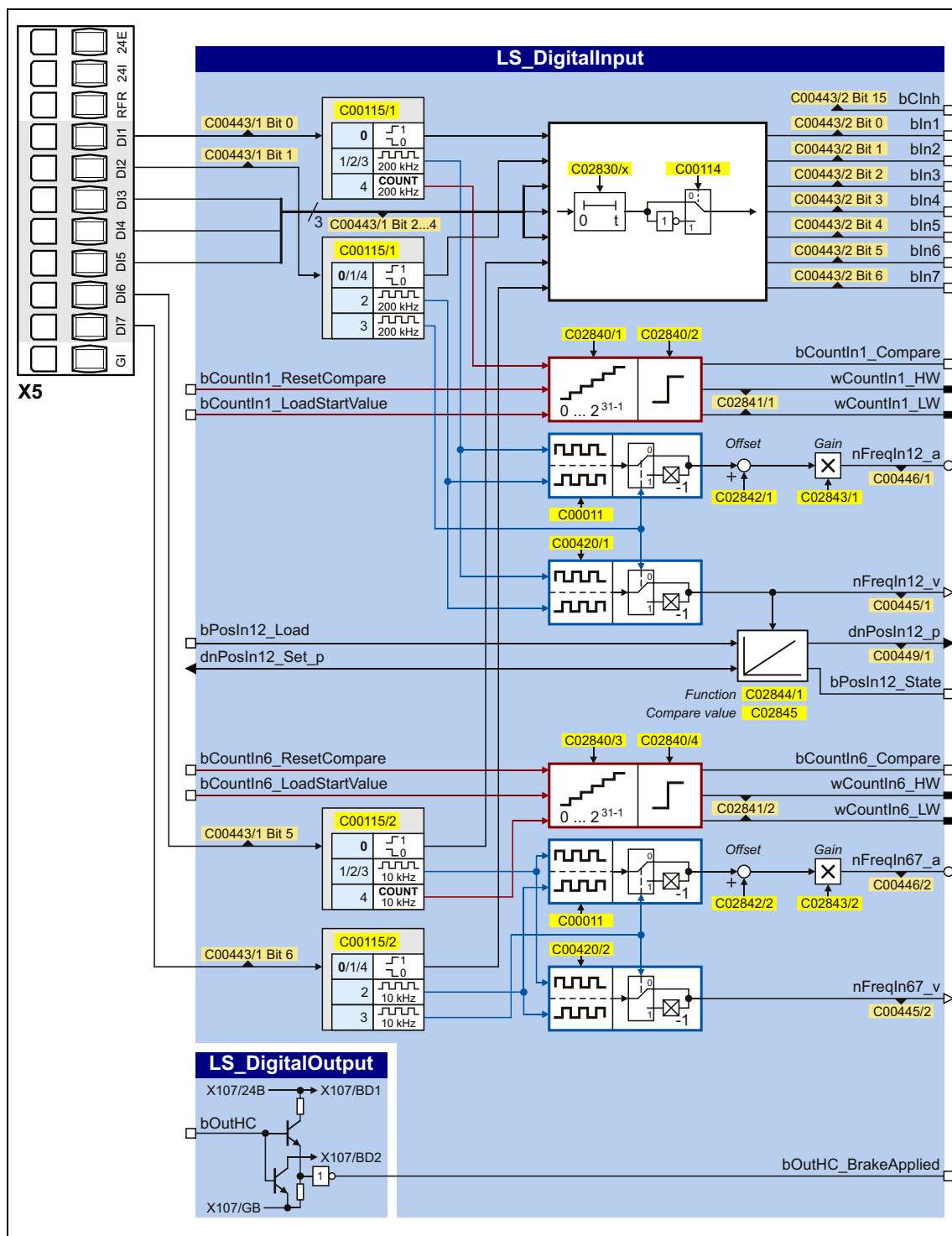
Related topics:

- ▶ [Using DI1\(6\) and DI2\(7\) as digital inputs](#) (380)
- ▶ [Using DI1\(6\) and DI2\(7\) as frequency inputs](#) (381)
- ▶ [Internal interfaces | System block "LS_DigitalInput"](#) (390)

7.1.2 Internal interfaces | System block "LS_DigitalInput"

The system block **LS_DigitalInput** maps the digital input terminals in the FB editor.

- The internal processing function of the digital DI1/2 and DI6/7 input terminals can be reconfigured in [C00115](#) if necessary. These input terminals can then be alternatively used as frequency inputs or counting inputs.
- The DI3 ... DI5 input terminals are basically designed as "normal" digital inputs.



Inputs

Identifier DIS code data type	Information/possible settings
Counting input DI1	► Using DI1(6) as counting input
bCountIn1_ResetCompare BOOL	Reset status signal "Comparison value reached"
	FALSE → TRUE The output <i>bCountIn1_Compare</i> is reset to FALSE.
bCountIn1_LoadStartValue BOOL	Load starting value into counter
	FALSE → TRUE The starting value set in C02840/1 is accepted as the current count value.
Frequency input DI1/DI2	► Output of the encoder position of the DI1/DI2 frequency input
bPosIn12_Load BOOL	Load angle integrator with starting value and reset status signal
	TRUE Angle integrator is loaded with the value at <i>dnPosIn12_Set_p</i> and <i>bPosIn12_State</i> is reset to FALSE.
dnPosIn12_Set_p DINT	Starting value for angle integrator
Counting input DI6	► Using DI1(6) as counting input
bCountIn6_ResetCompare BOOL	Reset status signal "Comparison value reached"
	FALSE → TRUE The output <i>bCountIn6_Compare</i> is reset to FALSE.
bCountIn6_LoadStartValue BOOL	Load starting value into counter
	FALSE → TRUE The starting value set in C02840/3 is accepted as the current count value.

Outputs

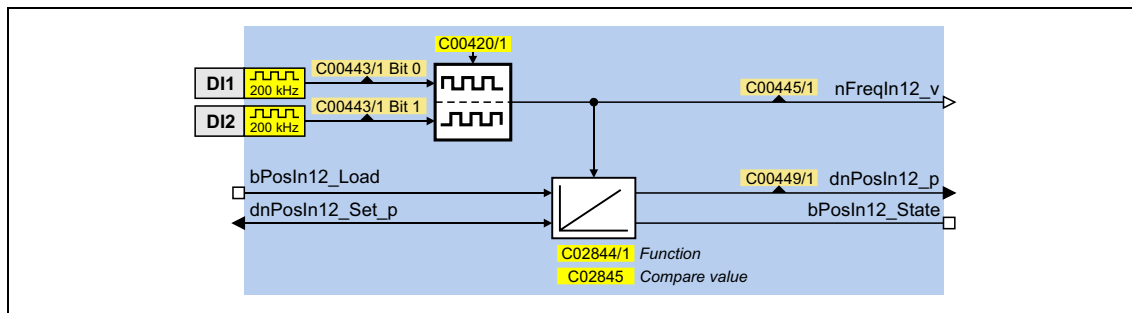
Identifier DIS code data type	Value/meaning
bCInh C00443/2 BOOL	RFR digital input (controller enable)
Digital inputs DI1 ... DI7	► Using DI1(6) and DI2(7) as digital inputs
bln1 ... bln7 C00443/2 BOOL	Digital input DI1 ... DI7
Counting input DI1	► Using DI1(6) as counting input
bCountIn1_Compare BOOL	Status signal "Comparison value reached"
	FALSE Current count value < comparison value (C02840/2)
	TRUE Current count value ≥ comparison value (C02840/2)
wCountIn1_HW wCountIn1_LW C02841/1 WORD	Current count value <ul style="list-style-type: none"> • Output as High and Low word (without sign) • Possible counting range: 0 ... $2^{31} - 1$
Frequency input DI1/DI2	► Using DI1(6) and DI2(7) as frequency inputs
nFreqIn12_a C00446/1 INT	Output frequency as scaled analog signal in [%]
nFreqIn12_v C00445/1 INT	Output frequency as speed signal in [inc/ms]
dnPosIn12_p DINT	Angle output signal <ul style="list-style-type: none"> • 65536 [incr.] ≡ 1 encoder revolution • Overflow is possible (display via <i>bPosIn12_State</i>)
bPosIn12_State BOOL	Status signal "Overflow occurred/distance processed"
	TRUE Overflow has occurred or distance is processed.

Identifier DIS code data type	Value/meaning	
Counting input DI6	► Using DI1(6) as counting input	
bCountIn1_Compare BOOL	Status signal "Comparison value reached"	
	FALSE	Current count value < comparison value (C02840/4)
	TRUE	Current count value ≥ comparison value (C02840/4)
wCountIn6_HW wCountIn6_LW C02841/2 WORD	Current count value • Output as High and Low word (without sign) • Possible counting range: 0 ... $2^{31} - 1$	
Frequency input DI6/DI7	► Using DI1(6) and DI2(7) as frequency inputs	
nFreqIn67_a C00446/2 INT	Output frequency as scaled analog signal in [%]	
nFreqIn67_v C00445/2 INT	Output frequency as speed signal in [inc/ms]	
High current output	► Switching status of the motor holding brake at the high current output	
bOutHC_BrakeApplied (from version 15.00.00) BOOL	Switching status of a motor holding brake connected to the high current output • The inverted signal logic of this status signal corresponds to the evaluation of a real brake contact which provides the FALSE state in case of a released holding brake and the TRUE state in case of a closed holding brake.	
	FALSE	High current output is controlled if an external 24-V supply is available (holding brake is released).
	TRUE	High current output is not controlled (holding brake is closed) or external 24-V supply is not available.

7.1.2.1 Output of the encoder position of the DI1/DI2 frequency input

The [LS_DigitalInput](#) system block includes an integrator for providing the encoder position.

- The integrator can take max. ± 32000 encoder revolutions.
- The starting position can be loaded via inputs.
- The internal function can be set via parameters.
- In addition to the encoder position, the "Overflow occurred/distance processed" status signal is provided.



Inputs

Identifier DIS code data type	Information/possible settings
bPosIn12_Load BOOL	Load angle integrator with starting value and reset status signal TRUE Angle integrator is loaded with the value at <i>dnPosIn12_Set_p</i> and <i>bPosIn12_State</i> is reset to FALSE.
dnPosIn12_Set_p DINT	Starting value for angle integrator

Outputs

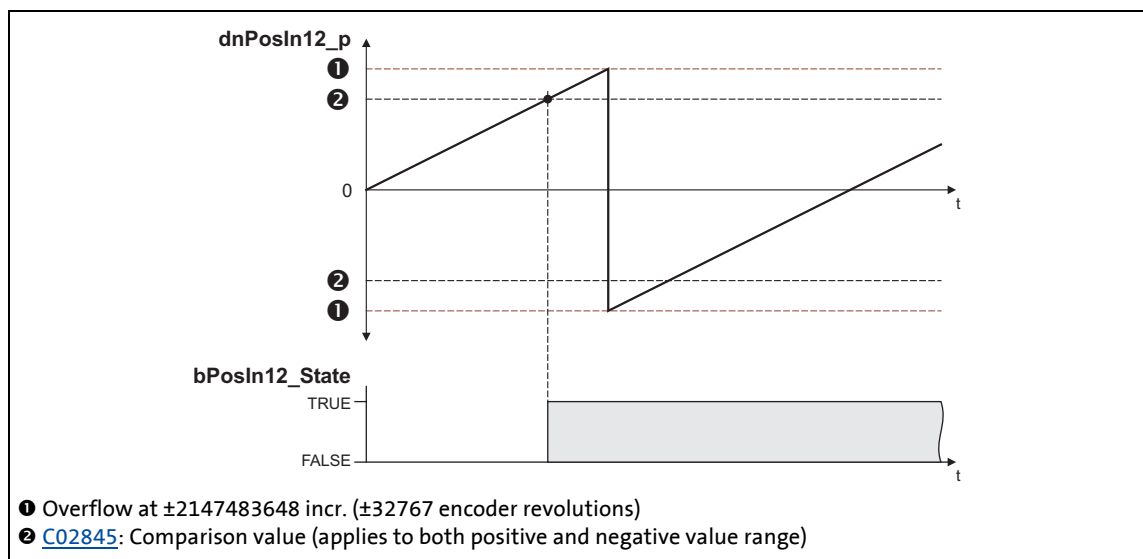
Identifier DIS code data type	Value/meaning
dnPosIn12_p DINT	Angle output signal • 65536 [incr.] \equiv 1 encoder revolution • Overflow is possible (display via <i>bPosIn12_State</i>)
bPosIn12_State BOOL	Status signal "Overflow occurred/distance processed" • Status signal can be reset via <i>bPosIn12_Load</i> . TRUE Overflow has occurred or distance is processed.

Parameter

Parameter	Possible settings			Info
C02844/1				Function
	0	Loading with level		Load integrator with TRUE level at the <i>bPosIn12_Load</i> input (Lenze setting).
	1	Loading with edge		Load integrator with FALSE/TRUE edge at the <i>bPosIn12_Load</i> input.
	2	Loading with level + reset		Load integrator when reaching the comparison value or with TRUE level at the <i>bPosIn12_Load</i> input.
C02845	0		2000000000	Comparison value <ul style="list-style-type: none"> • Is valid for both the positive and the negative value range. • Lenze setting: 0

Function at constant input value

Selection: [C02844/1](#) = "0: Loading with level" or "1: Loading with edge"



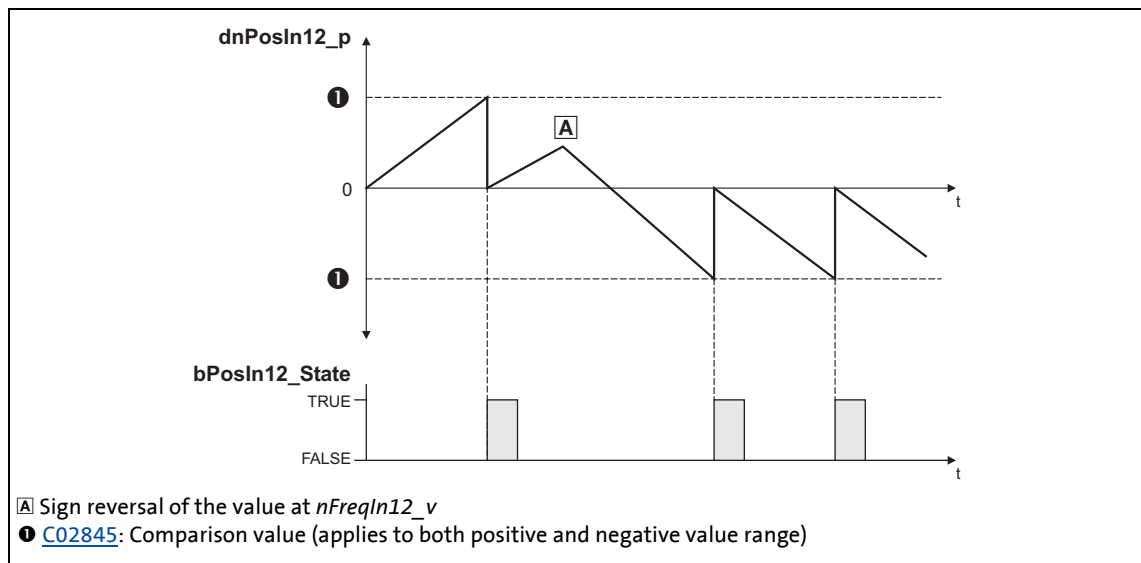
[7-2] Switching performance if the overflow is in the positive direction

- If "0: Loading with level" is selected in [C02844/1](#), the *bPosIn12_Load* input is status-controlled: In case of a TRUE signal, the integrator is loaded with the value at *dnPosIn12_Set_p* and the *bPosIn12_State* output is set to FALSE.
- If "1: Loading with edge" is selected in [C02844/1](#), the *bPosIn12_Load* input is edge-controlled: In case of a FALSE/TRUE edge, the integrator is loaded with the value at *dnPosIn12_Set_p* and then immediately continues to integrate, the *bPosIn12_State* output is set to FALSE.
- A positive *nFreqIn12_v* signal is incremented (the counter content is increased with every cycle).
- A negative *nFreqIn12_v* signal is decremented (the counter content is reduced with every cycle).

- *dnPosIn12_p* provides the counter content of the bipolar integrator.
 - If the counter content exceeds a value of +32767 encoder revolutions (corresponds to +2147483647 incr.), an overflow occurs and the counting process continues at a value of -32768 encoder revolutions.
 - If the counter content falls below a value of -32768 encoder revolutions (corresponds to -2147483648 incr.), an overflow occurs and the counting process starts at a value of +32767 encoder revolutions.
- *bPosIn12_State* is set to TRUE if the comparison value set in [C02845](#) has been reached.

Function at input value with sign reversal

Selection: [C02844/1](#) = "2: Loading with level + reset"



[7-3] Switching performance if the input signal changes signs

- If "2: Loading with level + reset" is selected in [C02844/1](#), the *bPosIn12_Load* input is status-controlled: In case of a TRUE signal, the integrator is loaded with the value at *dnPosIn12_Set_p* and the *bPosIn12_State* output is set to FALSE.
- A positive *nFreqIn12_v* signal is incremented (the counter content is increased with every cycle).
- A negative *nFreqIn12_v* signal is decremented (the counter content is reduced with every cycle).
- *dnPosIn12_p* provides the counter content of the bipolar integrator.
 - If the positive counter content is higher than the comparison value set in [C02845](#), the comparison value will be subtracted from the counter content, and *bPosIn12_State* will be set to TRUE for one task cycle.
 - If the negative counter content is lower than the comparison value set in [C02845](#), the comparison value will be added to the counter content, and *bPosIn12_State* will be set to TRUE for one task cycle.

Calculation of the output signal

The output value at *dnPosIn12_p* is calculated as per the formula below:

$$\text{dnPosIn12_p [incr.]} = \text{nFreqIn12_v [rpm]} \cdot t [\text{s}] \cdot 65535 [\text{incr./rev.}]$$

t = integration time

16384 \approx 15000 rpm

1 \approx 1 incr.

Example

You want to determine the counter content of the integrator at a certain speed at the input and a certain integration time *t*.

Given values:

- *nFreqIn12_v* = 1000 rpm \approx integer value 1092
- Integration time *t* = 10 s
- Starting value of the integrator = 0

Solution:

- Conversion of the *nFreqIn12_v* input signal:

$$1000 \text{ rpm} = \frac{1000 \text{ rev.}}{60 \text{ s}}$$

- Calculation of the output value:

$$\text{dnPosIn12_p} = \frac{1000 \text{ rev.}}{60 \text{ s}} \cdot 10 \text{ s} \cdot \frac{65535 \text{ incr.}}{\text{Rev.}} = 10922666 \text{ incr.}$$

7.1.2.2 Switching status of the motor holding brake at the high current output

This function extension is available from version 15.00.00!

For a simple monitoring of the switching status of a motor holding brake connected to the high current output, the *bOutHC_BrakeApplied* status signal can be used.

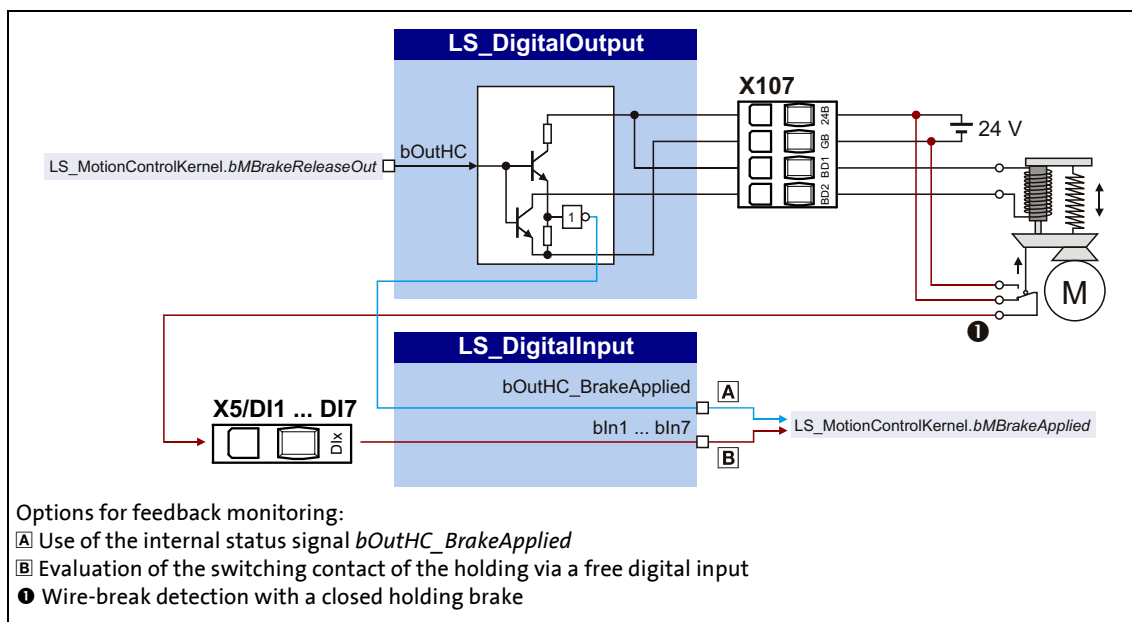
Identifier	Data type	Value/meaning
bOutHC_BrakeApplied	BOOL	Switching status of a motor holding brake connected to the high current output <ul style="list-style-type: none"> The inverted signal logic of this status signal corresponds to the evaluation of a real brake contact which provides the FALSE state in case of a released holding brake and the TRUE state in case of a closed holding brake.
	FALSE	High current output is controlled if an external 24-V supply is available (holding brake is released).
	TRUE	High current output is not controlled (holding brake is closed) or external 24-V supply is not available. In the closed state, an open-circuit monitoring is available so that a brake status error is created in case of an open circuit.

Required steps for a simple monitoring of the switching state:

1. Link the *bOutHC_BrakeApplied* status signal with the *bMBrakeApplied* input of the SB [LS_MotionControlKernel](#).
2. Activate feedback monitoring of the holding brake control: Set bit 5 in [C02582](#) to "1".

Connection principle

In the following, a connection principle for controlling a motor holding brake via the high current output is described with the two options for feedback monitoring:



[7-4] Connection principle motor holding brake

7.2 Digital output terminals

The controller has

- three parameterisable output terminals (DO1 ... DO3) for outputting digital signals
- a relay output (terminal strip X101),
- a (high-current) output for controlling a brake (terminal strip X107).



Note!

Initialisation behaviour:

- After mains switching up to the start of the application, the digital outputs remain set to FALSE.

Exception handling:

- In case of a critical exception in the application (e.g. reset), the digital outputs are set to FALSE considering the terminal polarity parameterised in [C00118](#).

Switching cycle diagnostics of the relay:

- A reference for evaluating the wear limit can be obtained via the number of switching cycles of the relay displayed in [C00177/2](#).

Parameterisation dialog in the »Engineer«:

Button	Function
	Indicates that the polarity of the output is HIGH active. The polarity can be changed from HIGH active to LOW active by clicking this button.
	Indicates that the polarity of the output is LOW active. The polarity can be changed from LOW active to HIGH active by clicking this button.

Short overview of parameters for the digital output terminals:

Parameter	Info	Lenze setting	
		Value	Unit
Digital outputs DO1 ... DO3			
C00118	DigOutX: Inversion	Bit coded	
C00423/3	DO1 ON delay	0.000	s
C00423/4	DO1 OFF delay	0.000	s
C00423/5	DO2 ON delay	0.000	s
C00423/6	DO2 OFF delay	0.000	s
C00423/7	DO3 ON delay	0.000	s
C00423/8	DO3 OFF delay	0.000	s
C00444/1	DOx: Input level	-	
C00444/2	DOx: Terminal level	-	
High current output			
C00423/9	DO "High Current" ON delay	0.000	s
C00423/10	DO "High Current" OFF delay	0.000	s
C00117	Status of brake output BD	-	
Relay output			
C00423/1	Relay ON delay	0.000	s
C00423/2	Relay OFF delay	0.000	s
Digital outputs - terminal configuration			
C00621/1	LS_DigitalOutput:bRelay	1001: LA_nCtrl_bDriveFail	
C00621/2	LS_DigitalOutput:bOut1	1000: LA_nCtrl_bDriveReady	
C00621/99	LS_DigitalOutput: bOut2	0: Not connected	
C00621/100	LS_DigitalOutput: bOut3	0: Not connected	
C00621/101	LS_DigitalOutput: bOut HighCurrent	0: Not connected	
Highlighted in grey = display parameter			

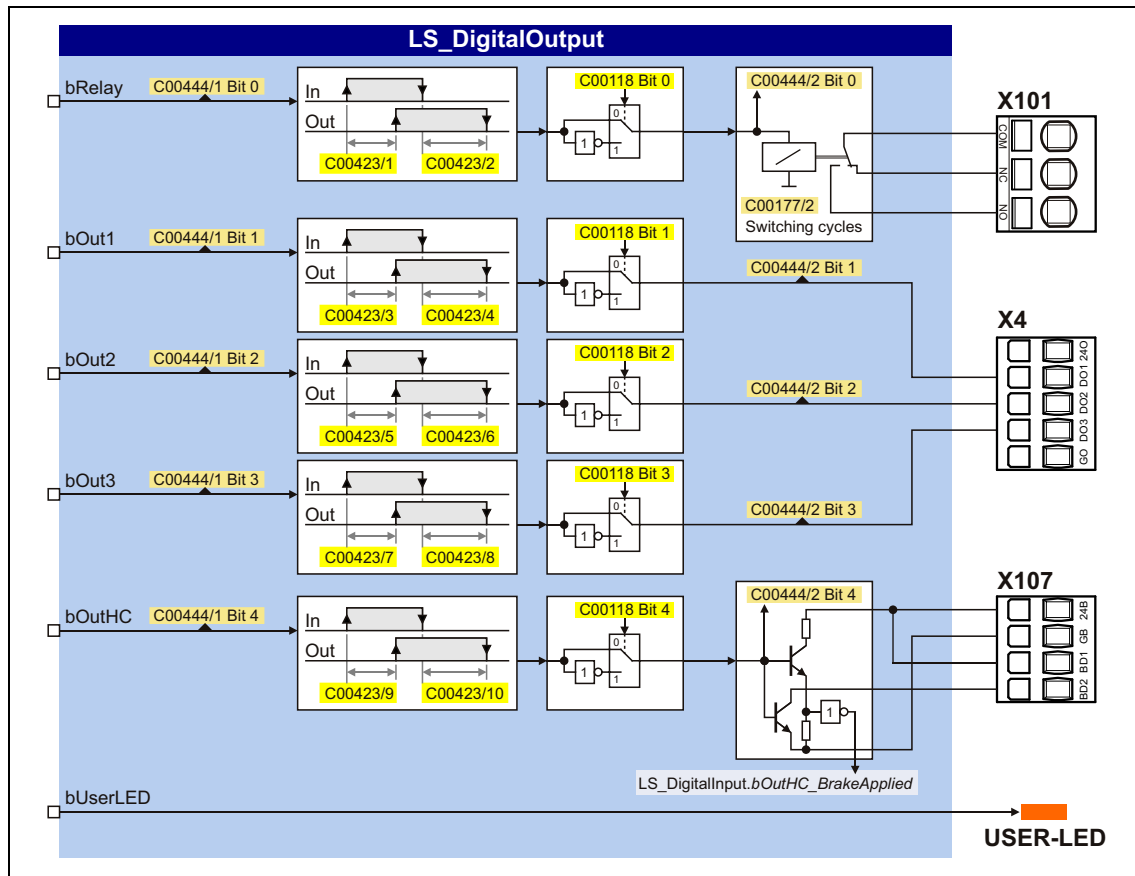
Related topics:

- ▶ [Configuring exception handling of the output terminals](#) (📖 420)
- ▶ [User-defined terminal assignment](#) (📖 421)

7.2.1 Internal interfaces | System block "LS_DigitalOutput"

The **LS_DigitalOutput** system block maps the digital output terminals in the FB editor.

- From **version 12.00.00 onwards**, the orange USER LED at the front of the controller can be controlled with any digital process signal via the *bUserLED* input.



Input	Information/possible settings	
bRelay DIS code data type C00444/1 BOOL	Relay output, potential-free two-way switch	
bOut1 ... bOut3 C00444/1 BOOL	Digital output DO1 ... DO3	
bOutHC C00444/1 BOOL	Output for brake control	
bUserLED C00444/1 BOOL (from version 12.00.00)	Control of the USER LED at the front of the controller	
	FALSE	USER LED off
	TRUE	USER LED on

7.3 Analog terminals

The analog input terminals together with the analog output terminals are located on the X3 plug connector.

Analog input terminals

The drive controller has four analog input terminals for detecting two current signals and two voltage signals:

- Voltage signals in the ± 10 V range
The voltage signal can be e.g. an analog speed setpoint or the signal of an external sensor (temperature, pressure, etc.).
- Current signals in the 0/+ 4 ... + 20 mA range
For open-circuit monitoring, the current signal can be evaluated with regard to "Life Zero" or "Dead Zero":
 - 0 ... 20 mA, without open-circuit monitoring
 - 4 ... 20 mA, with open-circuit monitoring



Note!

To avoid undefined states, free input terminals of the controller must be assigned as well, e.g. by applying 0 V to the terminal.

Analog output terminals

The drive controller has four analog output terminals.

- Two output terminals output an analog current signal (O1I, O2I)
- Two output terminals output an analog voltage signal (O1U, O2U)



Note!

Initialisation behaviour:

- After mains switching up to the start of the application, the analog outputs remain set to 0 V.

Exception handling:




- In case of a critical exception in the application (e.g. reset), the analog outputs are set to 0 V.

Parameterisation dialog in the »Engineer«:

Terminal assignment

Pin connection: Analog terminals

System signals		X3		Application signals		
Signal name	Value			Setting	Value	Application signal name
10V reference (max. 10mA)	←		AR			
Analog input 1	<input type="text" value="0,00"/> V		A1U	<input type="button" value="▷"/>	<input type="text" value="0,00"/> %	LA_NCtrl: nMainSetValue_a ...
Analog input 2	<input type="text" value="0,00"/> mA		A2U	<input type="button" value="▷"/>	<input type="text" value="0,00"/> %	- ...
Reference potential GND		A2I			
Analog output 1 (voltage)	<input type="text" value="0,00"/> V		GA	<input type="button" value="◁"/>	<input type="text" value="0,00"/> %	<input type="text" value="LA_nCtrl_nMotorSpeedAct_a"/> ▾
Analog output 1 (current)	<input type="text" value="0,000"/> mA		O1U	<input type="button" value="◁"/>	<input type="text" value="0,00"/> %	<input type="text" value="Not interconnected"/> ▾
Analog output 2 (voltage)	<input type="text" value="0,00"/> V		O1I	<input type="button" value="◁"/>	<input type="text" value="0,00"/> %	<input type="text" value="Not interconnected"/> ▾
Analog output 2 (current)	<input type="text" value="0,000"/> mA		O2U	<input type="button" value="◁"/>	<input type="text" value="0,00"/> %	<input type="text" value="Not interconnected"/> ▾
			O2I	<input type="button" value="◁"/>	<input type="text" value="0,00"/> %	<input type="text" value="Not interconnected"/> ▾

Button	Function
	Parameterising analog input (404)
	Parameterising analog output (408)
	Open the parameterising dialog for assigning application inputs to the analog input. ▶ Changing the terminal assignment with the »Engineer« (425)


Short overview of parameters for the analog terminals:

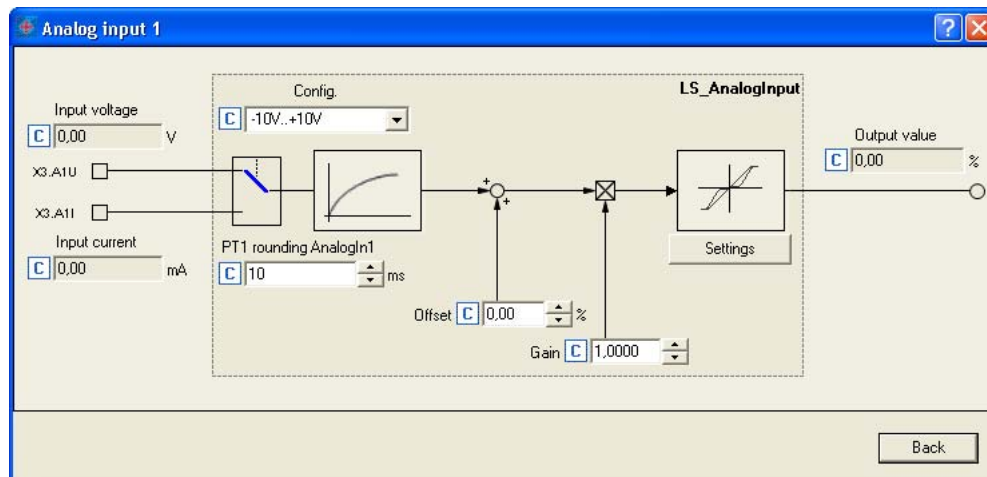
Parameter	Info	Lenze setting	
		Value	Unit
Analog input 1			
C00028/1	AIN1: Input voltage	-	V
C00029/1	AIN1: Input current	-	mA
C00033/1	AIN1: Output value (to application)	-	%
Analog input 2			
C00028/2	AIN2: Input voltage	-	V
C00029/2	AIN2: Input current	-	mA
C00033/2	AIN2: Output value (to application)	-	%
Analog output 1			
C00439/1	O1U: Input value (from application)	-	%
C00439/3	O1I: Input value (from application)	-	%
C00436/1	O1U: Voltage	-	V
C00437/1	O1I: Current	-	mA
Analog output 2			
C00439/2	O2U: Input value (from application)	-	%
C00439/4	O2I: Input value (from application)	-	%
C00436/2	O2U: Voltage	-	V
C00437/2	O2I: Current	-	mA
Analog outputs - terminal assignment			
C00620/1	LS_AnalogOutput: nOut1_a (V)	1003: LA_nCtrl_nMotorSpeedAct_a	
C00620/39	LS_AnalogOutput: nOut1_a (I)	0: Not connected	
C00620/38	LS_AnalogOutput: nOut2_a (V)	0: Not connected	
C00620/40	LS_AnalogOutput: nOut2_a (I)	0: Not connected	
Highlighted in grey = display parameter			

Related topics:

- ▶ [Configuring exception handling of the output terminals](#) (420)
- ▶ [User-defined terminal assignment](#) (421)

7.3.1 Parameterising analog input

By clicking on the  button on the **Terminal assignment** tab, you reach the parameterising dialog for the corresponding analog input:



Short overview of parameters for the analog inputs:

Parameter	Info	Lenze setting	
		Value	Unit
Analog input 1			
C00034/1	AIN1: Config.	0: -10V..+10V	
C00026/1	AIN1: Offset	0.00	%
C00027/1	AIN1: Gain	1.0000	
C00028/1	AIN1: Input voltage	-	V
C00029/1	AIN1: Input current	-	mA
C00033/1	AIN1: Output value (to application)	-	%
C00440/1	PT1 rounding AnalogIn1	10	ms
C00598/1	Resp. to open circuit AIN1	3: TroubleQuickStop	
Analog input 2			
C00034/2	AIN2: Config.	0: -10V..+10V	
C00026/2	AIN2: Offset	0.00	%
C00027/2	AIN2: Gain	1.0000	
C00028/2	AIN2: Input voltage	-	V
C00029/2	AIN2: Input current	-	mA
C00033/2	AIN2: Output value (to application)	-	%
C00440/2	PT1 rounding AnalogIn2	10	ms
C00598/2	Resp. to open circuit AIN2	3: TroubleQuickStop	
Highlighted in grey = display parameter			

Using current input A1I/A2I

In the Lenze setting, voltage signals in the range of ± 10 V are evaluated via the A1U and A2U input terminals. If current signals are detected via the A1I or A2I input terminals instead, the selection "1: 0...20mA" or "2: 4...20mA" is to be set in [C00034](#).

**Tip!**

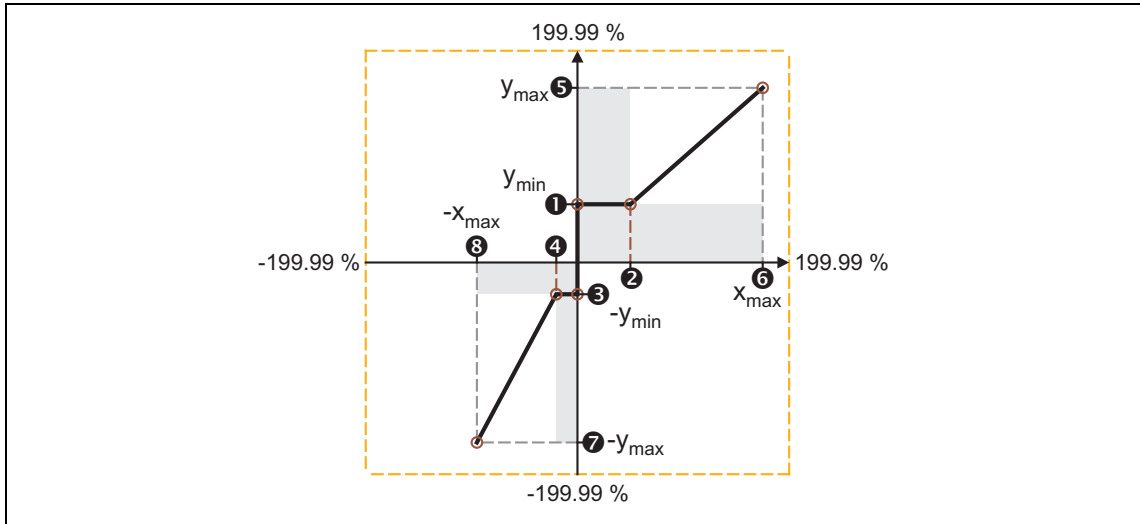
By selecting "2: 4...20mA", you can implement a 4 ...20 mA current loop, e.g. for stipulation of the speed setpoint.

Open-circuit monitoring

In the case of configuration as a 4 ... 20 mA current loop, the fault response set in [C00598](#) takes place in the event of a wire breakage (Lenze setting: "TroubleQuickStop").

7.3.1.1 Signal adaptation by means of characteristic

According to the illustration below, an individual characteristic can be parameterised for the analog inputs via the subcodes of [C00010](#) and [C00020](#) to provide different slopes and a dead band. Here, the input signal corresponds to the X axis and the output signal corresponds to the Y axis:




[7-5] Characteristic for analog inputs

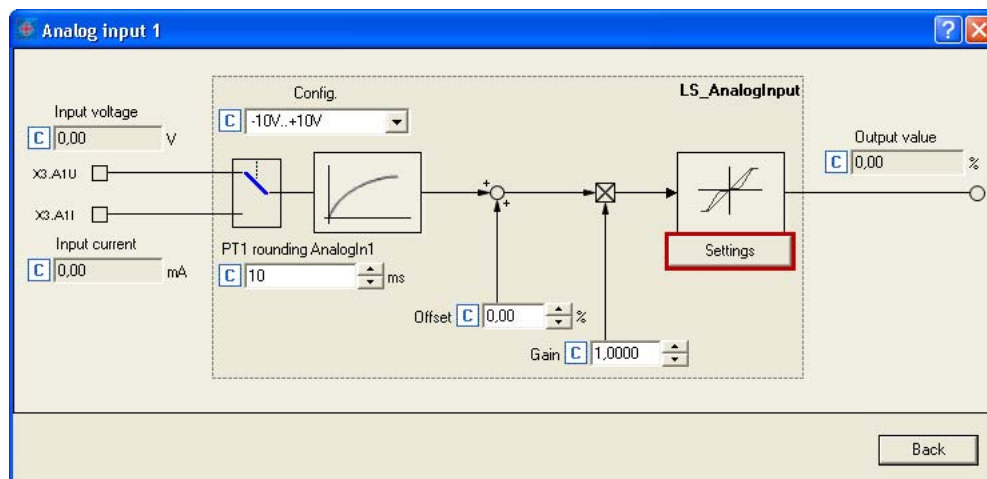
Parameter	Info	Lenze setting	
		Value	Unit
C00010/1	➊ AIN1: (+y0) = min	0.00	%
C00010/2	➋ AIN1: (+x0) = Dead band	1.00	%
C00010/3	➌ AIN1: (-y0) = (-min)	0.00	%
C00010/4	➍ AIN1: (-x0) = (-Dead band)	1.00	%
C00010/5	➎ AIN1: (+ymax)	199.99	%
C00010/6	➏ AIN1: (+xmax)	199.99	%
C00010/7	➐ AIN1: (-ymax)	199.99	%
C00010/8	➑ AIN1: (-xmax)	199.99	%
C00020/1	➊ AIN2: (+y0) = min	0.00	%
C00020/2	➋ AIN2: (+x0) = Dead band	1.00	%
C00020/3	➌ AIN2: (-y0) = (-min)	0.00	%
C00020/4	➍ AIN2: (-x0) = (-Dead band)	1.00	%
C00020/5	➎ AIN2: (+ymax)	199.99	%
C00020/6	➏ AIN2: (+xmax)	199.99	%
C00020/7	➐ AIN2: (-ymax)	199.99	%
C00020/8	➑ AIN2: (-xmax)	199.99	%

In the »Engineer«, there is a parameterising dialog for entering the characteristic. This dialog also displays the set characteristic graphically.

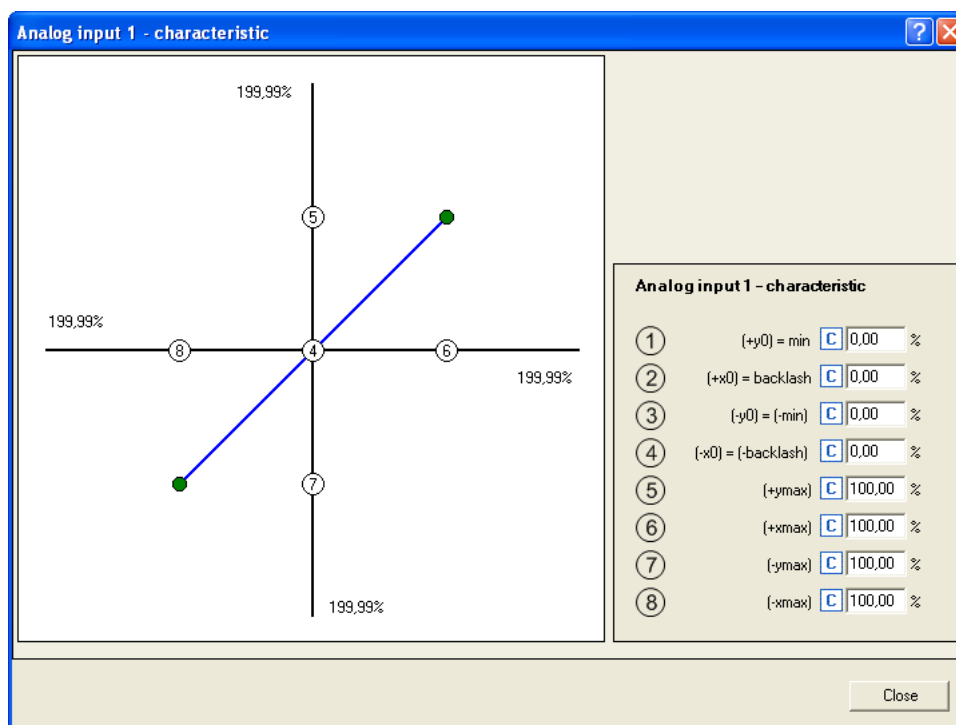


Proceed as follows to open the dialog for parameterising the characteristic:


1. Go to the **Terminal assignment** tab and select the "Analog terminals" entry in the **Control connections** list field.
2. Click on the  button for the analog input in order to open the *Analog input* dialog.

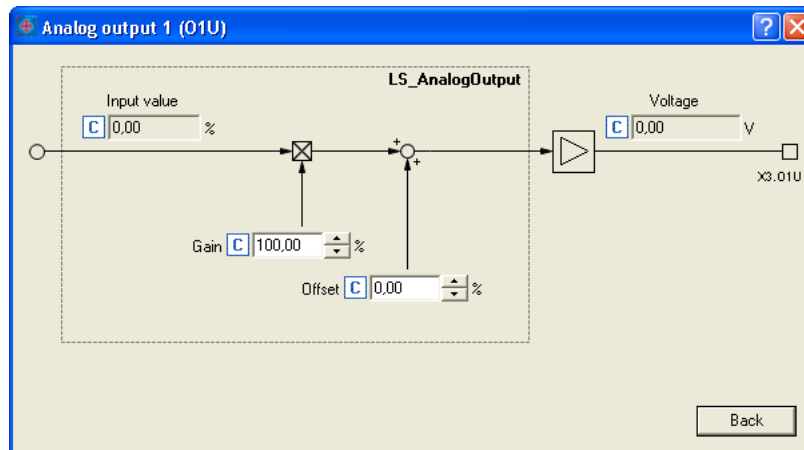


3. Click on the **Settings** button in order to open the *Analog input - Characteristic* dialog box:



7.3.2 Parameterising analog output

By clicking on the  button on the **Terminal assignment** tab, you can open the parameterising dialog for the corresponding analog output (here: O1U):

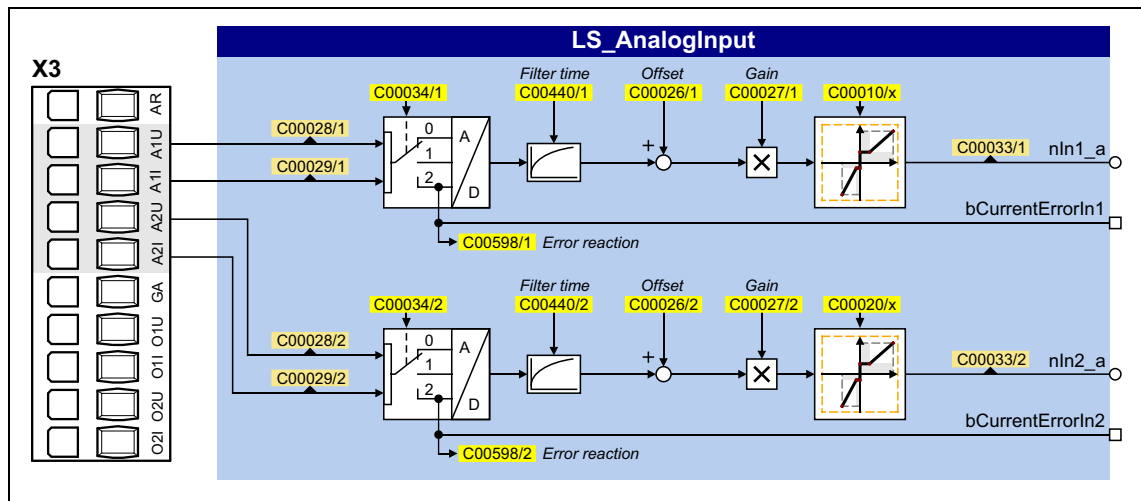


Short overview of parameters for the analog outputs:

Parameter	Info	Lenze setting	
		Value	Unit
Analog output 1			
C00434/1	O1U: Gain	100.00	%
C00435/1	O1U: Offset	0.00	%
C00439/1	O1U: Input value (from application)	-	%
C00439/3	O1I: Input value (from application)	-	%
C00436/1	O1U: Voltage	-	V
C00437/1	O1I: Current	-	mA
Analog output 2			
C00434/2	O2U: Gain	100.00	%
C00435/2	O2U: Offset	0.00	%
C00439/2	O2U: Input value (from application)	-	%
C00439/4	O2I: Input value (from application)	-	%
C00436/2	O2U: Voltage	-	V
C00437/2	O2I: Current	-	mA
Highlighted in grey = display parameter			

7.3.3 Internal interfaces | System block "LS_AnalogInput"

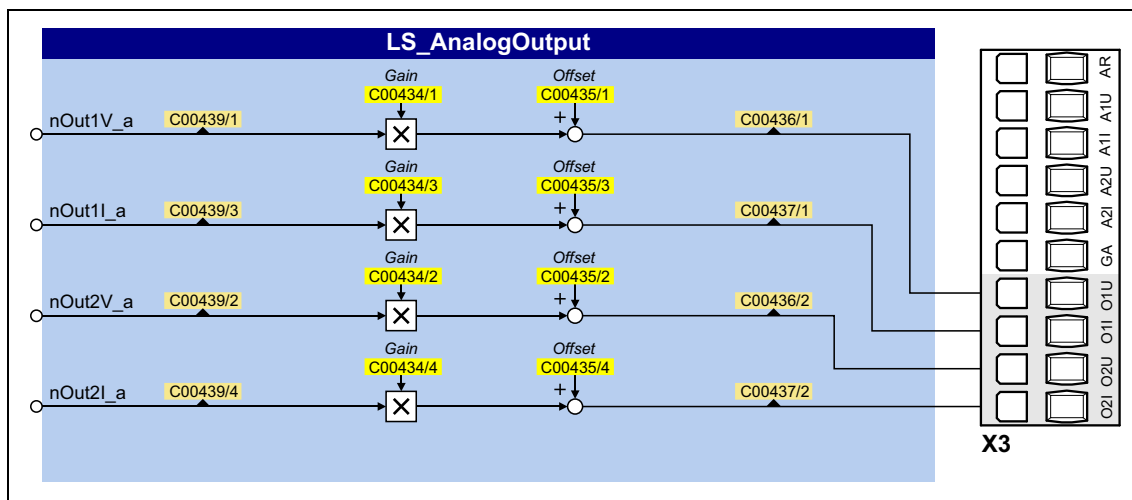
The **LS_AnalogInput** system block maps the analog inputs in the FB editor.



Output	Value/meaning
DIS code data type	
nIn1_a C00033/1 INT	Analog input 1 <ul style="list-style-type: none"> Scaling: <ul style="list-style-type: none"> $\pm 2^{14} \equiv \pm 10 \text{ V}$ for use as voltage input $+2^{14} \equiv +20 \text{ mA}$ for use as current input
bCurrentErrorIn1 BOOL	Status signal "Current input error" <ul style="list-style-type: none"> Only when analog input 1 is used as current input. Application: Cable-breakage monitoring of the 4 ...20 mA circuit.
TRUE	$ I_{AIN1} < 4 \text{ mA}$
nIn2_a C00033/2 INT	Analog input 2 <ul style="list-style-type: none"> Scaling: <ul style="list-style-type: none"> $\pm 2^{14} \equiv \pm 10 \text{ V}$ for use as voltage input $+2^{14} \equiv +20 \text{ mA}$ for use as current input
bCurrentErrorIn2 BOOL	Status signal "Current input error" <ul style="list-style-type: none"> Only when analog input 2 is used as current input. Application: Cable-breakage monitoring of the 4 ...20 mA circuit.
TRUE	$ I_{AIN2} < 4 \text{ mA}$

7.3.4 Internal interfaces | System block "LS_AnalogOutput"

The **LS_AnalogInput** system block maps the analog outputs in the FB editor.



Input	Information/possible settings
DIS code data type nOut1V_a C00439/1 INT	Analog output 1 (voltage) • Scaling: $2^{14} \equiv 16384 \equiv 10 \text{ V}$
nOut1I_a C00439/3 INT	Analog output 1 (current) • Scaling: $2^{14} \equiv 16384 \equiv 20 \text{ mA}$
nOut2V_a C00439/2 INT	Analog output 2 (voltage) • Scaling: $2^{14} \equiv 16384 \equiv 10 \text{ V}$
nOut2I_a C00439/4 INT	Analog output 2 (current) • Scaling: $2^{14} \equiv 16384 \equiv 20 \text{ mA}$

7.4 Touch probe detection

"Touch probe" (TP) in general means quick detection of a position by a quick sensor if the pulse duration of the sensor signal is too short to be detected by a "normal" digital input (scanning time: 1 ms).

Moreover, touch probe requires exact detection of the position. Here, the difference in position between the 1 ms position detection and the touch probe signal is considered as correction value.

Applications:

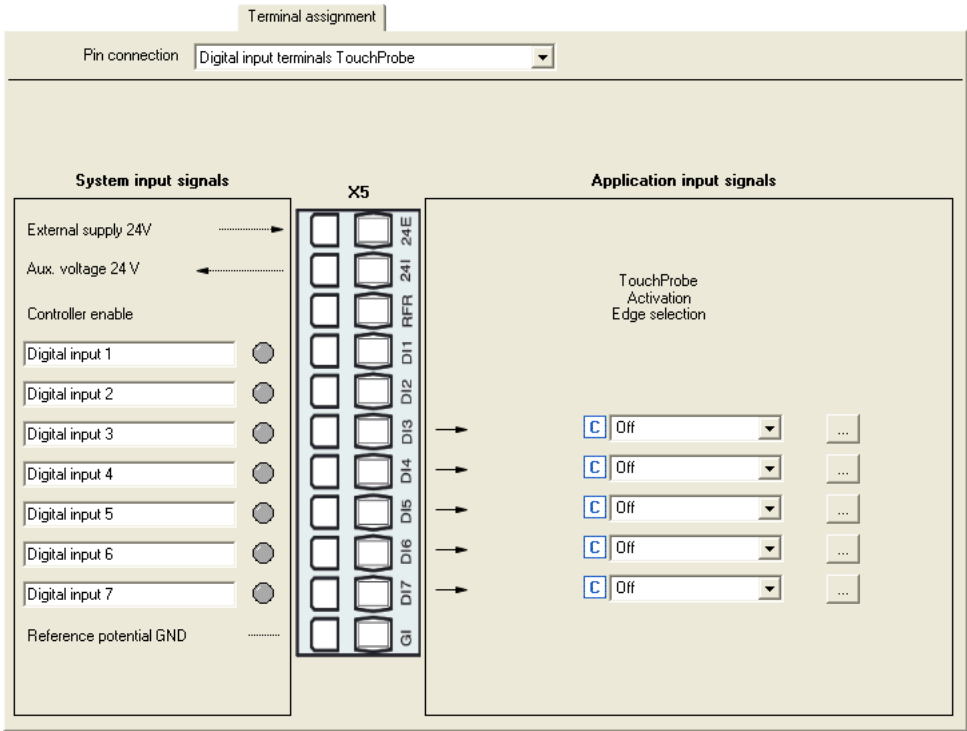
- Precise approach of a position at a previously detected signal mark
- High-precision traversing of a section starting at a previously detected signal mark
- Safe detection of signal marks with very short signal edges
- Measurement of a high-precision position at a previously detected signal mark
- Homing to touch probe (homing signal)
- Relative residual path positioning (traversing of a section starting at signal mark)
- Absolute positioning to target position, activated by a safely detected signal mark
- Position measurement of a distance between 2 signal marks


Overview of touch probe signal sources

The 8400 TopLine provides the following signal sources for touch probe detection which can be configured independently:

Signal source	Edge sensitivity	Applications
Digital input DI3 ... Digital input DI7	Rising edge, falling edge, rising and falling edge (parameterisable)	Homing Residual path positioning Position measurement Freely interconnectable
Z-track encoder (from version 12.00.00)		Homing
Z-track resolver (from version 12.00.00)		Homing

Parameterisation dialog in the »Engineer«:



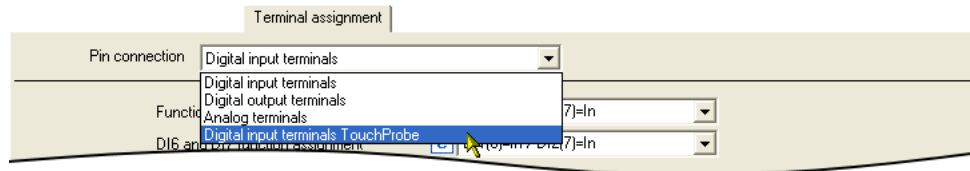
Button	Function
	Open the parameterisation dialog for the selected TP signal source. ▶ Parameter setting (□ 413)


Parameter	Info	Lenze setting
C02810/3...7	TPDigIn3 ... TPDigIn7: Edge selection	0: Off

7.4.1 Parameter setting

Proceed as follows to open the parameterisation dialog for setting a TP signal source:

1. Go to the **Terminal Assignment** tab and select "Digital input terminals TouchProbe" in the **Control connections** list field:

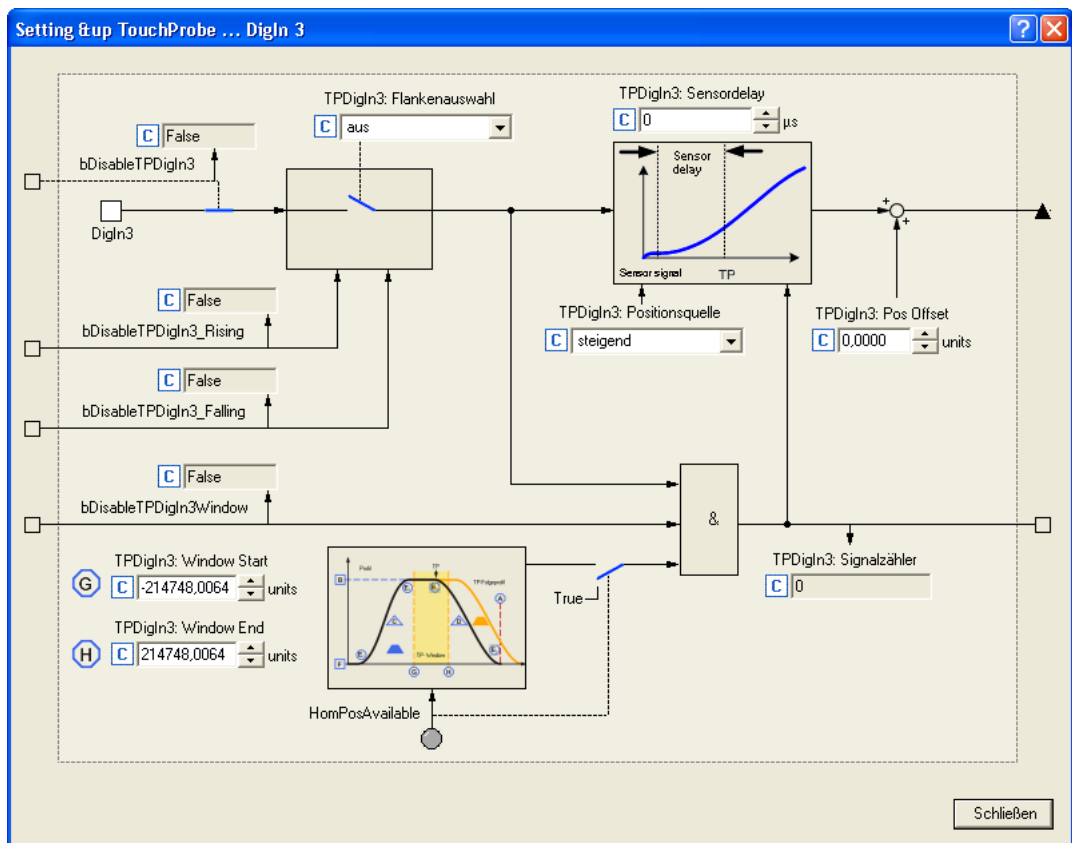


2. Click the  button for the digital input that is to be set for the touch probe detection.



Tip!

If the "Table positioning" technology application is used, the following parameterisation dialog can be opened for the selected TP signal source in the parameterisation dialogs for the [Profile entry](#) and the basic "[Homing](#)" function via the **Set up touch probe...** button:



Short overview of the relevant parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C02810/3...7	TPDigIn3 ... TPDigIn7: Edge selection	0: Off	
C02811/3...7	TPDigIn3 ... TPDigIn7: Sensor delay	0	µs
C02812/3...7	TPDigIn3 ... TPDigIn7: Pos Offset	0.0000	units
C02813/1...3	TPDigIn3 ... TPDigIn5: Window start	-214748.3647	units
C02814/1...3	TPDigIn3 ... TPDigIn5: Window end	214748.3647	units
C02815/3...7	TPDigIn3 ... TPDigIn7: Position source	0: Position encoder actual value	
C02816/3...7	TPDigIn3 ... TPDigIn7: Signal counter	-	
C02817/3...7	TPDigIn3 ... TPDigIn7: TP position	-	units

Highlighted in grey = display parameter

Edge selection

Select which edge the corresponding input is to respond to.

- In the case of signal sources DI3 ... DI5, the edge sensitivity can also be dynamically changed via inputs at the [LS_TouchProbe](#) SB.

Sensor delay

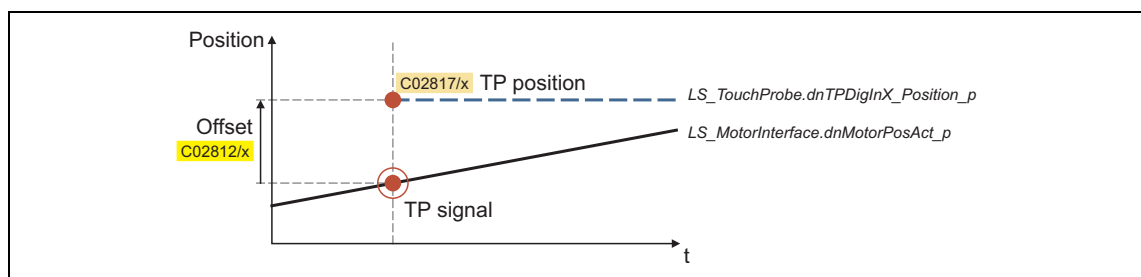
This setting serves to compensate for a sensor delay of the touch probe sensor, if any.

- Typical values for laser photoelectric barriers are e.g. 300 µs.
- Delay of the digital inputs for the 8400 device series:
 - 5 µs for a rising edge
 - 25 µs for a falling edge
- Internal automatic compensation for device-internal signal delay due to encoder zero pulse.

Pos Offset

Use this setting to add an offset to the position value measured by touch probe. This may be required if the touch probe sensor has assumed a disadvantageous position on the machine. By adding an offset the touch probe sensor can be moved to a position which is more convenient to the application.

The offset value given in [units] is added to the TP position value which depends on the position source selected in [C02815/x](#). The offset value influences the display of the TP position ([C02817/x](#)), home position values internally derived from the touch probe and the respective output *dnTpDigInX_Position_p* at the SB [LS_TouchProbe](#). For this purpose, the offset value is converted internally from [units] to [increments].



Window start / end

Via the two parameters Window start ([C02813/x](#)) and Window end ([C02814/x](#)), acceptance windows can be set for the DI3 ... DI5 signal sources in which the touch probe signal is accepted.

- The acceptance windows can be dynamically activated via the inputs at the [LS TouchProbe](#) SB.
- If the actual position is outside the acceptance window, touch probe is automatically deactivated.
- If both window limits are set to " ± 214748.3647 ", the acceptance window does not have any effect.
- To properly use this function, the drive needs to know the home position (zero position).

Position source

Selection of the position signal source to be measured with touch probe. This usually is the actual position of the motor / encoder position encoder.

**Note!**

When the touch probe functionality is used in the operating modes "[Positioning](#)" and "[Homing](#)":

Make sure that the position source of the respective TP signal in [C02815/x](#) is set to "0: position encoder actual value". Otherwise, no TP correction will take place.

7.4.1.1 Z-track encoder as a touch probe signal source

From version 12.00.00 onwards, the Z-track of a connected encoder is also supported as a touch probe signal source.

Short overview of the relevant parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C02810/8	TPEncoderZTrack: Edge selection	0: Off	
C02811/8	TPEncoderZTrack: Sensor delay	0	µs
C02812/8	TPEncoderZTrack: Pos offset	0.0000	units
C02813/4	TPEncoderZTrack: Window start	-214748.3647	units
C02814/4	TPEncoderZTrack: Window end	214748.3647	units
C02815/8	TPEncoderZTrack: Position source	0: Position encoder actual value	
C02816/8	TPEncoderZTrack: Signal counter	-	
C02817/8	TPEncoderZTrack: TP position	-	units
Highlighted in grey = display parameter			

Related topics:

► [Multi-Encoder \(X8\)](#) (📖 325)

7.4.1.2 Z-track resolver as a touch probe signal source

From version 12.00.00 onwards, the Z-track of a connected resolver is also supported as a touch probe signal source.

Short overview of the relevant parameters:

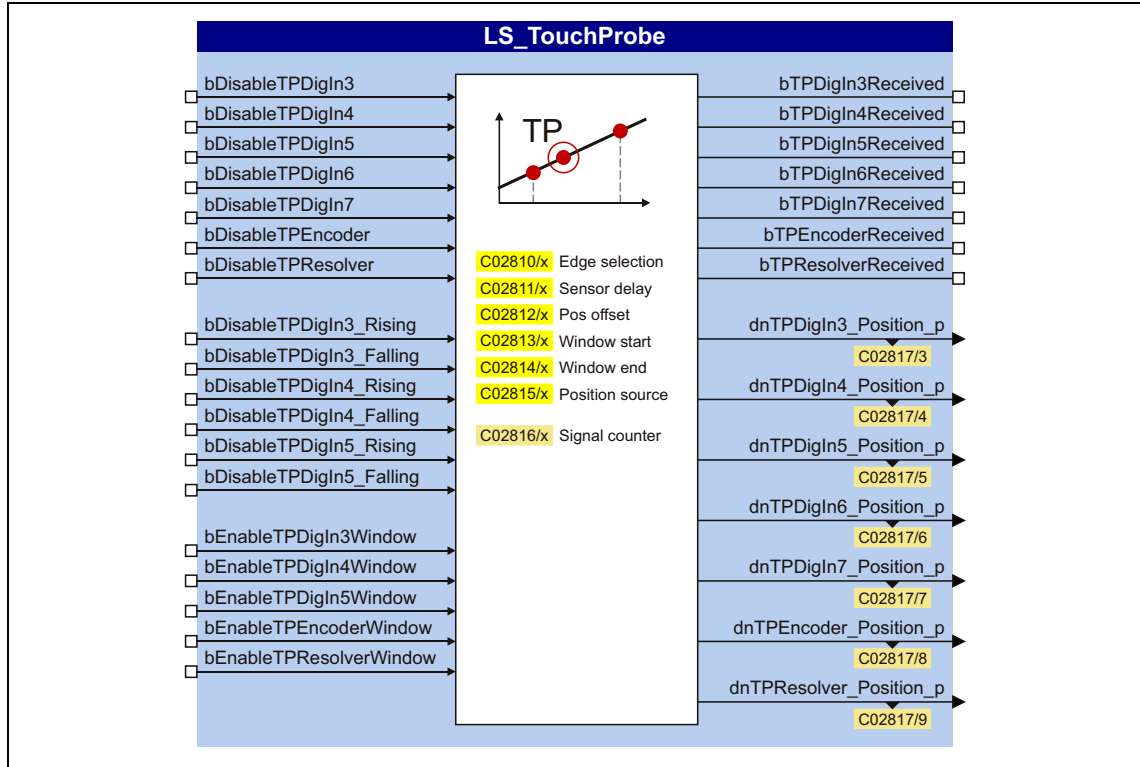
Parameter	Info	Lenze setting	
		Value	Unit
C02810/9	TPResolverZTrack: Edge selection	0: Off	
C02811/9	TPResolverZTrack: Sensor delay	0	µs
C02812/9	TPResolverZTrack: Pos offset	0.0000	units
C02813/5	TPResolverZTrack: Window start	-214748.3647	units
C02814/5	TPResolverZTrack: Window end	214748.3647	units
C02815/9	TPResolverZTrack: Position source	0: Position encoder actual value	
C02816/9	TPResolverZTrack: Signal counter	-	
C02817/9	TPResolverZTrack: TP position	-	units
Highlighted in grey = display parameter			

Related topics:

► [Resolver \(X7\)](#) (📖 319)

7.4.2 Internal interfaces | System block "LS_TouchProbe"

The **LS_TouchProbe** system block provides the internal interfaces for touch probe detection in the function block editor:



Inputs

Input	Data type	Information/possible settings
bDisableTPDigIn3...7	BOOL	DI3 ... DI7: Dynamically deactivate TP function
		TRUE TP function is deactivated.
bDisableTPEncoder	BOOL	Z-track of encoder: Dynamically deactivate TP function
(from version 12.00.00)		TRUE TP function is deactivated.
bDisableTPResolver	BOOL	Z-track of resolver: Dynamically deactivate TP function
(from version 12.00.00)		TRUE TP function is deactivated.
bDisableTPDigIn3...5_Rising	BOOL	DI3 ... DI5: Dynamically deactivate detection of rising edges
		TRUE Detection of rising edges is deactivated.
bDisableTPDigIn3...5_Falling	BOOL	DI3 ... DI5: Dynamically deactivate detection of falling edges
		TRUE Detection of falling edges is deactivated.
bEnableTPDigIn3...5Window	BOOL	DI3 ... DI5: Activate acceptance window
		TRUE Acceptance window function is active: • If the actual position is outside the acceptance window, whose starting position is set in C02813/1...3 and whose end position is set in C02814/1...3 , touch probe is automatically deactivated.
bEnableTPEncoderWindow	BOOL	Z-track of encoder: Activate acceptance window
(from version 12.00.00)		TRUE Acceptance window function is active: • If the actual position is outside the acceptance window, whose starting position is set in C02813/4 and whose end position is set in C02814/4 , touch probe is automatically deactivated.

Input	Data type	Information/possible settings
bEnableTPResolverWindow	BOOL	Z-track of resolver: Activate acceptance window
(from version 12.00.00)		TRUE Acceptance window function is active: <ul style="list-style-type: none"> If the actual position is outside the acceptance window, whose starting position is set in C02813/5 and whose end position is set in C02814/5, touch probe is automatically deactivated.

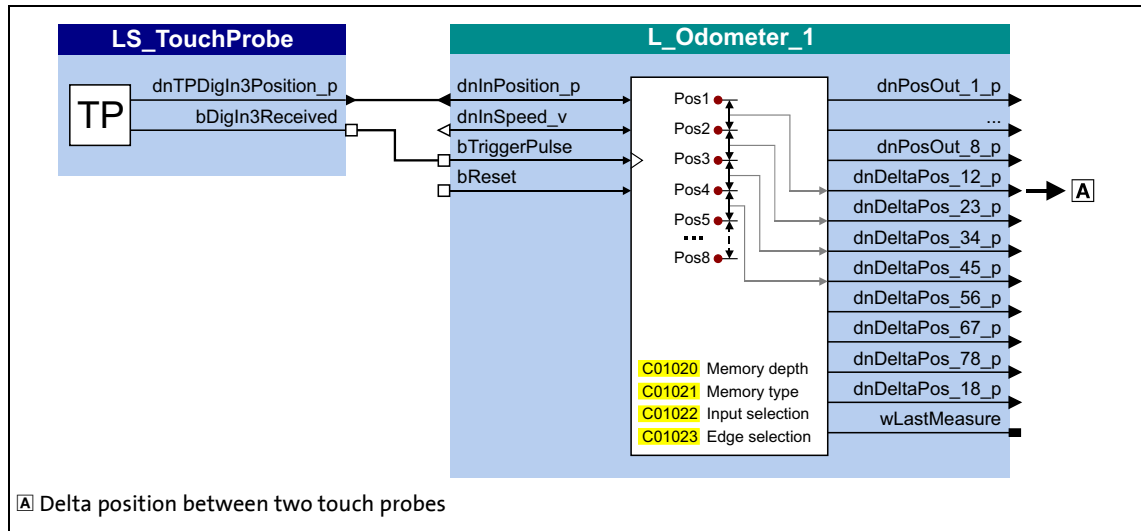
Outputs

Output	Data type	Value/meaning
bTPDigIn3...7Received	BOOL	TRUE DI3 ... DI7: Touch probe received. • The signal is only pending for one task cycle (1 ms).
bTPEncoderReceived	BOOL	TRUE Z-track of encoder: Touch probe received. • The signal is only pending for one task cycle (1 ms).
bTPResolverReceived	BOOL	TRUE Z-track of resolver: Touch probe received. • The signal is only pending for one task cycle (1 ms).
dnTPDigIn3...7_Position_p	DINT	DI3 ... DI7: Position measured by touch probe in [increments]
dnTPEncoder_Position_p	DINT	Z track of encoder: Position measured by touch probe in [increments]
dnTPResolver_Position_p	DINT	Z track of resolver: Position measured by touch probe in [increments]

7.4.2.1 Application example: "Position measurement"

The touch probe function can be combined with the [L_Odometer](#) FB for a position measurement. This FB is able to save position signals to a ring buffer and detect differences between two position signals.

In the wiring below, digital input DI3 is used to connect the touch probe sensor. For the sake of clarity, irrelevant inputs and outputs of the [LS_TouchProbe](#) SB are masked out.



[7-6] Wiring for position measurement

7.5 Configuring exception handling of the output terminals

Exception handling for the analog and digital output terminals in the event of an error can be set via decoupling configuration and decoupling values.

- Bit coded selection is carried out in [C00441](#) for the analog output terminals, defining the events that will trigger decoupling.
- Bit coded selection is carried out in [C00447](#) for the digital output terminals, defining the events that will trigger decoupling.

Bit	Event
Bit 0 <input type="checkbox"/>	SafeTorqueOff
Bit 1 <input type="checkbox"/>	ReadyToSwitchOn
Bit 2 <input type="checkbox"/>	SwitchedOn
Bit 3 <input type="checkbox"/>	Reserved
Bit 4 <input type="checkbox"/>	Trouble
Bit 5 <input type="checkbox"/>	Fault
Bit 6 <input type="checkbox"/>	Reserved
Bit 7 <input type="checkbox"/>	Reserved
Bit 8 <input type="checkbox"/>	Reserved
Bit 9 <input type="checkbox"/>	Fail CAN_Management
Bit 10 <input type="checkbox"/>	Reserved
Bit 11 <input type="checkbox"/>	Reserved
Bit 12 <input type="checkbox"/>	Reserved
Bit 13 <input type="checkbox"/>	Reserved
Bit 14 <input type="checkbox"/>	Reserved
Bit 15 <input type="checkbox"/>	Reserved

Finally, the following parameters define the value/status that the output terminals are to have when they are decoupled:

Parameter	Info	Lenze setting	
		Value	Unit
C00442/1	AOut1_U: Decoupling value	0.00	%
C00442/2	AOut2_U: Decoupling value	0.00	%
C00442/3	AOut1_I: Decoupling value	0.00	%
C00442/4	AOut2_I: Decoupling value	0.00	%
C00448	DigOut decoupling value	Bit coded	

Related topics:

- ▶ [Configuring exception handling of the CAN PDOs](#) (783)

7.6 User-defined terminal assignment

In order to individually adapt the preconfigured assignment of the input/output terminals to your application, you can choose one of the following procedures:

- A. In the »Engineer«:
 - Change the terminal assignment on the **Terminal assignment** tab.
 - Change the signal assignment on the **Application Parameters** tab, on the dialog level *Overview* → *Signal flow*.
 - Change the interconnections in the FB editor (on the I/O level).
- B. In the »Engineer« or with the keypad:
 - Change the parameters for signal configuration in the parameters list.



Note!

If you change the preconfigured assignment of the input/output terminals, the terminal assignment will be a user-defined one. In [C00007](#), control mode "0: Interconnection changed" will be shown.



Tip!

First of all, select a Lenze configuration useful for the purpose at hand by going to [C00005](#) and selecting a technology application that matches your drive task and then going to [C00007](#) and selecting an appropriate control mode. You will then have an application for which there is a signal flow, logical block links and terminal assignment.

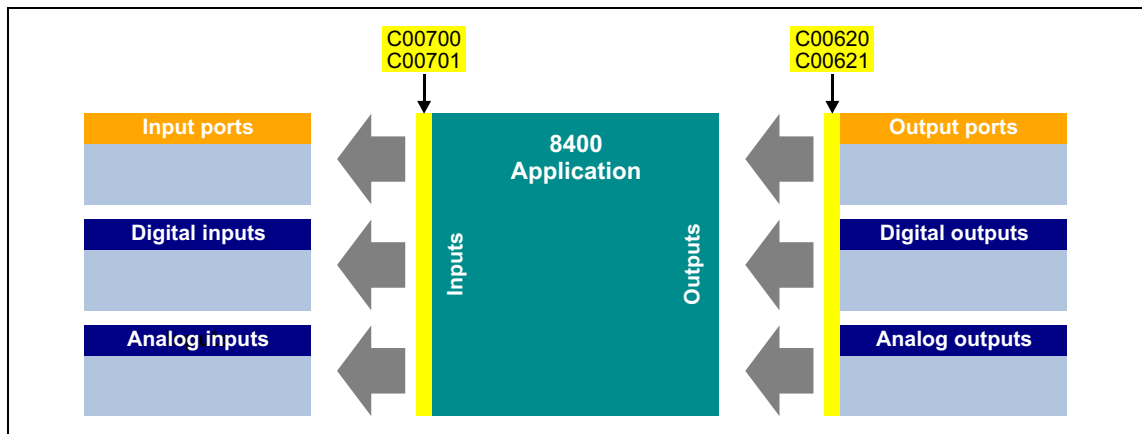
We recommend using the »Engineer« for the implementation of comprehensive user-defined drive solutions.

7.6.1 Source-destination principle

The I/O configuration of the input and output signals is carried out according to the source/destination principle:

- A connection always has a direction and therefore always has a source and a target.
- The inputs signals of the technology application are logically linked to the outputs of system blocks which represent the device input terminals.
- The inputs of system blocks that represent the device output terminals are logically linked to output signals of the technology application.

The following graphic illustrates the source/destination principle:



[7-7] Source-destination principle

Note the following:

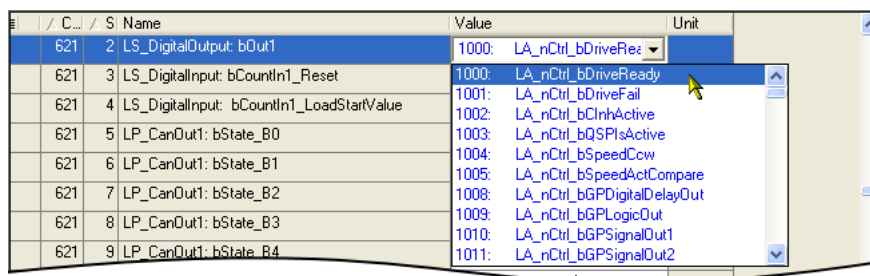
- An equipment input terminal can be logically linked to several inputs of the application block.
- Every input of the application block can only be logically linked to one input signal.
- An output of the application block can be logically linked to several device output terminals.

7.6.2 Changing the terminal assignment with the keypad

You can reconfigure the preconfigured terminal assignment with the keypad (and with the »Engineer«) by means of so-called configuration parameters.

- Each configuration parameter represents a signal input of a system block or application block.
- Each configuration parameter contains a selection list with output signals of the same type of data.
- Logical linking is thus carried out by selecting the output signal for the corresponding signal input.

In the following example, digital output 1 (**LS_DigitalOutput.bOut1** input) is logically linked to the status signal "Drive ready" (**LA_nCtrl_bDriveReady** output signal):



Configuration parameters for the analog and digital output terminals

The preconfigured assignment of the analog and digital output terminals can be altered by means of the subcodes of [C00620](#) and [C00621](#):

Parameter	Info	Lenze setting
Analog outputs - terminal assignment		
C00620/1	LS_AnalogOutput: nOut1_a (V)	1003: LA_nCtrl_nMotorSpeedAct_a
C00620/39	LS_AnalogOutput: nOut1_a (I)	0: Not connected
C00620/38	LS_AnalogOutput: nOut2_a (V)	0: Not connected
C00620/40	LS_AnalogOutput: nOut2_a (I)	0: Not connected
Digital outputs - terminal assignment		
C00621/1	LS_DigitalOutput:bRelay	1001: LA_nCtrl_bDriveFail
C00621/2	LS_DigitalOutput:bOut1	1000: LA_nCtrl_bDriveReady
C00621/99	LS_DigitalOutput: bOut2	0: Not connected
C00621/100	LS_DigitalOutput: bOut3	0: Not connected
C00621/101	LS_DigitalOutput: bOut HighCurrent	0: Not connected

Other subcodes (not shown here) allow the configuration of input signals of different system blocks and port blocks.

Configuration parameters for the inputs of the technology application

The following parameters can be used to change the preconfigured assignment of the application inputs:

Parameter	Info
TA "Actuating drive speed": Configuration parameters (454)	
C00700/x	Analog connection list
C00701/x	Digital connection list
TA "Table positioning": Configuration parameters (516)	
C00710/x	Analog connection list
C00711/x	Digital connection list
TA "Switch-off positioning": Configuration parameters (543)	
C00760/x	Analog connection list
C00761/x	Digital connection list

Example

Task: Starting from the preset technology application "Actuating drive speed" and the "Terminals 0" control mode, the DI2 digital input is to be used for choosing an alternative acceleration/deceleration time for the main setpoint instead of for choosing the fixed setpoint 2/3. To do this, the DI2 digital input is not to be linked to the *bJogSpeed2* input but to the *bJogRamp1* input of the application module.

Procedure:

1. Use the keypad to go to the menu level **Applications → Actuating drive speed (conf.)**. This menu level contains all the configuration parameters of the "Actuating drive speed" technology application". ▶ [Configuration parameters](#) (454)
2. Navigate to the configuration parameter LA_NCtrl: bJogSpeed2 ([C00701/10](#)) which represents the logical signal link of the application input *bJogSpeed2*.
3. Change the setting of [C00701/10](#):
Change selection "16001: DigIn_bln2" in selection "0: Not interconnected".
4. Navigate to the configuration parameter LA_NCtrl: bJogRamp1 ([C00701/13](#)) which represents the logical signal link of the application input *bJogRamp1*.
5. Change the setting of [C00701/13](#):
Change selection "0: Not interconnected" in selection "16001: DigIn_bln2".



Tip!

The example shows that, for each input of the application block, the associated configuration parameter ([C00700/x](#) or [C00701/x](#)) is only allowed to contain one source that you enter.

7.6.3 Changing the terminal assignment with the »Engineer«

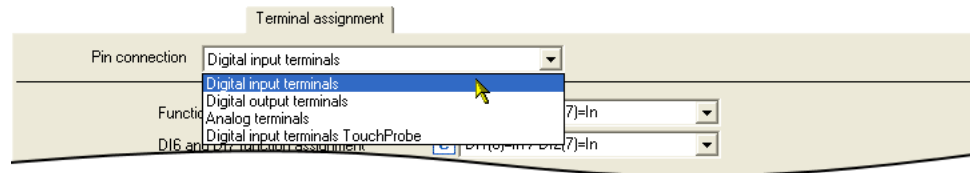
Whereas the configuration parameters referred to have to be parameterised with the keypad, implementation in the »Engineer« is much easier due to the availability of the corresponding dialogs. The following task illustrates the respective procedure.

Task: Starting from the preset technology application "Actuating drive speed" and the "Terminals 0" control mode, the DI2 digital input is to be used for choosing an alternative acceleration/deceleration time for the main setpoint instead of for choosing the fixed setpoint 2/3. To do this, the DI2 digital input is not to be linked to the *bJogSpeed2* input but to the *bJogRamp1* input of the application module.

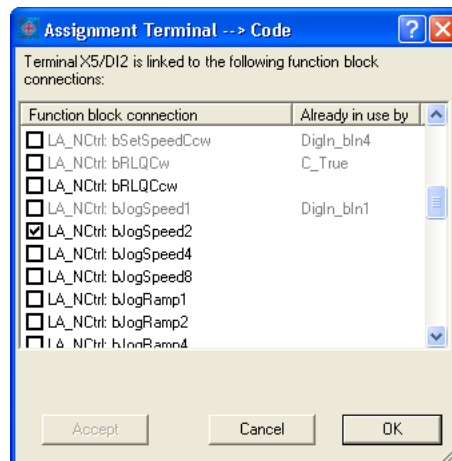
Possibility 1: Change terminal assignment by means of the Terminal Assignment tab

Procedure:

1. Go to the **Terminal Assignment** tab and select "Digital input terminals" in the **Control connections** list field:



2. Click on the **...** button for the DI2 terminal in order to open the dialog box *Assignment Terminal --> Function block*.
 - In the list field, all block inputs that are currently logically linked to digital input DI2 are marked with a checkmark:



3. Remove checkmark for the connection **LA_NCtrl: bJogSpeed2** in order to cancel the existing logical link.
4. Set checkmark for connection **LA_NCtrl: bJogRamp1** in order to logically link this application input to digital input DI2.

Possibility 2: Change terminal assignment by means of the signal flow shown

Procedure:

1. Go to the **Application parameters** tab.
2. Go to the **Application Parameters** tab and click on the **Signal flow** button in order to change to the dialog level *Overview → Signal flow*.
3. On the dialog level *Overview → Signal flow*, click on the **Digital control signals** button in order to open the *Digital control signals* dialog box:

Section	Signal	Selected Option
DCTRL	bClnh	Not interconnected
	bFailReset	DigIn_Clnh
MCTRL	bSetQuickstop	Not interconnected
	bSetDCBrake	DigIn_bln3
MCK	bMBRKRelease	Not interconnected
	bMANJogPos	Not interconnected
	bMANJogNeg	Not interconnected
Motor potentiometer	bMPOTUp	Not interconnected
	bMPOTDown	Not interconnected
	bMPOTInAct	Not interconnected
	bMPotEnable	Not interconnected
NSET	bSetSpeedCw	DigIn_bln4
	bJogSpeed1	DigIn_bln1
	bJogSpeed2	DigIn_bln2
	bJogSpeed4	Not interconnected
	bJogSpeed8	Not interconnected
	bJogRamp1	Not interconnected
	bJogRamp2	Not interconnected
	bJogRamp4	Not interconnected
PID/PCTRL	bPIDEnableInfluenceRamp	Not interconnected

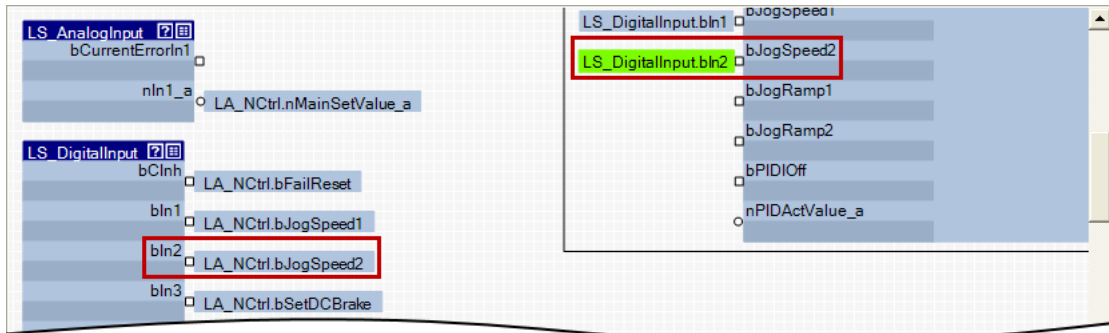
Back

4. In the **bJogSpeed2** list field, set the selection "0: Not interconnected".
5. In the **bJogRamp1** list field, set the selection "16001: DigIn_bln2".
6. Click on the **Back** button in order to close the dialog box again.

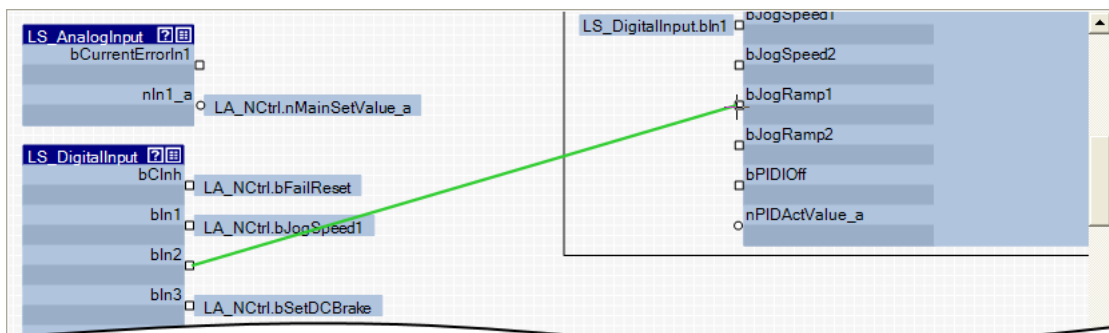
Possibility 3: Change terminal assignment with the FB editor

Procedure:

1. Go to the **FB Editor** tab.
2. Delete the existing interconnection from **LS_DigitalInput.bIn2** to **LA_NCtrl.bJogSpeed2**:



3. Establish a new interconnection from **LS_DigitalInput.bIn2** to **LA_NCtrl.bJogRamp1**:



Tip!

You can find detailed information on how to use the FB editor of the »Engineer« in the main chapter entitled "[Working with the FB Editor](#)". (📖 1329)

8 Technology applications

This chapter describes the handling and the functional range of the technology applications available for the 8400 TopLine controller.



Technology application "Actuating drive speed"

This technology application preset in [C00005](#) serves to solve speed-controlled drive tasks, e.g. conveyor drives (interconnected), extruders, test benches, vibrators, travelling drives, presses, machine tools, dosing systems.

▶ [TA "Actuating drive speed"](#) (430)



technology application "Actuating drive speed (AC Drive Profile)"

This technology application available from version 13.00.00 provides a speed and torque control by means of "AC Drive Profile". The fieldbuses EtherNet/IP™ and system bus (CANopen) are supported.

▶ [TA "actuating drive speed \(AC Drive Profile\)"](#) (457)



Technology application "Table positioning"

This technology application serves to solve position-controlled drive tasks which are normally controlled by a higher-level control via a fieldbus, e.g. transport facilities, rotary tables, storage and retrieval units, feed drives, metering units, hoists.

Note: This TA requires an external sequence control!

From version 12.00.00, the FB [L_Sequencer 1](#) can also be used as internal sequence control. This FB processes a positioning program based on a sequence table.

▶ [TA "Table positioning"](#) (490)



"Switch-off positioning" technology application

This technology application is used to solve speed-controlled drive tasks which require a pre-switch off or stopping at certain positions, e.g. roller conveyors and conveying belts. The pre-switch off is implemented by connecting switch-off sensors.

▶ [TA "Switch-off positioning"](#) (519)



Note!

Please note that the "StateLine", "HighLine" and "TopLine" device types differ with regard to the number, functional range, and flexibility of the technology applications offered.

Related topics:

▶ [Integrated technology applications](#) (30)

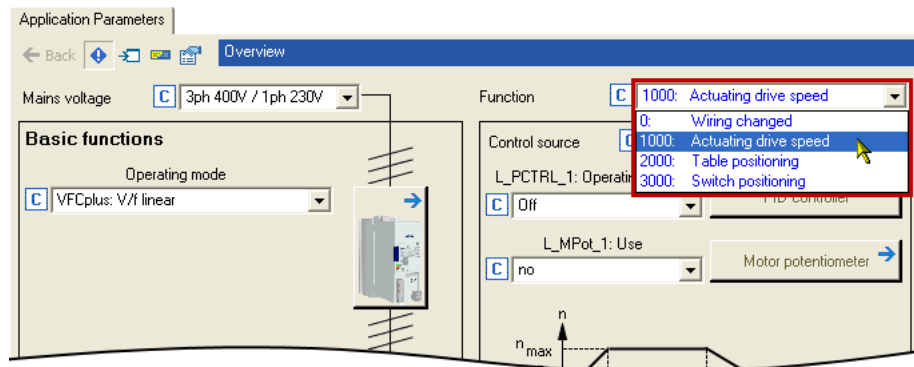
▶ [Commissioning](#) (52)

8.1

Selection of the technology application and the control mode

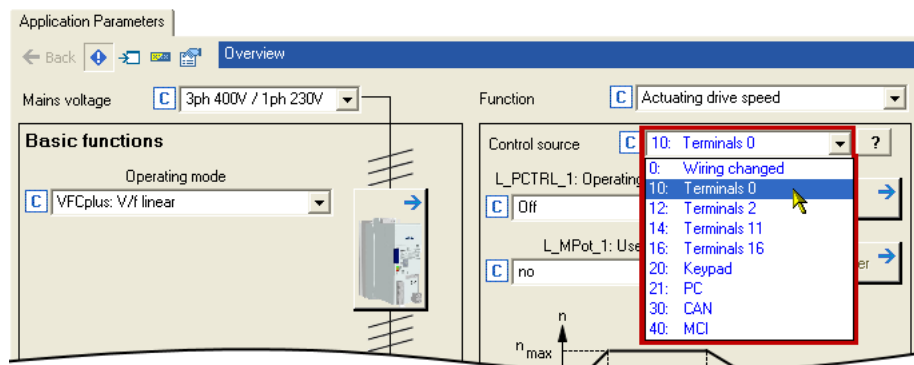
The technology application to be used is selected in [C00005](#).

- You can select the technology application in the »Engineer« on the **Application parameter** tab via the **Application** list field:



Different control modes can be selected for every application in [C00007](#). By selecting the control mode you set the way by which the technology application should be controlled, e.g. via terminals or via a fieldbus. The interconnection of the input/output terminals and ports shown in the FB editor in the I/O level changes accordingly.

- You can select the control mode in the »Engineer« on the **Application parameter** tab via the **Control mode** list field:

**Tip!**

You can infer the pre-configured assignment of the input/output terminals and ports for each control mode from the description of the corresponding technology application:

TA "Actuating drive speed": [Terminal assignment of the control modes](#) (441)

TA "Table positioning": [Terminal assignment of the control modes](#) (504)

TA "Switch-off positioning": [Terminal assignment of the control modes](#) (530)

Detailed information on the individual configuration of the input/output terminals can be found in the description of the I/O terminals in the subchapter "[User-defined terminal assignment](#)". (421)

8.2

TA "Actuating drive speed"

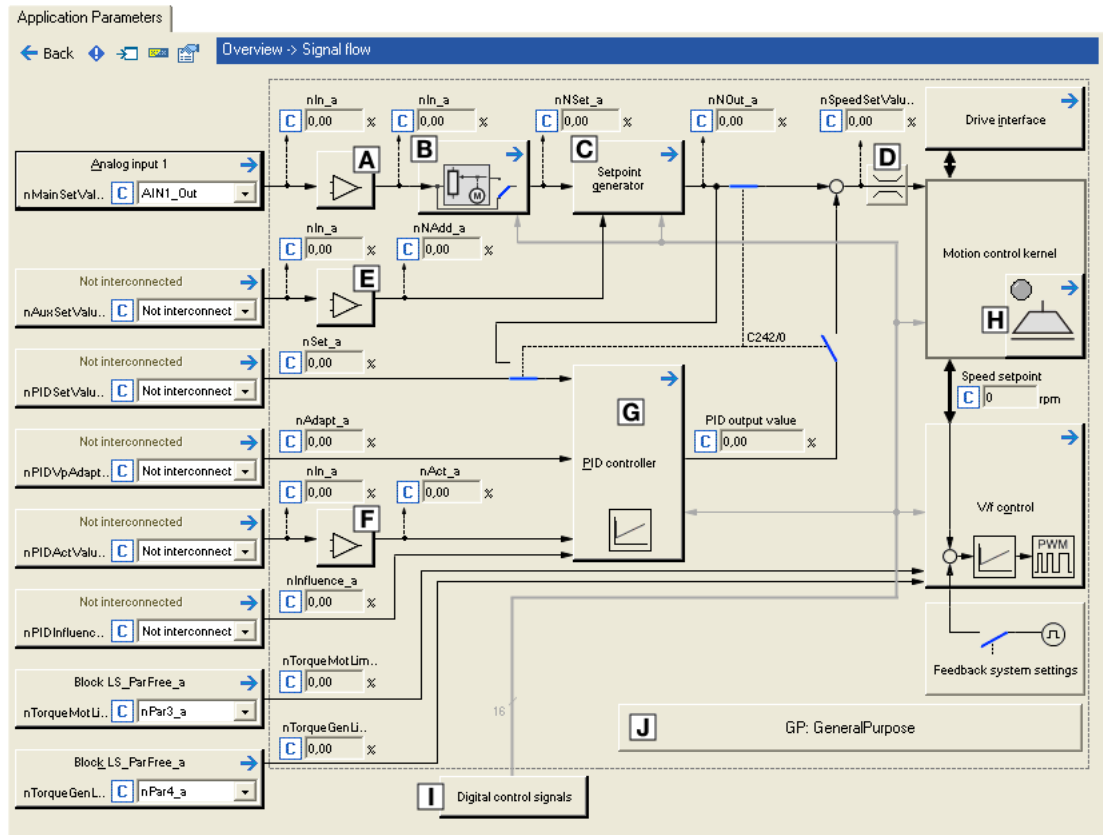
Features

- Pre-configured control modes for terminals and bus control (with predefined process data connection to the fieldbus)
- Free configuration of input and output signals
- Offset, gain, and negation of main setpoint, additional setpoint, actual process controller value
- Up to 15 fixed setpoints for speed and ramp time
- Adjustable setpoint ramp times
- Freely selectable, variable ramp shape
- Automatic holding brake control
- Quick stop (QSP) with adjustable ramp time
- Motor potentiometer function
- Process controller
- Load monitoring (*in preparation*)
- Integrated, freely available "GeneralPurpose" functions:
Analog switch, arithmetic, multiplication/division, binary delay element, binary logic, analog comparison, D-flipflop
- Interface to the safety module (optional)
- Integration of encoder feedback

Related topics:

- ▶ [Commissioning of the "Actuating drive speed" technology application](#) (📖 59)

8.2.1 Basic signal flow



[8-1] Signal flow of the technology application "Actuating drive speed"

- [A] Main speed setpoint offset and gain ([L_OffsetGainP_1](#))
- [B] Motor potentiometer function ([L_MPot_1](#))
- [C] Setpoint generator ([L_NSet_1](#))
- [D] Speed setpoint input limitation
- [E] Additional speed setpoint offset and gain ([L_OffsetGainP_2](#))
- [F] Actual speed/sensor value offset and gain ([L_OffsetGainP_3](#))
- [G] Process controller ([L_PCTRL_1](#))
- [H] [Holding brake control](#)
- [I] Terminal assignment & display of digital control signals
- [J] Integrated disposable "[GeneralPurpose](#)" functions: Analog switch, arithmetic, multiplication/division, binary delay element, binary logic, analog comparison, D-flipflop

Selection of the main speed setpoint

The main speed setpoint is selected in the Lenze setting via the analog input 1.

- Offset and gain of this input signal can be set in [C00696](#) and [C00670](#) for a simple signal adjustment of a setpoint encoder.
- Scaling: $16384 \equiv 100\%$ reference speed ([C00011](#))
- The main setpoint is transformed to a speed setpoint in the setpoint encoder via a ramp function generator with linear or S-shaped ramps.
- Upstream to the ramp function generator, a blocking speed masking function and a setpoint MinMax limitation are effective.
- For a detailed functional description see the [L_NSet](#) FB.

Motor potentiometer function

Alternatively, the main speed setpoint can be generated via a motor potentiometer function.

- In the Lenze setting, the motor potentiometer function is deactivated.
- Activation is possible via [C00806](#) or via the *bMPotEnable* input.
- The behaviour of the motor potentiometer during switch-on of the drive system can be selected in [C00805](#).
- For a detailed functional description see the [L_MPot](#) FB.

Optional selection of an additional speed setpoint

You can optionally select an additional speed setpoint (e.g. as a correcting signal).

- The additional speed setpoint can be linked arithmetically with the main speed setpoint behind the ramp function generator.
- You must set the setpoint arithmetic to "1: NOut = NSet + NAdd" in [C00190](#) in order to activate the additional speed setpoint.
- Offset and gain of this input signal can be set in [C00697](#) and [C00671](#) for a simple signal adjustment of a setpoint encoder.
- Scaling: $16384 \equiv 100\%$ reference speed ([C00011](#))
- The acceleration and deceleration time for the additional speed setpoint can be set in [C00220](#) and [C00221](#).
- For a detailed functional description see the [L_NSet](#) FB.



Tip!

In the case of a grinding machine, the additional speed setpoint can, for instance, be used to control a constant circumferential speed while the grinding disk diameter is reduced.

8.2.2 Internal interfaces | application block "LA_NCtrl"




**Note!**

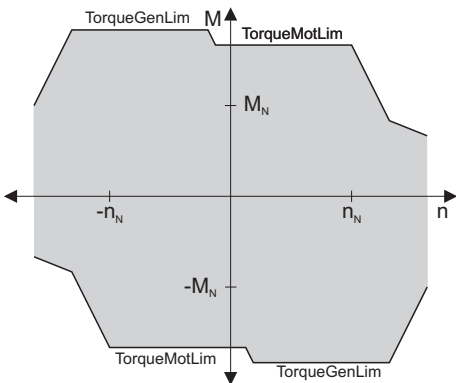
The connectors grayed out in the following table are hidden in the function block editor in the Lenze setting.

- These connections can be shown via the **Connector visibilities** command in the *Context menu* of the application block.

Inputs

Identifier	Data type	Information/possible settings
wCANDriveControl	WORD	Control word via system bus (CAN) for device control <ul style="list-style-type: none"> • See the "wCANControl/wMCIControl control words" subchapter of the chapter on device control for a detailed description of the individual control bits.
wMCIDriveControl	WORD	Control word via communication module (e.g. PROFIBUS) for device control <ul style="list-style-type: none"> • See the "wCANControl/wMCIControl control words" subchapter of the chapter on device control for a detailed description of the individual control bits.
wSMControl	WORD	Interface to the optional safety system. <ul style="list-style-type: none"> • Setting control bit 0 ("SafeStop1") in this control word causes e.g. the automatic deceleration of the drive to standstill within this application (in the Motion Control Kernel). • See the "Interface to safety system" subchapter of the chapter on basic drive functions for a detailed description of the control bits.
bCInh	BOOL	Enable/Inhibit controller
		<div>FALSE</div> <div>Enable controller: The controller switches to the "OperationEnabled" device status if no other source of a controller inhibit is active. <ul style="list-style-type: none"> • C00158 provides a bit coded representation of all active sources/triggers of a controller inhibit. </div>
		<div>TRUE</div> <div>Inhibit controller (controller inhibit): The controller switches to the "SwitchedOn" device status.</div>
bFailReset	BOOL	Reset error message In the Lenze setting this input is connected to the digital input controller enable so that a possibly existing error message is reset together with the controller enable (if the cause for the fault is eliminated).
		<div>TRUE</div> <div>The current fault is reset, if the cause for the fault is eliminated. <ul style="list-style-type: none"> • If the fault still exists, the error status remains unchanged. </div>
bSetQuickstop	BOOL	Enable quick stop (QSP) <ul style="list-style-type: none"> • Also see device command "Activate/deactivate quick stop".
		<div>TRUE</div> <div>Activate quick stop <ul style="list-style-type: none"> • Motor control is decoupled from the setpoint selection and, within the deceleration time parameterised in C00105, the motor is brought to a standstill ($n_{act} = 0$). • The motor is kept at a standstill during closed-loop operation. • A pulse inhibit is set if the auto-DCB function has been activated via C00019. </div>
		<div>FALSE</div> <div>Deactivate quick stop <ul style="list-style-type: none"> • The quick stop is deactivated if no other source for the quick stop is active. • C00159 displays a bit code of active sources/causes for the quick stop. </div>

Identifier	Data type	Information/possible settings
bSetDCBrake	BOOL	Manual DC-injection braking (DCB) <ul style="list-style-type: none"> Detailed information on DC-injection braking is provided in the motor control chapter, subchapter "DC-injection braking".
		 Note! Holding braking is not possible when this braking mode is used! Use the basic " Holding brake control " function for controlling the holding brake with a low rate of wear.
		FALSE Deactivate DC-injection braking.
		TRUE Activate DC-injection braking, i.e. the drive is brought to a standstill by means of DC-injection braking. <ul style="list-style-type: none"> The braking effect stops when the rotor is at standstill. After the hold time (C00107) has expired, the controller sets the pulse inhibit.
bRFG_Stop	BOOL	Ramp function generator: Maintain the current value of the main setpoint integrator <ul style="list-style-type: none"> The speed, for instance, of a running ramp process is immediately kept constant when <i>bRFG_Stop</i> is activated. At the same time, the acceleration/deceleration jumps to the value "0". For a detailed functional description see the L_NSet FB.
		TRUE The current value of the main setpoint integrator is held.
bRFG_0	BOOL	Ramp function generator: Lead the main setpoint integrator to "0" within the current Ti times <ul style="list-style-type: none"> For a detailed functional description see the L_NSet FB.
		TRUE The current value of the main setpoint integrator is led to "0" within the Ti time set.
nVoltageAdd_a	INT	Additive voltage impression <ul style="list-style-type: none"> An additional setpoint for the motor voltage can be specified via this process input. If there are, for instance, different loads at the motor output end, it is possible to apply a voltage boost at the starting time. If the value is negative, the voltage is reduced. Scaling: 16384 \equiv 1000 V
		 Stop! Values selected too high may cause the motor to heat up due to the resulting current!
nBoost_a	INT	Additional setpoint for the motor voltage at speed = 0 <ul style="list-style-type: none"> The entire voltage-frequency characteristic is provided with an offset. Scaling: 16384 \equiv 1000 V
		 Stop! Values selected too high may cause the motor to heat up due to the resulting current!
nPWMAngleOffset	INT	Additional offset for the electrical angle of rotation <ul style="list-style-type: none"> If a torque is connected, e.g. dynamic acceleration processes can be generated. Scaling: $\pm 32767 \equiv \pm 180^\circ$ angle of rotation

Identifier	Data type	Information/possible settings				
nTorqueMotLim_a nTorqueGenLim_a	INT	<p>Torque limitation in motor mode and in generator mode</p> <ul style="list-style-type: none">• These input signals are directly transferred to the motor control to limit the controller's maximum torque in motor and generator mode.• The drive cannot output a higher torque in motor/generator mode than set here.• The applied values (any polarity) are internally interpreted as absolute values.• If V/f characteristic control (VFCplus) is selected, limitation is <u>indirectly</u> performed via a so-called I_{\max} controller.• If sensorless vector control (SLVC) or servo control (SC) is selected, limitation has a <u>direct</u> effect on the torque-producing current component.• Scaling: $16384 \equiv 100 \% M_{\max}$ (C00057) <p>Torque limits in motor and generator mode:</p> 				
bSetSpeedCcw	BOOL	<p>Change of direction of rotation</p> <ul style="list-style-type: none">• For instance if a motor or gearbox is fixed laterally reversed to a machine part, but the setpoint selection should still be executed for the positive direction of rotation. <table><tr><td>FALSE</td><td>Clockwise rotation (Cw)</td></tr><tr><td>TRUE</td><td>Direction of rotation to the left (Ccw)</td></tr></table>	FALSE	Clockwise rotation (Cw)	TRUE	Direction of rotation to the left (Ccw)
FALSE	Clockwise rotation (Cw)					
TRUE	Direction of rotation to the left (Ccw)					
bRLQCw	BOOL	<p>Activate clockwise rotation (fail-safe)</p> <ul style="list-style-type: none">• For a detailed functional description see the L_RLO FB. <table><tr><td>FALSE</td><td>Quick stop</td></tr><tr><td>TRUE</td><td>CW rotation</td></tr></table>	FALSE	Quick stop	TRUE	CW rotation
FALSE	Quick stop					
TRUE	CW rotation					
bRLQCcw	BOOL	<p>Activate counter-clockwise rotation (fail-safe)</p> <ul style="list-style-type: none">• For a detailed functional description see the L_RLO FB. <table><tr><td>FALSE</td><td>Quick stop</td></tr><tr><td>TRUE</td><td>Counter-clockwise rotation</td></tr></table>	FALSE	Quick stop	TRUE	Counter-clockwise rotation
FALSE	Quick stop					
TRUE	Counter-clockwise rotation					
nMainSetValue_a	INT	<p>Main speed setpoint</p> <ul style="list-style-type: none">• Offset and gain of this input signal can be set in C00696 and C00670 for a simple signal adjustment of a setpoint encoder.• Scaling: $16384 \equiv 100 \% \text{ reference speed}$ (C00011)• The main setpoint is transformed to a speed setpoint in the setpoint encoder via a ramp function generator with linear or S-shaped ramps.• Upstream to the ramp function generator, a blocking speed masking function and a setpoint MinMax limitation are effective.• For a detailed functional description see the L_NSet FB.				

Identifier	Data type	Information/possible settings
nAuxSetValue_a	INT	<p>Additional speed setpoint</p> <ul style="list-style-type: none">• The additional speed setpoint can be linked arithmetically with the main speed setpoint behind the ramp function generator.• You must set the setpoint arithmetic to "1: NOut = NSet + NAdd" in C00190 in order to activate the additional speed setpoint.• Offset and gain of this input signal can be set in C00697 and C00671 for a simple signal adjustment of a setpoint encoder.• Scaling: $16384 \equiv 100\%$ reference speed (C00011)• The acceleration and deceleration time for the additional speed setpoint can be set in C00220 and C00221.• For a detailed functional description see the L_NSet FB.
bJogSpeed1 bJogSpeed2	BOOL	<p>Selection inputs for fixed changeover setpoints (JOG setpoints) for the main setpoint</p> <ul style="list-style-type: none">• A fixed setpoint for the setpoint generator can be activated instead of the main setpoint via these selection inputs.• The four selection inputs are binary coded, therefore 15 fixed setpoints can be selected.• In the case of binary coded selection "0" (all inputs = FALSE or not assigned), main setpoint <i>nMainSetValue_a</i> is active.• The selection of the fixed setpoints is carried out in C00039/1...15 in [%] based on the reference speed (C00011).• For a detailed functional description see the L_NSet FB.
bJogSpeed4 bJogSpeed8	BOOL	
bJogRamp1 bJogRamp2	BOOL	<p>Selection inputs for alternative acceleration/deceleration times for the main setpoint</p> <ul style="list-style-type: none">• The four selection inputs are binary coded, therefore 15 alternative acceleration/deceleration times can be selected.• For main setpoint <i>nMainSetValue_a</i>, the set acceleration time (C00012) and deceleration time (C00013) are active in the case of the binary coded selection "0" (all inputs = FALSE or not assigned).• Alternative acceleration times are selected in C00101/1...15.• The selection of the alternative deceleration times is carried out in C00103/1...15.• For a detailed functional description see the L_NSet FB.
bJogRamp4 bJogRamp8	BOOL	
<p>Motor potentiometer</p> <p>Alternatively to the input signal <i>nMainSetValue_a</i>, the main setpoint can also be generated by a motor potentiometer function.</p> <ul style="list-style-type: none">• In the Lenze setting, the motor potentiometer function is deactivated.• Activation is possible via C00806 or via the <i>bMPotEnable</i> input.• The behaviour of the motor potentiometer during switch-on of the drive system can be selected in C00805.• For a detailed functional description see the L_MPot FB.		
bMPotEnable	BOOL	<p>Activating the motor potentiometer function</p> <ul style="list-style-type: none">• This input and C00806 are OR'd.
	TRUE	The motor potentiometer function is active; the speed setpoint can be changed via the <i>bMPotUp</i> and <i>bMPotDown</i> control inputs.
bMPotUp	BOOL	<p>Increasing the speed setpoint</p>
	TRUE	Approach the upper speed limit value set in C00800 with the acceleration time set in C00802 .
bMPotInAct	BOOL	<p>Activating the inactive function</p>
	TRUE	<p>The speed setpoint behaves according to the inactive function set in C00804.</p> <ul style="list-style-type: none">• In the Lenze setting, the speed setpoint is maintained.
bMPotDown	BOOL	<p>Decreasing the speed setpoint</p>
	TRUE	Approach the lower speed limit value set In C00801 with the deceleration time set in C00803 .

Identifier	Data type	Information/possible settings
Process controller <ul style="list-style-type: none"> In the Lenze setting, the process controller is deactivated. The activation is executed by selecting the operating mode in C00242. For a detailed functional description see FB L_PCTRL. 		
bPIDEnableInfluenceRamp	BOOL	Activate ramp for influencing factor
		FALSE Influencing factor of the PID controller is ramped down to "0".
		TRUE Influencing factor of the PID controller is ramped up to the value <i>nPIDInfluence_a</i> .
bPIDIOff	BOOL	Switch off the I-component of the process controller <ul style="list-style-type: none"> In conjunction with the operating mode set in C00242 (Lenze setting: "Off").
		TRUE I-component of the process controller is switched off.
nPIDVpAdapt_a	INT	Adaptation of gain Vp set in C00222 in percent <ul style="list-style-type: none"> Scaling: 16384 \equiv 100 % Internal limitation to \pm 199.99 % Changes can be done online.
nPIDSetValue_a	INT	Sensor and process setpoint for operating modes 2, 4 and 5 <ul style="list-style-type: none"> Scaling: 16384 \equiv 100 % Internal limitation to \pm 199.99 %
nPIDActValue_a	INT	Speed or actual sensor value (actual process value) <ul style="list-style-type: none"> Offset and gain for this input signal can be set in C00698 and C00672. Scaling: 16384 \equiv 100 % Internal limitation to \pm 199.99 %
nPIDInfluence_a	INT	Limitation of the influencing factor in percent <ul style="list-style-type: none"> The influence factor of the PID controller can be limited to a certain value (- 199.99% ... + 199.99%) via <i>nPIDInfluence_a</i>. Scaling: 16384 \equiv 100 % Internal limitation to \pm 199.99 %
MCK basic functions		
bMBrakeRelease	BOOL	Holding brake control : Release/apply brake <ul style="list-style-type: none"> In conjunction with the operating mode selected in C02580 (Lenze setting: "Brake control off").
		FALSE Apply brake. <ul style="list-style-type: none"> During automatic operation, the internal brake logic controls the brake.
		TRUE Release brake manually (forced release). <ul style="list-style-type: none"> Note! The brake can also be released if the controller is inhibited! During automatic operation, the internal brake logic is deactivated and the brake is released (supervisor operation). If a controller inhibit has been set by the brake control, it will be deactivated. In semi-automatic operation, the brake is released including feedforward control.

Identifier	Data type	Information/possible settings
GP: GeneralPurpose The following inputs are interconnected with logic/arithmetic functions on application level for free usage. ▶ "GeneralPurpose" functions		
bGPFree1 ... bGPFree2 (from version 12.00.00)	BOOL	Free inputs for digital signals <ul style="list-style-type: none"> Digital signals can be transferred from the I/O level to the application level via these inputs.
nGPAAnalogSwitchIn1_a nGPAAnalogSwitchIn2_a	INT	Analog switch : Input signals <ul style="list-style-type: none"> The input signal selected via the selection input <i>bGPAAnalogSwitchSet</i> is output at output <i>nGPAAnalogSwitchOut_a</i>.
bGPAAnalogSwitchSet	BOOL	Analog switch : Selection input
		FALSE <i>nGPAAnalogSwitchOut_a</i> = <i>nGPAAnalogSwitchIn1_a</i>
		TRUE <i>nGPAAnalogSwitchOut_a</i> = <i>nGPAAnalogSwitchIn2_a</i>
nGPArithmetikIn1_a nGPArithmetikIn2_a	INT	Arithmetic : Input signals <ul style="list-style-type: none"> The arithmetic function is selected in C00338. The result is output at output <i>nGPArithmetikOut_a</i>.
nGPMulDivIn_a	INT	Multiplication/Division : Input signal <ul style="list-style-type: none"> The factor for the multiplication can be set in C00699/1 (numerator) and C00699/2 (denominator). The result is output at output <i>nGPMulDivOut_a</i>.
bGPDigitalDelayIn	BOOL	Binary delay element : Input signal <ul style="list-style-type: none"> The on-delay can be set in C00720/1. The off-delay can be set in C00720/2. The time-delayed input signal is output at output <i>bGPDigitalDelayOut</i>.
bGPLogicIn1 bGPLogicIn2 bGPLogicIn3	BOOL	Binary logic : Input signals <ul style="list-style-type: none"> The logic operation is selected in C00820. The result is output at output <i>bGPLogicOut</i>.
nGPCompareIn1_a nGPCompareIn2_a	INT	Analog comparison : Input signals <ul style="list-style-type: none"> The comparison operation is selected in C00680. Hysteresis and window size can be set in C00680 and C00682. If the comparison statement is true, the output <i>bGPCompareOut</i> will be set to TRUE.
bGPDFlipFlop_InD bGPDFlipFlop_InClk bGPDFlipFlop_InClr	BOOL	D-FlipFlop : Input signals <ul style="list-style-type: none"> Data, clock and reset input
Free inputs The following inputs can freely be interconnected on the application level. The signals can be transferred from the I/O level to the application level via these inputs.		
bFreeIn1 ... bFreeIn8	BOOL	Free inputs for digital signals
wFreeIn1 ... wFreeIn4	WORD	Free inputs for 16-bit signals

Outputs

Identifier	Data type	Value/meaning	
wDriveControlStatus	WORD	Status word of the controller <ul style="list-style-type: none"> The status word contains information on the current status of the drive controller. See the "wDeviceStatusWord status word" subchapter of the chapter on device control for a detailed description of the bit assignment. 	
wStateDetermFailNoLow	WORD	Display of the status determining error (LOW word)	
wStateDetermFailNoHigh	WORD	Display of the status determining error (HIGH word)	
bDriveFail	BOOL	TRUE	Drive controller in error status. <ul style="list-style-type: none"> "Fault" device status is active.
bDriveReady	BOOL	TRUE	Controller is ready for operation. <ul style="list-style-type: none"> "SwitchedOn" device status is active. The drive is in this device status if the DC bus voltage is applied and the controller is still inhibited by the user (controller inhibit).
bCInhActive	BOOL	TRUE	Controller inhibit is active.
bQSPisActive	BOOL	TRUE	Quick stop is active.
bSpeedCcw	BOOL	Current direction of rotation	
		FALSE	Clockwise rotation (Cw)
		TRUE	Direction of rotation to the left (Ccw)
bSpeedActCompare	BOOL	Result of the speed comparison (detection of speed=0)	
		TRUE	During open-loop operation: Speed setpoint < Comparison value (C00024)
			During closed-loop operation: Actual speed value < Comparison value (C00024)
bOverLoadActive	BOOL	In preparation (output is not interconnected on the application level)	
bUnderLoadActive	BOOL	In preparation (output is not interconnected on the application level)	
blmaxActive	BOOL	"Current setpoint inside the limitation" status signal	
		TRUE	The current setpoint is internally limited (the drive controller operates at the maximum current limit).
bSpeedSetReached	BOOL	Status signal "setpoint = 0"	
		TRUE	Speed setpoint from the ramp function generator = 0
bSpeedActEqSet	BOOL	TRUE	Actual speed value = speed setpoint
nMotorCurrent_a	INT	Current stator current/effective motor current <ul style="list-style-type: none"> Scaling: $16384 \equiv 100\% I_{\max_mot}$ (C00022) 	
nMotorSpeedSet_a	INT	Speed setpoint <ul style="list-style-type: none"> Scaling: $16384 \equiv 100\%$ reference speed (C00011) 	
nMotorSpeedAct_a	INT	Actual speed value <ul style="list-style-type: none"> Scaling: $16384 \equiv 100\%$ reference speed (C00011) 	
nMotorTorqueAct_a	INT	Actual torque <ul style="list-style-type: none"> In the "VFC (+encoder)" operating mode of the motor control, this value is determined from the current motor current and corresponds to the actual torque only by approximation. Scaling: $16384 \equiv 100\% M_{\max}$ (C00057) 	

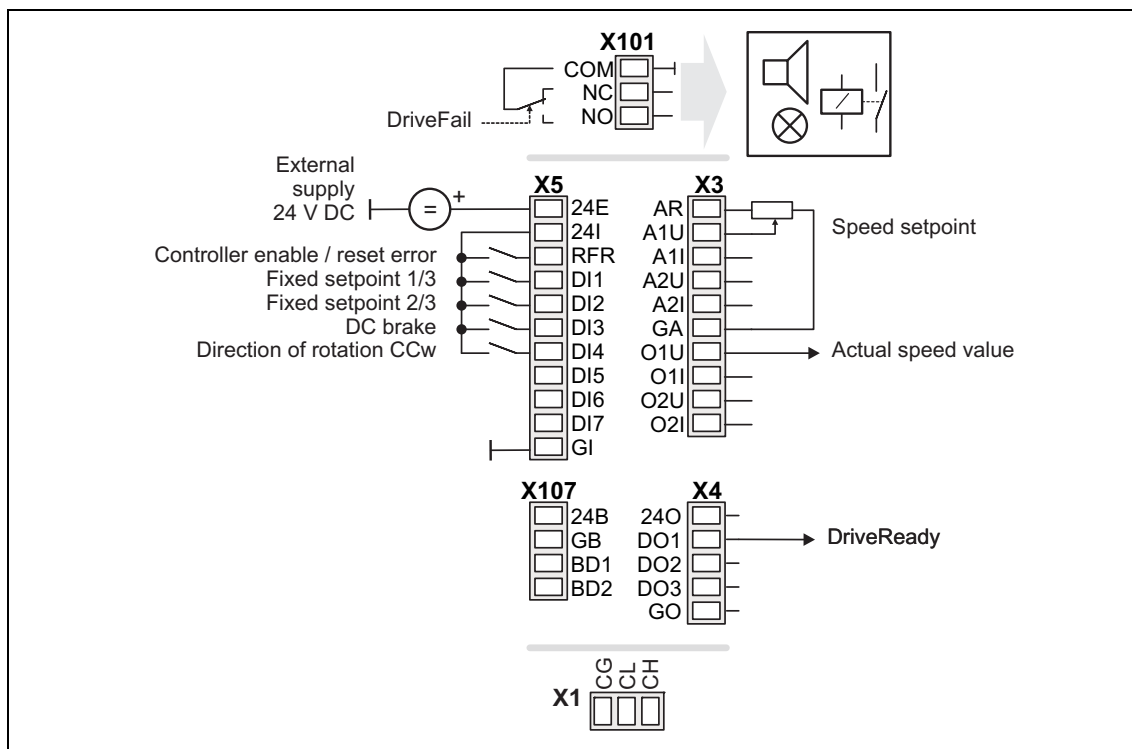
Identifier	Data type	Value/meaning
nDCVoltage_a	INT	Actual DC-bus voltage <ul style="list-style-type: none">• Scaling: 16384 ≡ 1000 V
nMotorVoltage_a	INT	Current motor voltage/inverter output voltage <ul style="list-style-type: none">• Scaling: 16384 ≡ 1000 V
MCK basic functions		
bMBrakeReleaseOut	BOOL	Holding brake control : Trigger signal for the holding brake control switching element via a digital output <ul style="list-style-type: none">• Use bit 0 in C02582 to activate inverted switching element triggering.
		FALSE Apply brake.
		TRUE Release brake.
bMBrakeReleased	BOOL	Holding brake control : "Brake released" considering the brake release time <ul style="list-style-type: none">• When the holding brake is triggered to close, <i>bMBrakeReleased</i> is immediately set to FALSE even if the brake closing time has not yet elapsed!
		TRUE Brake released (after the brake release time has expired).
GP: GeneralPurpose The following outputs are interconnected with logic/arithmetic functions on application level for free usage. ▶ "GeneralPurpose" functions		
nGPAAnalogSwitchInOut_a	INT	Analog switch : Output signal
nGPArithmetikOut_a	INT	Arithmetic : Output signal
nGPMulDivOut_a	INT	Multiplication/Division : Output signal
bGPDigitalDelayOut	BOOL	Binary delay element : Output signal
bGPLogicOut	BOOL	Binary logic : Output signal
bGPCompareOut	BOOL	Analog comparison : Output signal
bGPSignalOut1 ... bGPSignalOut4	BOOL	Binary signal monitor : Output signals <ul style="list-style-type: none">• The signal sources to be output are selected in C00411/1...4.• A bit coded inversion of the output signals can be parameterised in C00412.
nGPSignalOut1_a ... nGPSignalOut4_a	BOOL	Analog signal monitor : Output signals <ul style="list-style-type: none">• The signal sources to be output are selected in C00410/1...4.• Gain and offset for each output signal can be parameterised in C00413/1...8.
bGPDFlipFlop_Out	BOOL	D-FlipFlop : Output signal
bGPDFlipFlop_NegOut	BOOL	D-FlipFlop : Negated output signal
Free outputs The following outputs can freely be interconnected on the application level. The signals from the application level can be transferred to the I/O level via these outputs.		
bFreeOut1 ... bFreeOut8	BOOL	Free outputs for digital signals
wFreeOut1 ... wFreeOut4	WORD	Free outputs for 16-bit signals

8.2.3 Terminal assignment of the control modes

The following comparison provides information about which inputs/outputs of the application block **LA_NCtrl** are interconnected to the digital and analog input/output terminals of the drive controller in the different control modes.

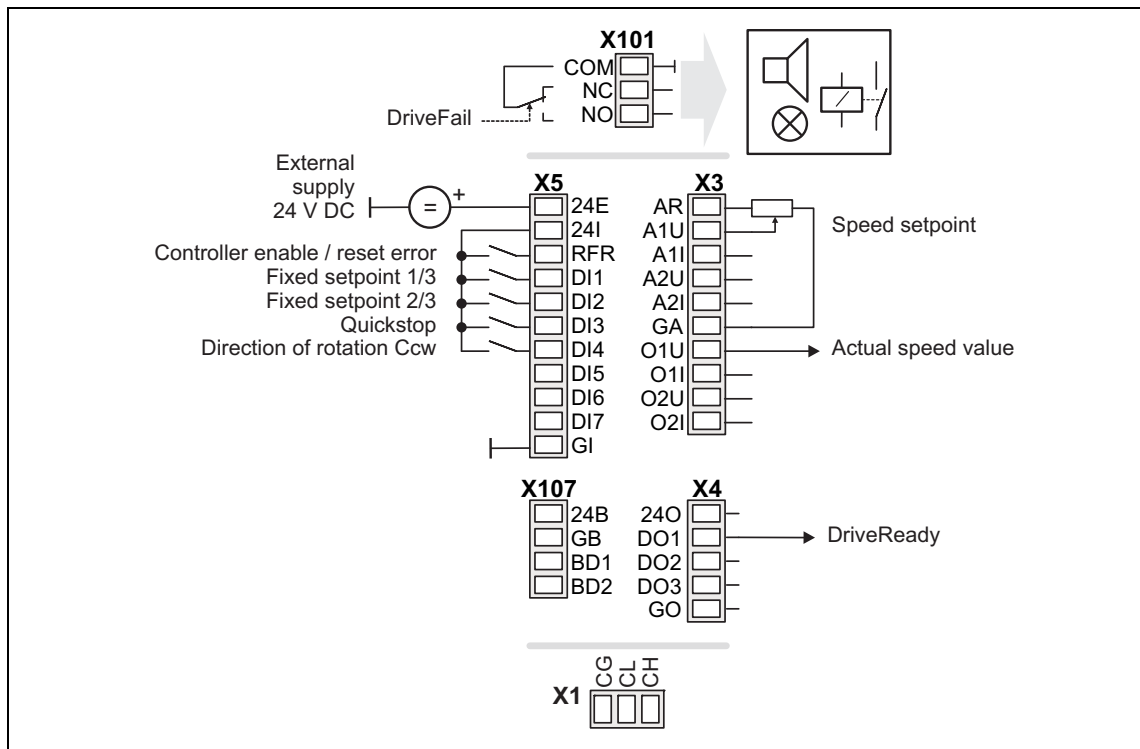
	Control mode (C00007)							
	10: Terminals 0	12: Terminals 2	14: Terminals 11	16: Terminal 16	20: Keypad	21: PC	30: CAN	40: MCI
Digital input terminals								
X5/RFR	Controller enable / Reset of error message bFailReset							
X5/DI1	Fixed setpoint 1/3 bJogSpeed1		Change of direction of rotation bSetSpeedCcw	Fixed setpoint 1/3 bJogSpeed1	-	-	Quick stop bSetQuickstop	
X5/DI2	Fixed setpoint 2/3 bJogSpeed2		Activate manual DC-injection braking (DCB) bSetDCBrake	Fixed setpoint 2/3 bJogSpeed2	-	-	-	-
X5/DI3	Activate manual DC-injection braking (DCB) bSetDCBrake	Quick stop bSetQuickstop	Motor potentiometer: Increase speed bMPotUp	CW rotation quick stop bRLQCw	-	-	-	-
X5/DI4	Change of direction of rotation bSetSpeedCcw		Motor potentiometer: Decrease speed bMPotDown	CCW rotation quick stop bRLQCcw	-	-	-	-
X5/DI5 ... DI7	-	-	-	-	-	-	-	-
Analog input terminals								
X3/A1U, A1I	Main speed setpoint nMainSetValue_a 10 V ≡ 100 % reference speed (C00011)				-	-	Additional speed setpoint nAuxSetValue_a 10 V ≡ 100 % reference speed (C00011)	
X3/A2U, A2I	-	-	-	-	-	-	-	-
Digital output terminals								
X4/DO1	Status "Drive is ready" bDriveReady							
X4/DO2 ... DO3	-	-	-	-	-	-	-	-
X107/BD1, BD2	-	-	-	-	-	-	-	-
X101/COM, NO	Status "Error is pending" bDriveFail							
Analog output terminals								
X3/O1U	Actual speed value nMotorSpeedAct_a 10 V ≡ 100 % reference speed (C00011)							
X3/O1I	-	-	-	-	-	-	-	-
X3/O2U								
X3/O2I								

8.2.3.1 Terminals 0



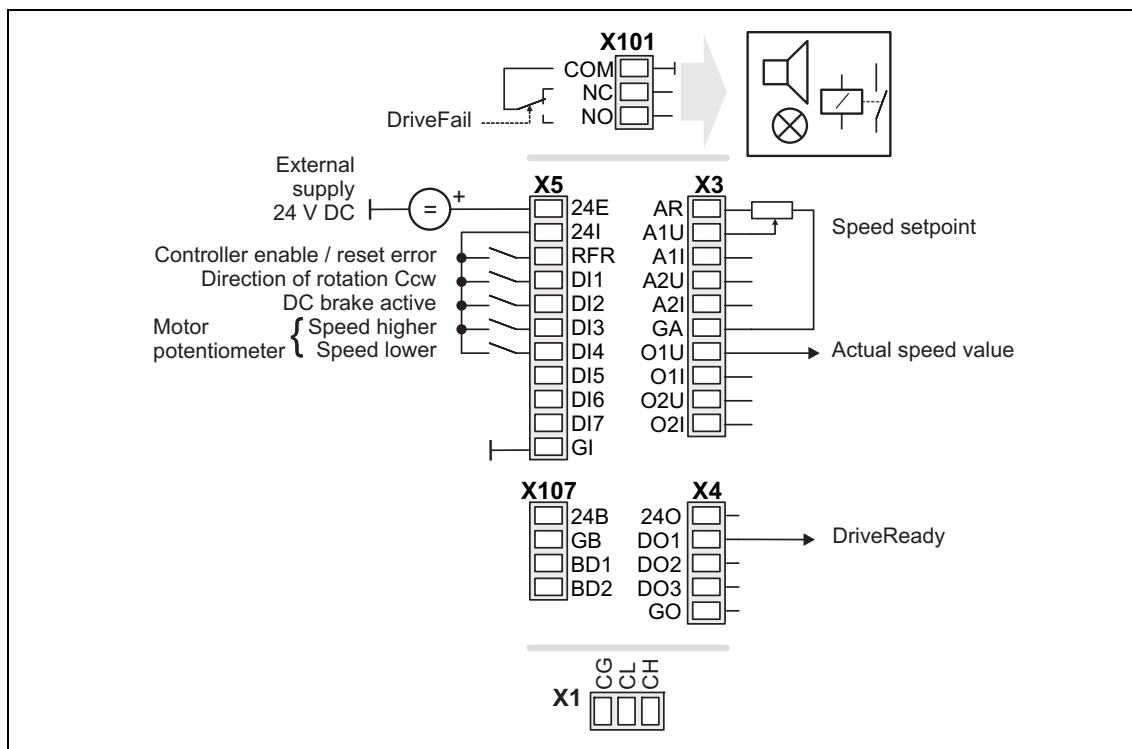
Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	LA_NCtrl.nMainSetValue_a *
X5/DI1	LA_NCtrl.bJogSpeed1	X3/A1I	-
X5/DI2	LA_NCtrl.bJogSpeed2	X3/A2U	-
X5/DI3	LA_NCtrl.bSetDCBrake	X3/A2I	-
X5/DI4	LA_NCtrl.bSetSpeedCcw	X3/O1U	LA_NCtrl.nMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
		* 10 V \equiv 100 % reference speed (C00011)	
X107/BD1	-	X4/DO1	LA_NCtrl.bDriveReady
X107/BD2	-	X4/DO2	-
		X4/DO3	-

8.2.3.2 Terminals 2



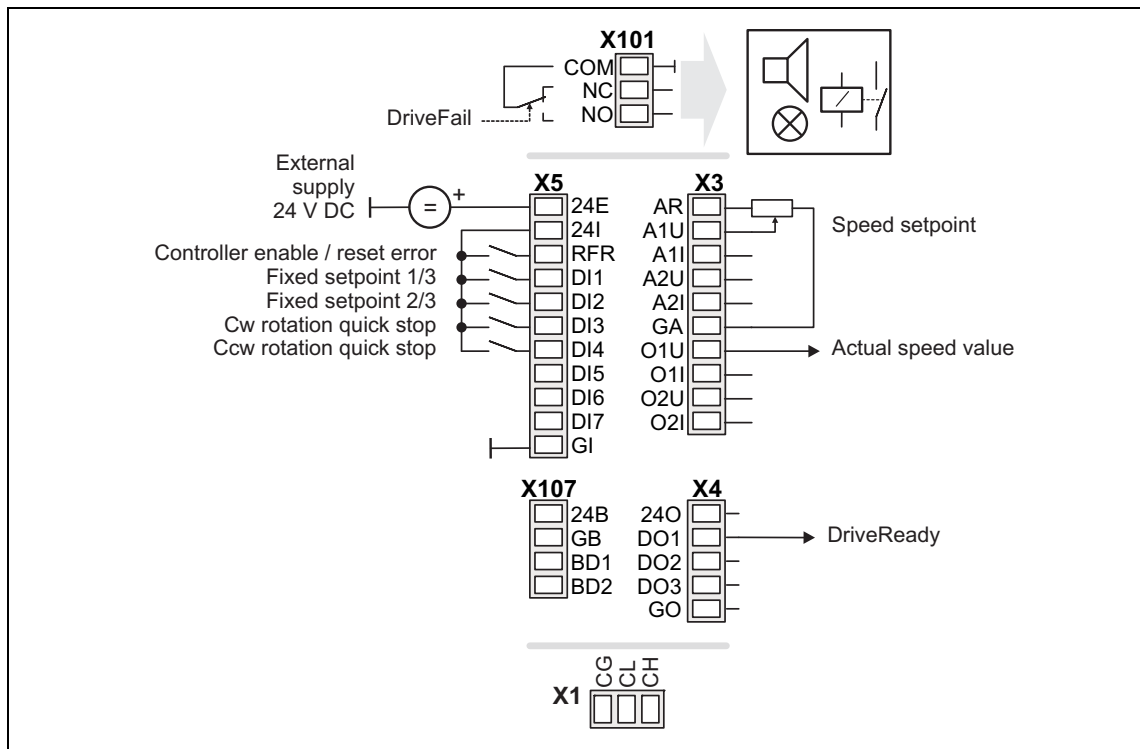
Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	LA_NCtrl.nMainSetValue_a *
X5/DI1	LA_NCtrl.bJogSpeed1	X3/A1I	-
X5/DI2	LA_NCtrl.bJogSpeed2	X3/A2U	-
X5/DI3	LA_NCtrl.bSetQuickstop	X3/A2I	-
X5/DI4	LA_NCtrl.bSetSpeedCcw	X3/O1U	LA_NCtrl.nMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
		* 10 V \equiv 100 % reference speed (C00011)	
X107/BD1	-	X4/DO1	LA_NCtrl.bDriveReady
X107/BD2	-	X4/DO2	-
		X4/DO3	-

8.2.3.3 Terminals 11



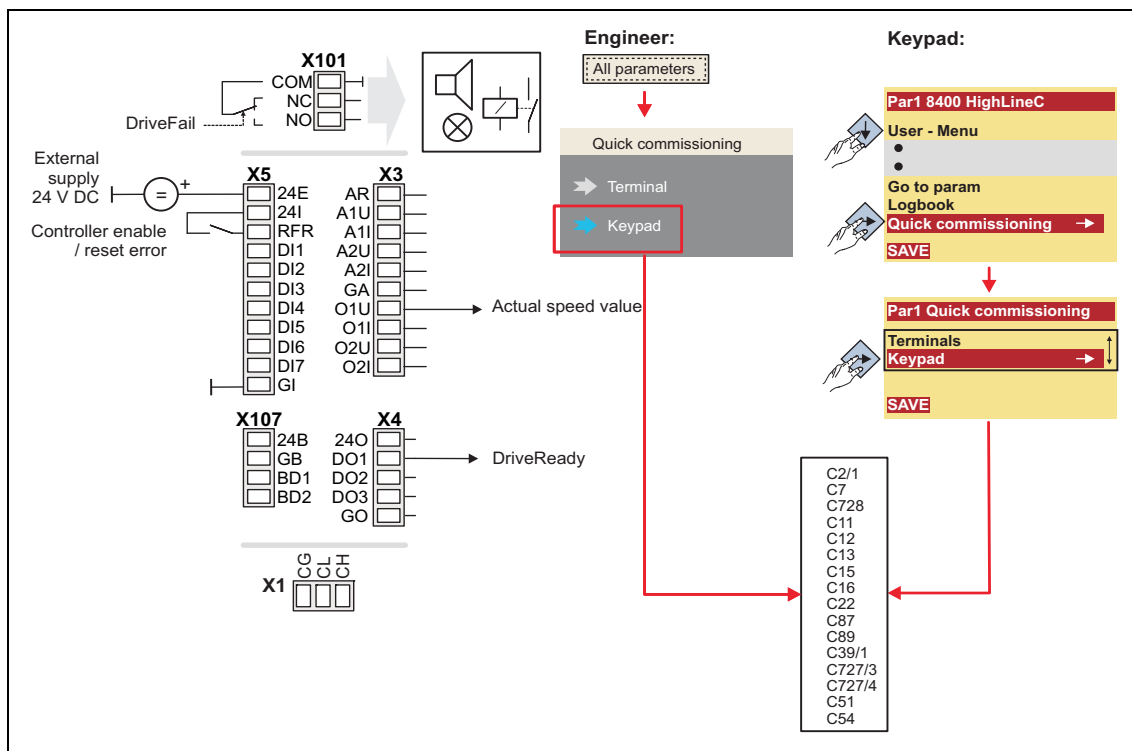
Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	LA_NCtrl.nMainSetValue_a *
X5/DI1	LA_NCtrl.bSetSpeedCcw	X3/A1I	-
X5/DI2	LA_NCtrl.bSetDCBrake	X3/A2U	-
X5/DI3	LA_NCtrl.bMPotUp	X3/A2I	-
X5/DI4	LA_NCtrl.bMPotDown	X3/O1U	LA_NCtrl.nMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
		* 10 V ≙ 100 % reference speed (C00011)	
X107/BD1	-	X4/DO1	LA_NCtrl.bDriveReady
X107/BD2	-	X4/DO2	-
		X4/DO3	-

8.2.3.4 Terminal 16



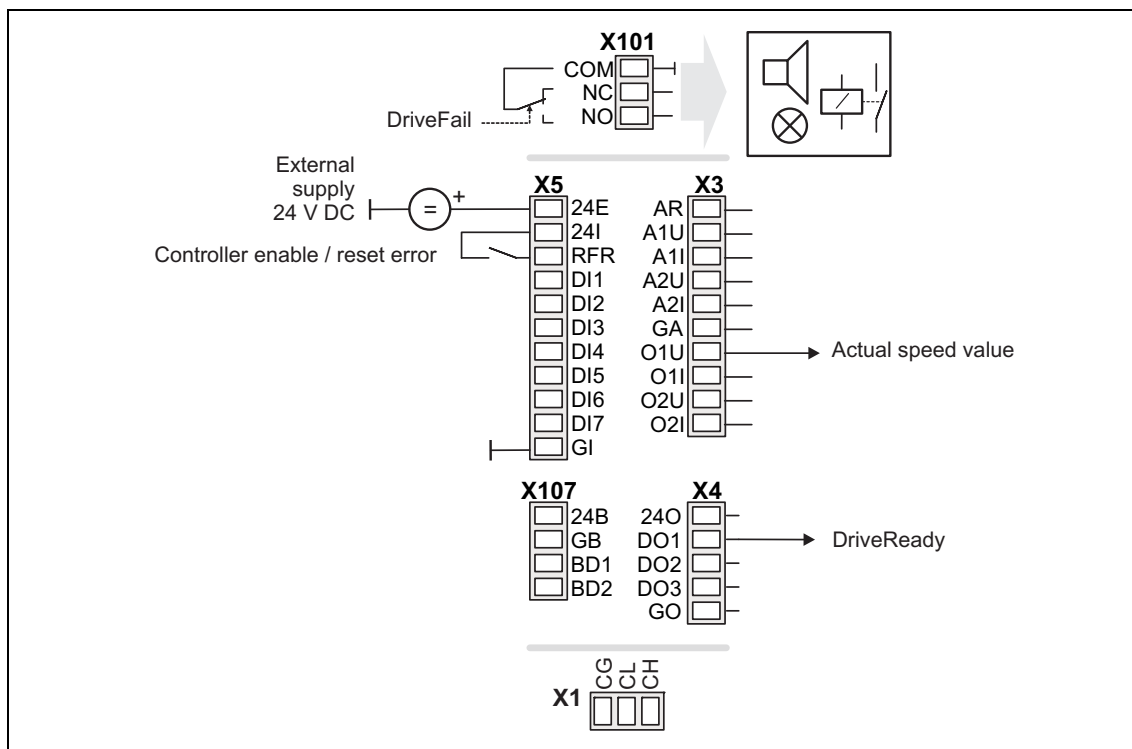
Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	LA_NCtrl.nMainSetValue_a *
X5/DI1	LA_NCtrl.bJogSpeed1	X3/A1I	-
X5/DI2	LA_NCtrl.bJogSpeed2	X3/A2U	-
X5/DI3	LA_NCtrl.bRLQCw	X3/A2I	-
X5/DI4	LA_NCtrl.bRLQCcw	X3/O1U	LA_NCtrl.nMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
		* 10 V \equiv 100 % reference speed (C00011)	
X107/BD1	-	X4/DO1	LA_NCtrl.bDriveReady
X107/BD2	-	X4/DO2	-
		X4/DO3	-

8.2.3.5 Keypad



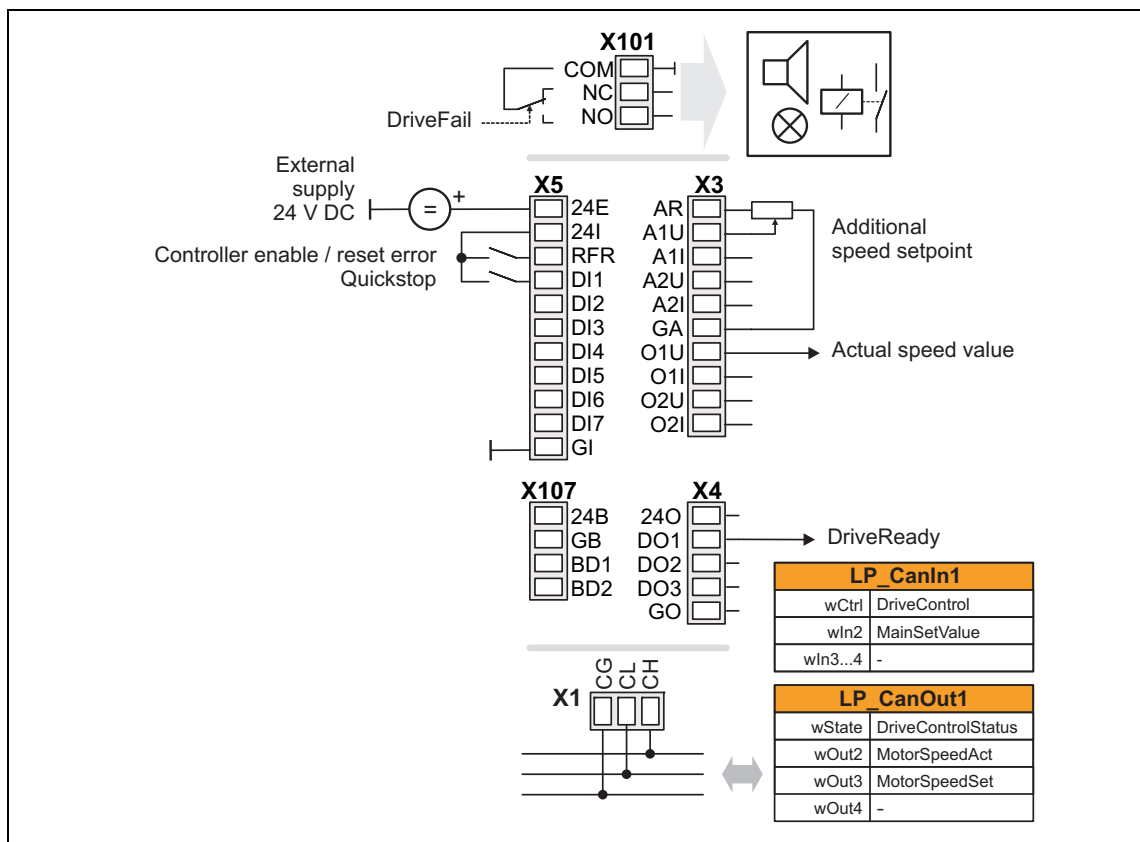
Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	-
X5/DI1	-	X3/A1I	-
X5/DI2	-	X3/A2U	-
X5/DI3	-	X3/A2I	-
X5/DI4	-	X3/O1U	LA_NCtrl.nMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
X107/BD1	-		* 10 V ≡ 100 % reference speed (C00011)
X107/BD2	-	X4/DO1	LA_NCtrl.bDriveReady
		X4/DO2	-
		X4/DO3	-

8.2.3.6 PC



Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	-
X5/DI1	-	X3/A1I	-
X5/DI2	-	X3/A2U	-
X5/DI3	-	X3/A2I	-
X5/DI4	-	X3/O1U	LA_NCtrl.nMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
		* 10 V \equiv 100 % reference speed (C00011)	
X107/BD1	-	X4/DO1	LA_NCtrl.bDriveReady
X107/BD2	-	X4/DO2	-
		X4/DO3	-

8.2.3.7 CAN



Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	LA_NCtrl.nAuxSetValue_a *
X5/DI1	LA_NCtrl.bSetQuickStop	X3/A1I	-
X5/DI2	-	X3/A2U	-
X5/DI3	-	X3/A2I	-
X5/DI4	-	X3/O1U	LA_NCtrl.NMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
		* 10 V ≙ 100 % reference speed (C00011)	
X107/BD1	-	X4/DO1	LA_NCtrl.bDriveReady
X107/BD2	-	X4/DO2	-
		X4/DO3	-

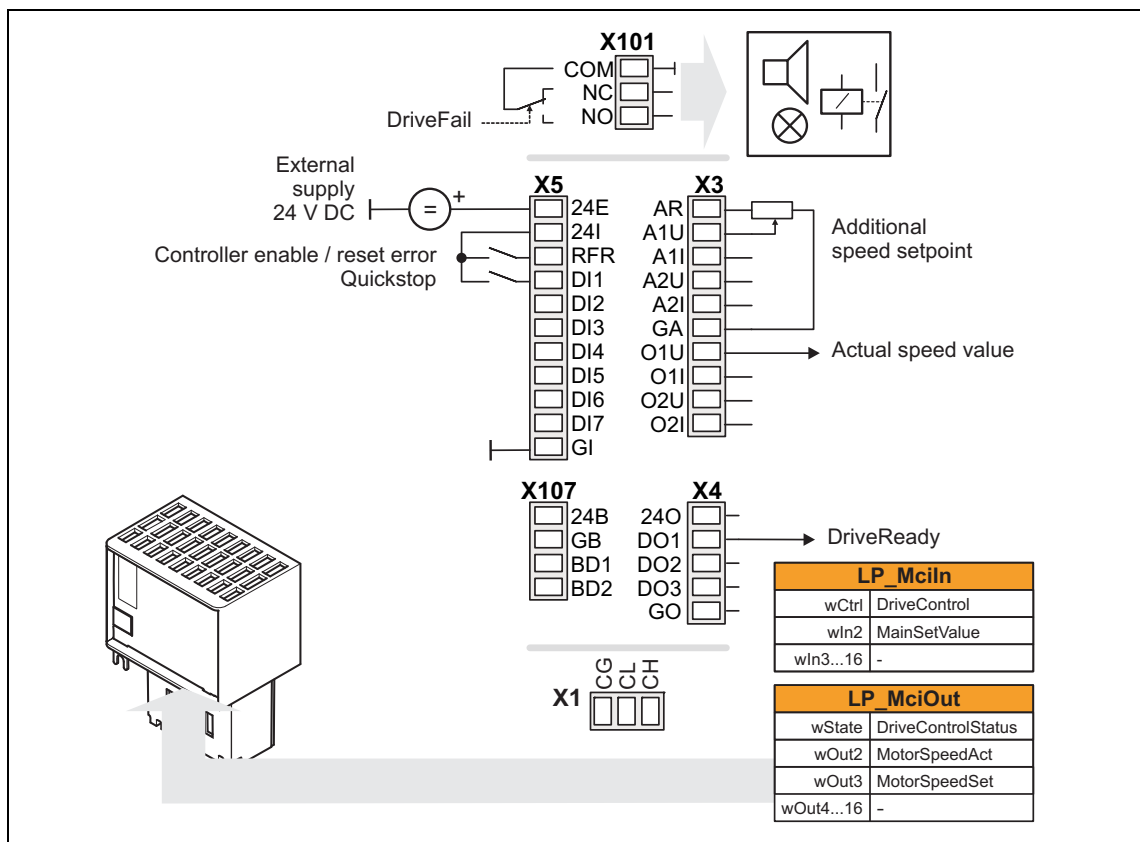
► [Process data assignment for fieldbus communication \(450\)](#)



Note!

- You must set the setpoint arithmetic in [C00190](#) to "1: NOut = NSet + NAdd" so that the additional speed setpoint selected via the analog input A1U has an additive effect.
- The "manual jog" function via digital terminals is being prepared!

8.2.3.8 MCI



Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	LA_NCtrl.nAuxSetValue_a *
X5/DI1	LA_NCtrl.bSetQuickStop	X3/A1I	-
X5/DI2	-	X3/A2U	-
X5/DI3	-	X3/A2I	-
X5/DI4	-	X3/O1U	LA_NCtrl.NMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
		* 10 V ≙ 100 % reference speed (C00011)	
X107/BD1	-	X4/DO1	LA_NCtrl.bDriveReady
X107/BD2	-	X4/DO2	-
		X4/DO3	-

► [Process data assignment for fieldbus communication \(450\)](#)

**Note!**

- You must set the setpoint arithmetic in [C00190](#) to "1: NOut = NSet + NAdd" so that the additional speed setpoint selected via the analog input A1U has an additive effect.
- The "manual jog" function via digital terminals is being prepared!

8.2.4 Process data assignment for fieldbus communication

The fieldbus communication is connected (preconfigured) to the previously selected technology application by selecting the corresponding control mode in [C00007](#):

- "30: [CAN](#)" for the connection to the system bus (CAN)
- "40: [MCI](#)" for the connection to a plugged-on communication module (e.g. PROFIBUS)

The assignment of the process data words depends only on the application, not on the bus system used:

Input words	Name	Assignment
Word 1	DriveControl	Control word • For bit assignment see the table below.
Word 2	MainSetValue	Speed setpoint • Scaling: 16384 \equiv 100 % reference speed (C00011)
Word 3	-	Not preconfigured
Word 4	-	Not preconfigured
Words 5 ... 16	-	Not preconfigured • Only available in control mode "40: MCI".

Control word	Name	Function
Bit 0	SwitchOn	1 \equiv Change to the " SwitchedOn " device status • This bit must be set in the CAN/MCI control word to ensure that the device changes to the " SwitchedOn " device status after mains connection without the need for a master control specifying this bit via fieldbus. • If control via a bus system is not wanted (e.g. in the case of control via terminals), the <i>wDriveCtrl</i> output signal of the LS_ParFix system block can be connected to the control word inputs.
Bit 1	DisableVoltage	1 \equiv Inhibit inverter control (pulse inhibit)
Bit 2	SetQuickStop	1 \equiv Activate quick stop (QSP). ▶ Activate/deactivate quick stop (□ 108)
Bit 3	EnableOperation	1 \equiv Enable controller (RFR) • If control via terminals is performed, this bit must be set both in the CAN control word and in the MCI control word. Otherwise, the controller is inhibited. ▶ Enable/Inhibit controller (□ 107)
Bit 4	ModeSpecific_1	Reserved (currently not assigned)
Bit 5	ModeSpecific_2	
Bit 6	ModeSpecific_3	
Bit 7	ResetFault	1 \equiv Reset fault (trip reset) • Acknowledge error message (if the error cause has been eliminated). ▶ Reset error (□ 111)
Bit 8	SetHalt	1 \equiv Activate stop function • Stop drive via stopping ramp (in preparation).
Bit 9	reserved_1	Reserved (currently not assigned)
Bit 10	reserved_2	
Bit 11	SetDCBrake	1 \equiv Activate DC-injection braking ▶ Manual DC-injection braking (DCB) (□ 268)
Bit 12	JogSpeed1	Activation of fixed speed 1 ... 3
Bit 13	JogSpeed2	

Control word	Name	Function
Bit 14	SetFail	1 ≡ Set error (trip set)
Bit 15	SetSpeedCcw	0 ≡ Direction of rotation to the right (Cw) 1 ≡ Direction of rotation to the left (Ccw)

Output words	Name	Assignment
Word 1	DriveControlStatus	Status word • For bit assignment see the table below.
Word 2	MotorSpeedAct	Actual speed value • Scaling: 16384 ≡ 100 % reference speed (C00011)
Word 3	MotorSpeedSet	Resulting overall setpoint • Scaling: 16384 ≡ 100 % reference speed (C00011)
Word 4	-	Not preconfigured
Words 5 ... 16	-	Not preconfigured • Only available in control mode "40: MCI".

Status word	Name	Status
Bit 0	FreeStatusBit0	Free status bit 0 (not assigned, freely assignable)
Bit 1	PowerDisabled	1 ≡ Inverter control inhibited (pulse inhibit is active)
Bit 2	FreeStatusBit2	Free status bit 2 (not assigned, freely assignable)
Bit 3	FreeStatusBit3	Free status bit 3 (not assigned, freely assignable)
Bit 4	FreeStatusBit4	Free status bit 4 (not assigned, freely assignable)
Bit 5	FreeStatusBit5	Free status bit 5 (not assigned, freely assignable)
Bit 6	ActSpeedIsZero	During open-loop operation: 1 ≡ Speed setpoint < Comparison value (C00024)
		During closed-loop operation: 1 ≡ Actual speed value < Comparison value (C00024)
Bit 7	ControllerInhibit	1 ≡ Controller inhibited (controller inhibit is active)
Bit 8	StatusCodeBit0	Bit coded display of the active device status ► Device state machine and device states (see table [4-1])
Bit 9	StatusCodeBit1	
Bit 10	StatusCodeBit2	
Bit 11	StatusCodeBit3	
Bit 12	Warning	1 ≡ A warning is indicated
Bit 13	Trouble	1 ≡ Controller is in the " Trouble " device status • E.g. if an overvoltage has occurred.
Bit 14	FreeStatusBit14	Free status bit 14 (not assigned, freely assignable)
Bit 15	FreeStatusBit15	Free status bit 15 (not assigned, freely assignable)

8.2.5 Setting parameters (short overview)

Parameter	Info	Lenze setting	
		Value	Unit
C00012	Accel. time - main setpoint	2.000	s
C00013	Decel. time - main setpoint	2.000	s
C00019	Auto-DCB: Threshold	3	rpm
C00024	LS_DriveInterface: bNActCompare	0.00	%
C00036	DCB braking: Current	50.00	%
C00039/1	Fixed setpoint 1	40.00	%
C00039/2	Fixed setpoint 2	60.00	%
C00039/3	Fixed setpoint 3	80.00	%
C00039/4...15	Fixed setpoint 4 ... 15	0.00	%
C00101/1...15	Add. accel. time 1 ... 15	0.000	s
C00103/1...15	Add. decel. time 1 ... 15	0.000	s
C00105	Decel. time - quick stop	2.000	s
C00106	Auto-DCB: Hold time	0.500	s
C00107	DCB braking: Hold time	999.000	s
C00134	L_NSet_1: Ramp smoothing	0: Off	
C00182	L_NSet_1: S-ramp time PT1	20.00	s
C00190	L_NSet_1: Setpoint arithmetic	0: Out = Set	
C00220	L_NSet_1: Acceleration time - add. setpoint	0.000	s
C00221	L_NSet_1: Deceleration time - add. setpoint	0.000	s
C00222	L_PCTRL_1: Vp	1.0	
C00223	L_PCTRL_1: Tn	400	ms
C00224	L_PCTRL_1: Kd	0.0	
C00225	L_PCTRL_1: MaxLimit	199.99	%
C00226	L_PCTRL_1: MinLimit	-199.99	%
C00227	L_PCTRL_1: Acceleration time	0.010	s
C00228	L_PCTRL_1: Deceleration time	0.010	s
C00233	L_PCTRL_1: Root function	0: Off	
C00241	L_NSet_1: Hyst. NSet reached	0.50	%
C00242	Operating mode of process controller	0: Off	
C00243	L_PCTRL_1: Accel. time influence	5.000	s
C00244	L_PCTRL_1: Deceleration time influence	5.000	s
C00632/1	L_NSet_1: Blocking speed 1 max	0.00	%
C00632/2	L_NSet_1: Blocking speed 2 max	0.00	%
C00632/3	L_NSet_1: Blocking speed 3 max	0.00	%
C00633/1	L_NSet_1: Blocking speed 1 min	0.00	%
C00633/2	L_NSet_1: Blocking speed 2 min	0.00	%
C00633/3	L_NSet_1: Blocking speed 3 min	0.00	%
C00635	L_NSet_1: nMaxLimit	199.99	%
C00636	L_NSet_1: nMinLimit	-199.99	%
C00670	L_OffsetGainP_1: Gain	1.0000	
C00671	L_OffsetGainP_2: Gain	1.0000	
C00672	L_OffsetGainP_3: Gain	1.0000	

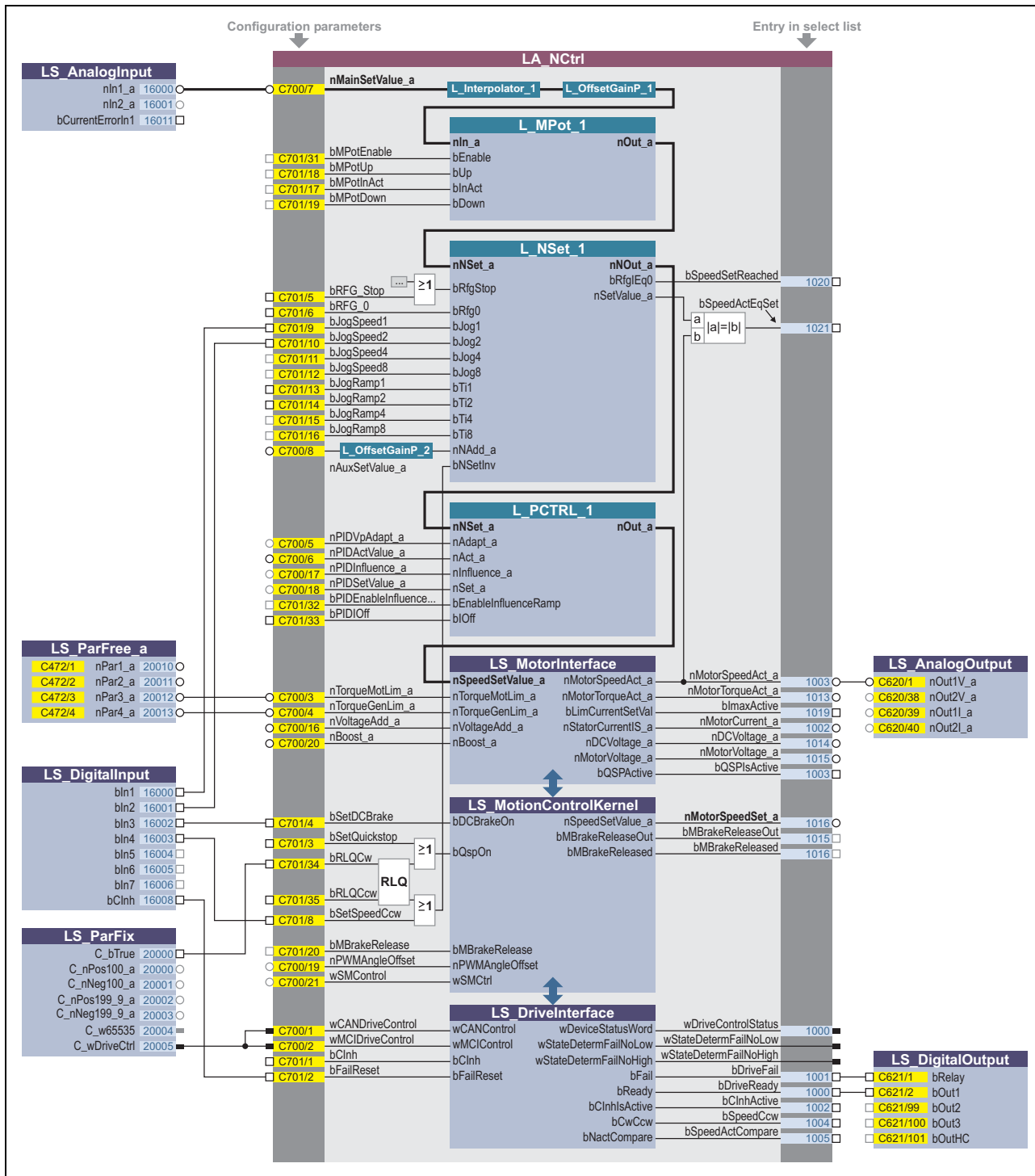
Parameter	Info	Lenze setting	
		Value	Unit
C00696	L_OffsetGainP_1: Offset	0.00	%
C00697	L_OffsetGainP_2: Offset	0.00	%
C00698	L_OffsetGainP_3: Offset	0.00	%
C00800	L_MPot_1: Upper limit	100.00	%
C00801	L_MPot_1: Lower limit	-100.00	%
C00802	L_MPot_1: Acceleration time	10.0	s
C00803	L_MPot_1: Deceleration time	10.0	s
C00804	L_MPot_1: Inactive fct.	0: Retain value	
C00805	L_MPot_1: Init fct.	0: Load last value	
C00806	Use of motor potentiometer	0: No	

Related topics:

► ["GeneralPurpose" functions](#) (📖 546)

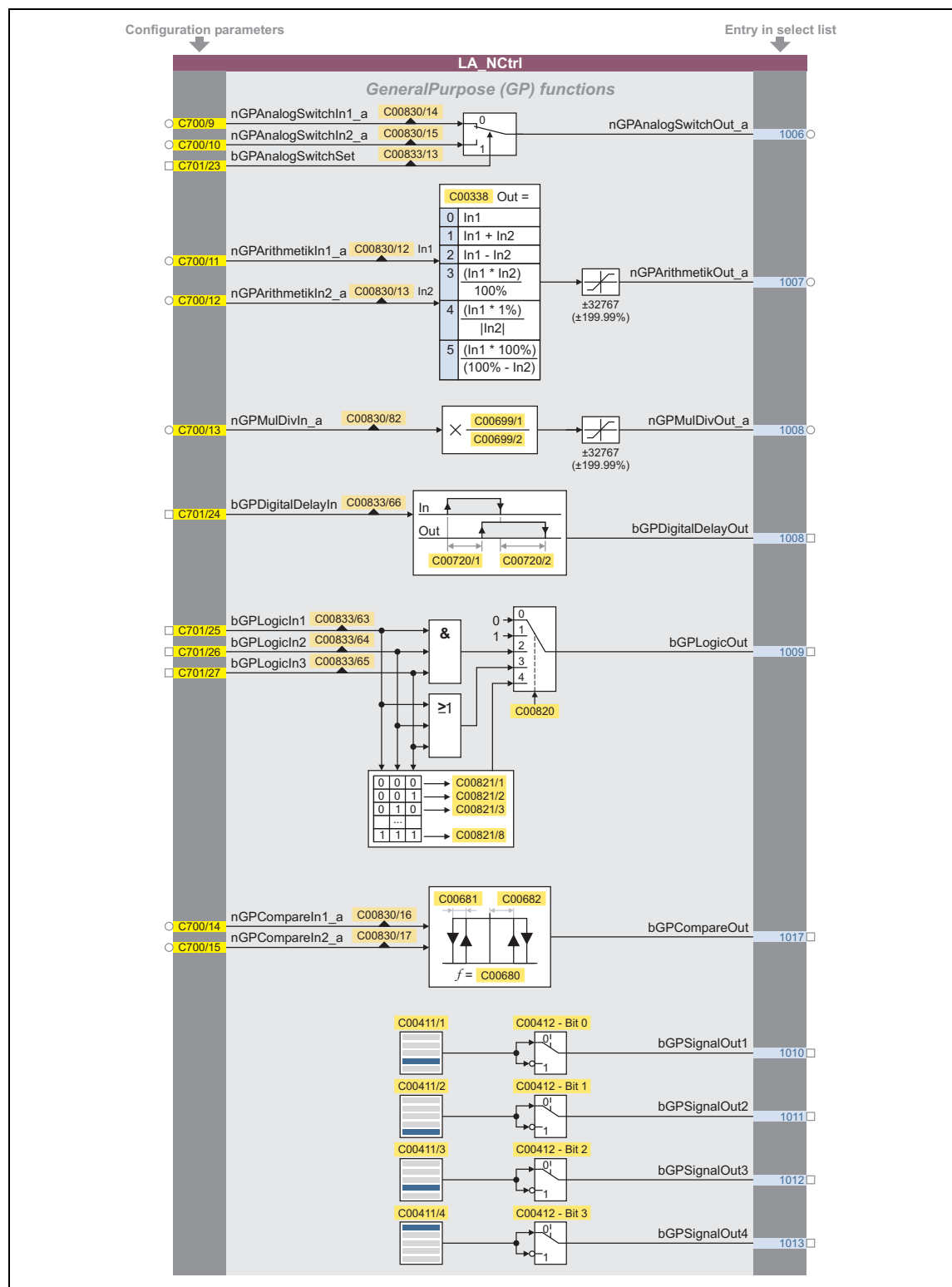
8.2.6 Configuration parameters

If required, the subcodes of [C00700](#) and [C00701](#) serve to change the pre-configured assignment of the application inputs:

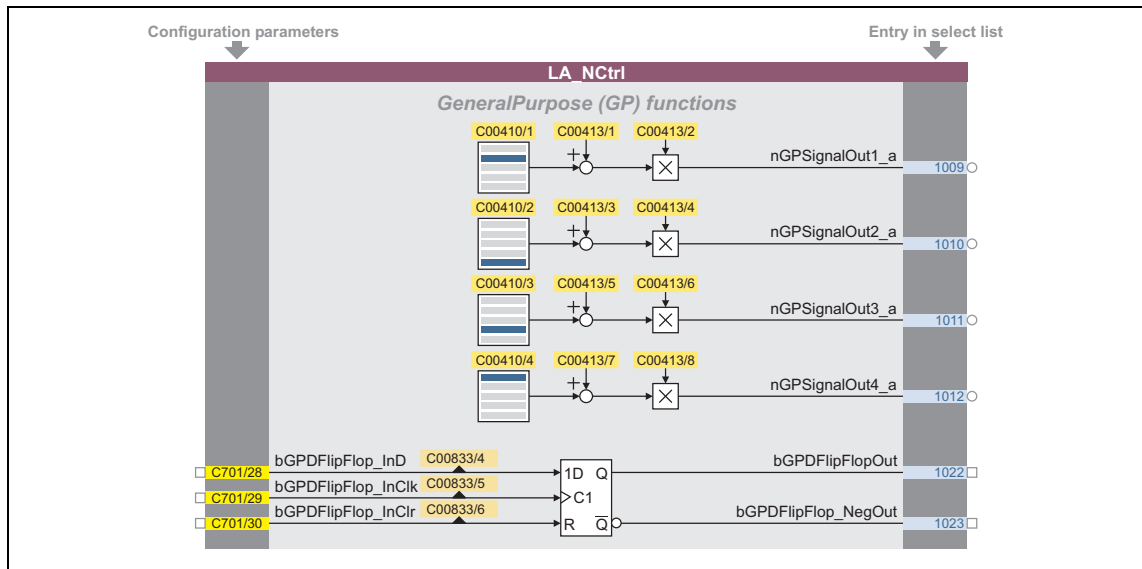


[8-2] Pre-assignment of the "Actuating drive speed" application in the "Terminals 0" control mode

Configuration parameters for "GeneralPurpose" functions



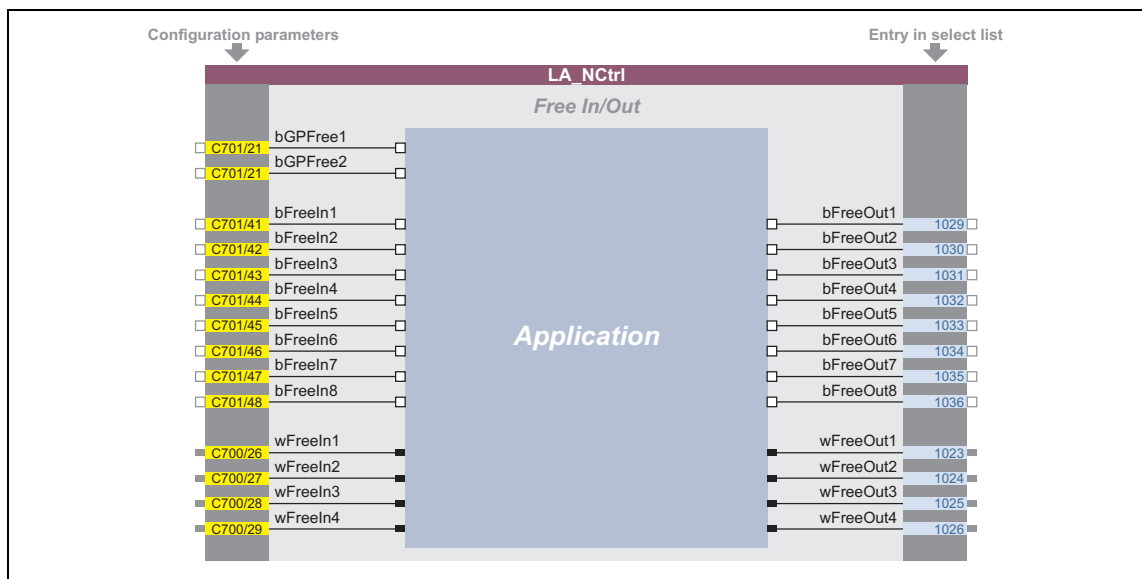
[8-3] "GeneralPurpose" functions



[8-4] "GeneralPurpose" functions (continuation)

Free inputs and outputs

These inputs can be freely interconnected in the application level. They can be used to transfer signals from the I/O level to the application level and vice versa.



[8-5] Free inputs/outputs

Related topics:

- ▶ [User-defined terminal assignment](#) (421)
- ▶ ["GeneralPurpose" functions](#) (546)

8.3 TA "actuating drive speed (AC Drive Profile)"

This technology application is available from version 13.00.00!

The EtherNet/IP™ communication module supports the "AC Drive Profile".

When the controller is provided with an EtherNet/IP™ communication module and the control is to be carried out by means of "AC Drive Profile" via EtherNet/IP™, make the following settings:

1. Set the application "1100: Actuating drive speed (AC Drive Profile)" in [C00005](#).
2. Set the "40: MCI" control mode in [C00007](#).
 - The process data word received by the master control is then interpreted by the application as "AC Drive Profile" control word.
 - When the control is carried out via the system bus (CANopen), set the "30: CAN" control mode instead in [C00007](#).

Features

- Pre-configured control modes for terminals and bus control (with predefined process data connection to the fieldbus)
- Free configuration of input and output signals
- adjustable offset, gain and negation of the speed setpoint
- Up to 15 fixed setpoints for speed and ramp time
- Adjustable setpoint ramp times
- Freely selectable, variable ramp shape
- Automatic holding brake control
- Quick stop (QSP) with adjustable ramp time
- Motor potentiometer function (optional)
- Process controller (optional)
- Integrated, freely available "GeneralPurpose" functions:
Analog switch, arithmetic, multiplication/division, binary delay element, binary logic, analog comparison, D-flipflop
- Interface to the safety module (optional)
- Integration of encoder feedback



Note!

In contrast to the "actuating drive speed" standard application, this application makes use of the *nAuxSetValue_a* input to determine a local speed setpoint (when NetRef=0). For this reason, the *nNAdd_a* input at the [L NSet 1](#) setpoint generator for determining an additional speed setpoint is not connected in the Lenze setting.

8.3.1 I/O assemblies

For the data exchange, the technology application supports the assembly output object instance 23 (0x17) and assembly input object instance 73 (0x49) defined by the ODVA (Open DeviceNet Vendor Association).

Instance 23 (0x17): Extended Speed and Torque Control Output								
Bytes	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
0		Net Ref	NetCtrl			Fault Reset	Run Rev	Run Fwd
1								
2	Speed Reference (Low Byte)							
3	Speed Reference (High Byte)							
4	Torque Reference (Low Byte)							
5	Torque Reference (High Byte)							

Instance 73 (0x49): Extended Speed and Torque Control Input								
Bytes	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
0	At Reference	RefFrom Net	CtrlFrom Net	Ready	Running2 (Rev)	Running1 (Fwd)	Warning	Faulted
1	Drive State							
2	Speed Actual (Low Byte)							
3	Speed Actual (High Byte)							
4	Torque Actual (Low Byte)							
5	Torque Actual (High Byte)							



Detailed information on the data transfer and "AC Drive Profile" can be found in the E84AYCEO communication manual (EtherNet/IP™).



Tip!

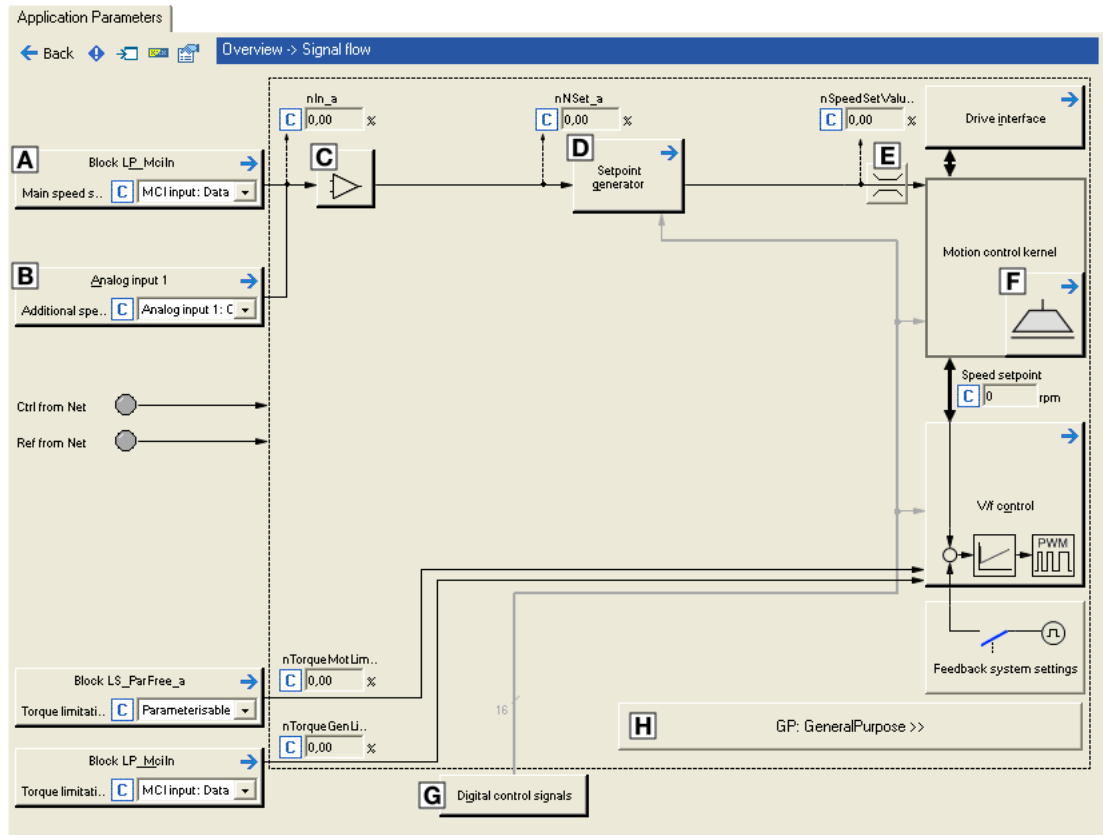
Detailed information on EtherNet/IP™ can be found at the web page of the ODVA (Open DeviceNet Vendor Association) user organisation:

<http://www.odva.org>

Related topics:

- [Process data assignment for fieldbus communication](#)
- [Run/Stop event](#)
- [Scaling of speed and torque values](#)

8.3.2 Basic signal flow





[8-6] Signal flow of the "actuating drive speed (AC Drive Profile)" technology application

- [A] Configuration of the signal source for setpoint selection via fieldbus (NetRef=1)
- [B] Configuration of the signal source for local setpoint selection (NetRef=0)
- [C] Offset and gain for speed setpoint ([L_OffsetGainP 1](#))
- [D] Setpoint generator ([L_NSet 1](#))
- [E] Speed setpoint input limitation
- [F] [Holding brake control](#)
- [G] Terminal assignment & display of digital control signals
- [H] Integrated disposable "[GeneralPurpose](#)" functions: Analog switch, arithmetic, multiplication/division, binary delay element, binary logic, analog comparison, D-flipflop

Definition of the speed setpoint

The speed setpoint is usually defined as process data via the fieldbus. If set accordingly, the speed setpoint can also be determined locally (e.g. via the analog input 1). Depending on the selection, either only the *nMainSetValue_a* application input or only the application input *nAuxSetValue_a* is effective. The following table shows the relationships:

Fieldbus used	Control mode (C00007)	Speed reference	AC Drive Profile control word (wMCIDriveControl)	effective input (at LA_NCtrl)
	40: MCI	via fieldbus (data word 2)	Bit 6 ("NetRef") = 1	<i>nMainSetValue_a</i>
		local*	Bit 6 ("NetRef") = 0	<i>nAuxSetValue_a</i>
	30: CAN	via fieldbus (data word 2)	Bit 6 ("NetRef") = 1	<i>nMainSetValue_a</i>
		local*	Bit 6 ("NetRef") = 0	<i>nAuxSetValue_a</i>
-	10: Terminals 0 12: Terminals 2 14: Terminals 11 16: Terminals 16	local*	9 ≡ 0x0009 • Bit 0, SwitchOn = TRUE • Bit 3, EnableOperation = TRUE • All others: FALSE	<i>nAuxSetValue_a</i>
	20: Keypad	C00728/3		
	21: PC	C00472/1		

* The local setpoint is selected in the Lenze setting via the analog input 1

Scaling of the speed setpoint

If the setpoint is determined via fieldbus (NetRef=1), the setpoint applied to the *nMainSetValue_a* application input is evaluated with the speed scaling set in [C01353/1](#) (AC Drive Attribute 22). ▶ [Scaling of speed and torque values](#).

If the setpoint is determined locally (e.g. via the analog input 1), the setpoint applied to the *nAuxSetValue_a* application input is scaled as follows:

16384 ≡ 100 % reference speed ([C00011](#)).

Offset & gain

Offset and gain of the speed signal can be set in [C00696](#) and [C00670](#) for a simple signal adjustment of a setpoint encoder.

Ramp function generator

The setpoint is transformed to a speed setpoint in the setpoint encoder via a ramp function generator with linear or S-shaped ramps.

- Upstream to the ramp function generator, a blocking speed masking function and a setpoint MinMax limitation are effective.
- For a detailed functional description see the [L_NSet](#) FB.

Selection of the direction of rotation

- In case of control via fieldbus via bit 0 "Run Forward" and bit 1 "Run Backward" of the AC Drive Profile control word.
- In case of local control via the *bSetSpeedCcw* application input or by selecting negative fixed setpoints.



Selection of the torque setpoint in torque mode

In torque mode", the *nTorqueGenLim_a* application input has the function of the torque setpoint selection.

The torque setpoint is usually defined as process data via the fieldbus. If set accordingly, the torque setpoint can also be determined locally (e.g. via the analog input 1).

For the local selection of the torque setpoint, the same application input (*nAuxSetValue_a*) is used as for the local selection of the speed setpoint. In "torque mode" however, the *nAuxSetValue_a* input is internally connected to the *nTorqueGenLim_a* input. In this case, the speed setpoint is internally permanently set to "100 %".

The relationships are shown in the following table:

Fieldbus used	Control mode (C00007)	Torque reference	AC Drive Profile control word (wMCIDriveControl)	effective input (at LA_NCtrl)
	40: MCI	via fieldbus (data word 3)	Bit 6 ("NetRef") = 1	<i>nTorqueGenLim_a</i>
		local*	Bit 6 ("NetRef") = 0	<i>nAuxSetValue_a</i>
	30: CAN	via fieldbus (data word 3)	Bit 6 ("NetRef") = 1	<i>nTorqueGenLim_a</i>
		local*	Bit 6 ("NetRef") = 0	<i>nAuxSetValue_a</i>
-	10: Terminals 0 12: Terminals 2 14: Terminals 11 16: Terminals 16	local*	9 ≡ 0x0009 • Bit 0, SwitchOn = TRUE • Bit 3, EnableOperation = TRUE • All others: FALSE	<i>nAuxSetValue_a</i>
	20: Keypad	C00728/3		
	21: PC	C00472/1		
* The local setpoint is selected in the Lenze setting via the analog input 1				

8.3.3 Internal interfaces | application block "LA_NCtrl"



**Note!**

The connectors grayed out in the following table are hidden in the function block editor in the Lenze setting.

- These connections can be shown via the **Connector visibilities** command in the *Context menu* of the application block.

Inputs

Identifier	Data type	Information/possible settings
wCANDriveControl	WORD	Input for CAN control word <ul style="list-style-type: none"> • Is not used in this configuration and is thus set to the permanent value "9" in the Lenze setting (SwitchOn = TRUE and EnableOperation = TRUE). • For the evaluation of the AC Drive Profile control word received via fieldbus, the <i>wMCIDriveControl</i> input is used in the control modes 30: CAN" and "40: MCI".
wMCIDriveControl	WORD	Input for the AC Drive Profile control word received via fieldbus <ul style="list-style-type: none"> • The AC Drive Profile control word operates the controller in compliance with the assembly output object instances 20 ... 23. For this purpose, the control bits are evaluated and lead to a corresponding modification of the control signals <i>bFailReset</i>, <i>bRFG_0</i> and <i>bSetSpeedCw</i> which results in the AC Drive-specific behaviour. • See the "Process data assignment for fieldbus communication" subchapter for a detailed description of the individual control bits. • Display parameter: C01351/1
wSMControl	WORD	Interface to the optional safety system. <ul style="list-style-type: none"> • Setting control bit 0 ("SafeStop1") in this control word causes e.g. the automatic deceleration of the drive to standstill within this application (in the Motion Control Kernel). • See the subchapter "Interface to safety system" of the chapter on basic drive functions for a detailed description of the individual control bits.
bCIInh	BOOL	Enable/Inhibit controller
		<div>FALSE</div> <div>Enable controller: The controller switches to the "OperationEnabled" device status if no other source for controller inhibit is active. <ul style="list-style-type: none"> • C00158 provides a bit coded representation of all active sources/triggers of a controller inhibit. </div> <div>TRUE</div> <div>Inhibit controller (controller inhibit): The controller switches to the "SwitchedOn" device status.</div>
bFailReset	BOOL	Reset error message <ul style="list-style-type: none"> • In the Lenze setting this input is connected to the digital input controller enable so that a possibly existing error message is reset together with the controller enable (if the cause for the fault is eliminated). • In case of control via fieldbus (NetCtrl=1): This input is OR'd with bit 2 ("fault reset") of the AC Drive Profile control word.
		<div>TRUE</div> <div>The current fault is reset, if the cause for the fault is eliminated. <ul style="list-style-type: none"> • If the fault still exists, the error status remains unchanged. </div>

Identifier	Data type	Information/possible settings
bSetQuickstop	BOOL	Enable quick stop (QSP) • Also see device command " Activate/deactivate quick stop ".
		TRUE Activate quick stop • Motor control is decoupled from the setpoint selection and, within the deceleration time parameterised in C00105 , the motor is brought to a standstill ($n_{act} = 0$). • The motor is kept at a standstill during closed-loop operation. • A pulse inhibit is set if the auto-DCB function has been activated via C00019 .
		FALSE Deactivate quick stop • The quick stop is deactivated if no other source for the quick stop is active. • C00159 displays a bit code of active sources/causes for the quick stop.
bSetDCBrake	BOOL	Manual DC-injection braking (DCB) • Detailed information on DC-injection braking is provided in the motor control chapter, subchapter " DC-injection braking ".
		 Note! Holding braking is not possible when this braking mode is used! Use the basic " Holding brake control " function for controlling the holding brake with a low rate of wear.
		FALSE Deactivate DC-injection braking.
		TRUE Activate DC-injection braking, i.e. the drive is brought to a standstill by means of DC-injection braking. • The braking effect stops when the rotor is at standstill. • After the hold time (C00107) has expired, the controller sets the pulse inhibit.
bRFG_Stop	BOOL	Ramp function generator: Maintain the current value of the main setpoint integrator • The speed, for instance, of a running ramp process is immediately kept constant when <i>bRFG_Stop</i> is activated. At the same time, the acceleration/deceleration jumps to the value "0". • For a detailed functional description see the L_NSet FB.
		TRUE The current value of the main setpoint integrator is held.
bRFG_0	BOOL	Ramp function generator: Lead the main setpoint integrator to "0" within the current T_i times • In case of control via fieldbus (NetCtrl=1): If a stop is triggered via bit 0 ("Run Forward") and bit 1 ("Run Backward") of the AC Drive Profile control word, this signal is internally set to TRUE and thus the drive is braked to standstill. • For a detailed functional description see the L_NSet FB.
		TRUE The current value of the main setpoint integrator is led to "0" within the T_i time set.
nVoltageAdd_a	INT	Additive voltage impression • An additional setpoint for the motor voltage can be specified via this process input. • If there are, for instance, different loads at the motor output end, it is possible to apply a voltage boost at the starting time. • If the value is negative, the voltage is reduced. • Scaling: $16384 \equiv 1000 \text{ V}$
		 Stop! Values selected too high may cause the motor to heat up due to the resulting current!

Identifier	Data type	Information/possible settings
nBoost_a	INT	<div>Additional setpoint for the motor voltage at speed = 0</div> <div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><div></div></div><div><</div></div>

Identifier	Data type	Information/possible settings
bRLQCcw	BOOL	<p>Activate counter-clockwise rotation (fail-safe)</p> <ul style="list-style-type: none"> • Input only effective in case of local control (NetCtrl=0) • For a detailed functional description see the L_RLQ FB.
		<p>FALSE Quick stop</p>
		<p>TRUE Counter-clockwise rotation</p>
nMainSetValue_a	INT	<p>Speed setpoint via fieldbus in [rpm]</p> <ul style="list-style-type: none"> • Input only effective in case of setpoint selection via fieldbus (NetRef=1) • This input is evaluated with the speed scaling set in C01353/1 (AC Drive Attribute 22). ▶ Scaling of speed and torque values • An absolute value is created internally (the sign has no meaning). • Offset and gain of this input signal can be set in C00696 and C00670 for a simple signal adjustment of a setpoint encoder. • The setpoint is transformed to a speed setpoint in the setpoint encoder via a ramp function generator with linear or S-shaped ramps. • Upstream to the ramp function generator, a blocking speed masking function and a setpoint MinMax limitation are effective. • For a detailed functional description see the L_NSet FB.
nAuxSetValue_a	INT	<p>Local speed setpoint (speed mode) or torque setpoint (torque mode)</p> <ul style="list-style-type: none"> • Input only effective in case of local setpoint selection (NetRef=0) <p>When "speed mode" is set, the following applies:</p> <ul style="list-style-type: none"> • The input value is interpreted as speed setpoint. • Scaling: $16384 \equiv 100\%$ reference speed (C00011) • Offset and gain of this input signal can be set in C00696 and C00670 for a simple signal adjustment of a setpoint encoder. • The setpoint is transformed to a speed setpoint in the setpoint encoder via a ramp function generator with linear or S-shaped ramps. • Upstream to the ramp function generator, a blocking speed masking function and a setpoint MinMax limitation are effective. • For a detailed functional description see the L_NSet FB. <p>When "torque mode" is set, the following applies:</p> <ul style="list-style-type: none"> • The input value is interpreted as torque setpoint. • (Input <i>nAuxSetValue_a</i> is internally connected to input <i>nTorqueGenLim_a</i>). • Scaling: $16384 \equiv 100\%$ M_{\max} (C00057) • The speed setpoint is internally permanently set to "100 %".
bJogSpeed1 bJogSpeed2	BOOL	<p>Selection inputs for override fixed setpoints (JOG setpoints)</p> <ul style="list-style-type: none"> • Inputs only effective in case of local setpoint selection (NetRef=0) • These selection inputs can be used to activate a fixed setpoint for the setpoint generator instead of the setpoint applied to the <i>nAuxSetValue_a</i> input. • The four selection inputs are binary coded, therefore 15 fixed setpoints can be selected. • In case of binary coded selection "0" (all inputs = FALSE or not assigned), the main setpoint applied to the <i>nAuxSetValue_a</i> input is active. • The selection of the fixed setpoints is carried out in C00039/1...15 in [%] based on the reference speed (C00011). • For a detailed functional description see the L_NSet FB.
bJogSpeed4 bJogSpeed8	BOOL	
bJogRamp1 bJogRamp2	BOOL	<p>Selection inputs for alternative acceleration/deceleration times</p> <ul style="list-style-type: none"> • The four selection inputs are binary coded, therefore 15 alternative acceleration/deceleration times can be selected. • In case of binary selection "0" (all inputs = FALSE or not assigned), the acceleration time (C00012) and deceleration time (C00013) set for the main setpoint are active. • Alternative acceleration times are selected in C00101/1...15. • The selection of the alternative deceleration times is carried out in C00103/1...15. • For a detailed functional description see the L_NSet FB.
bJogRamp4 bJogRamp8	BOOL	

Identifier	Data type	Information/possible settings	
Motor potentiometer Alternatively to the input signal <i>nMainSetValue_a</i> (or <i>nAuxSetValue_a</i> in case of local setpoint selection), the speed setpoint can also be generated via a motor potentiometer function. <ul style="list-style-type: none">• In the Lenze setting, the motor potentiometer function is deactivated.• Activation is possible via C00806 or via the <i>bMPotEnable</i> input.• The behaviour of the motor potentiometer during switch-on of the drive system can be selected in C00805.• For a detailed functional description see the L_MPot FB.			
bMPotEnable	BOOL	Activating the motor potentiometer function <ul style="list-style-type: none">• This input and C00806 are OR'd.	
		TRUE	The motor potentiometer function is active; the speed setpoint can be changed via the <i>bMPotUp</i> and <i>bMPotDown</i> control inputs.
bMPotUp	BOOL	Increasing the speed setpoint	
		TRUE	Approach the upper speed limit value set in C00800 with the acceleration time set in C00802 .
bMPotInAct	BOOL	Activating the inactive function	
		TRUE	The speed setpoint behaves according to the inactive function set in C00804 . <ul style="list-style-type: none">• In the Lenze setting, the speed setpoint is maintained.
bMPotDown	BOOL	Decreasing the speed setpoint	
		TRUE	Approach the lower speed limit value set In C00801 with the deceleration time set in C00803 .
Process controller <ul style="list-style-type: none">• In the Lenze setting, the process controller is deactivated.• The activation is executed by selecting the operating mode in C00242.• For a detailed functional description see FB L_PCTRL.			
bPIDEnableInfluenceRamp	BOOL	Activate ramp for influencing factor	
		FALSE	Influencing factor of the PID controller is ramped down to "0".
		TRUE	Influencing factor of the PID controller is ramped up to the value <i>nPIDInfluence_a</i> .
bPIDIOff	BOOL	Switch off the I-component of the process controller <ul style="list-style-type: none">• In conjunction with the operating mode set in C00242 (Lenze setting: "Off").	
		TRUE	I-component of the process controller is switched off.
nPIDVpAdapt_a	INT	Adaptation of gain Vp set in C00222 in percent <ul style="list-style-type: none">• Scaling: 16384 \equiv 100 %• Internal limitation to ± 199.99 %• Changes can be done online.	
nPIDSetValue_a	INT	Sensor and process setpoint for operating modes 2, 4 and 5 <ul style="list-style-type: none">• Scaling: 16384 \equiv 100 %• Internal limitation to ± 199.99 %	
nPIDActValue_a	INT	Speed or actual sensor value (actual process value) <ul style="list-style-type: none">• Offset and gain for this input signal can be set in C00698 and C00672.• Scaling: 16384 \equiv 100 %• Internal limitation to ± 199.99 %	
nPIDInfluence_a	INT	Limitation of the influencing factor in percent <ul style="list-style-type: none">• The influence factor of the PID controller can be limited to a certain value (-199.99% ... +199.99%) via <i>nPIDInfluence_a</i>.• Scaling: 16384 \equiv 100 %• Internal limitation to ± 199.99 %	

Identifier	Data type	Information/possible settings	
MCK basic functions			
bMBrakeRelease	BOOL	Holding brake control : Release/apply brake <ul style="list-style-type: none">In conjunction with the operating mode selected in C02580 (Lenze setting: "Brake control off").	
		FALSE	Apply brake. <ul style="list-style-type: none">During automatic operation, the internal brake logic controls the brake.
		TRUE	Release brake manually (forced release). <ul style="list-style-type: none">Note! The brake can also be released if the controller is inhibited!During automatic operation, the internal brake logic is deactivated and the brake is released (supervisor operation). If a controller inhibit has been set by the brake control, it will be deactivated.In semi-automatic operation, the brake is released including feedforward control.
GP: GeneralPurpose The following inputs are interconnected with logic/arithmetic functions on application level for free usage. ▶ "GeneralPurpose" functions			
bGPFree1 ... bGPFree2	BOOL	Free inputs for digital signals <ul style="list-style-type: none">Digital signals can be transferred from the I/O level to the application level via these inputs.	
nGPAnalogSwitchIn1_a nGPAnalogSwitchIn2_a	INT	Analog switch : Input signals <ul style="list-style-type: none">The input signal selected via the selection input <i>bGPAnalogSwitchSet</i> is output at output <i>nGPAnalogSwitchOut_a</i>.	
bGPAnalogSwitchSet	BOOL	Analog switch : Selection input	
		FALSE	<i>nGPAnalogSwitchOut_a</i> = <i>nGPAnalogSwitchIn1_a</i>
		TRUE	<i>nGPAnalogSwitchOut_a</i> = <i>nGPAnalogSwitchIn2_a</i>
nGPArithmetikIn1_a nGPArithmetikIn2_a	INT	Arithmetic : Input signals <ul style="list-style-type: none">The arithmetic function is selected in C00338.The result is output at output <i>nGPArithmetikOut_a</i>.	
nGPMulDivIn_a	INT	Multiplication/Division : Input signal <ul style="list-style-type: none">The factor for the multiplication can be set in C00699/1 (numerator) and C00699/2 (denominator).The result is output at output <i>nGPMulDivOut_a</i>.	
bGPDigitalDelayIn	BOOL	Binary delay element : Input signal <ul style="list-style-type: none">The on-delay can be set in C00720/1.The off-delay can be set in C00720/2.The time-delayed input signal is output at output <i>bGPDigitalDelayOut</i>.	
bGPLogicIn1 bGPLogicIn2 bGPLogicIn3	BOOL	Binary logic : Input signals <ul style="list-style-type: none">The logic operation is selected in C00820.The result is output at output <i>bGPLogicOut</i>.	
nGPCompareIn1_a nGPCompareIn2_a	INT	Analog comparison : Input signals <ul style="list-style-type: none">The comparison operation is selected in C00680.Hysteresis and window size can be set in C00680 and C00682.If the comparison statement is true, the output <i>bGPCompareOut</i> will be set to TRUE.	
bGPDFlipFlop_InD bGPDFlipFlop_InClk bGPDFlipFlop_InClr	BOOL	D-FlipFlop : Input signals <ul style="list-style-type: none">Data, clock and reset input	

Identifier	Data type	Information/possible settings
Free inputs The following inputs can freely be interconnected on the application level. The signals can be transferred from the I/O level to the application level via these inputs.		
bFreeIn1 ... bFreeIn8	BOOL	Free inputs for digital signals
wFreeIn1 ... wFreeIn4	WORD	Free inputs for 16-bit signals

Outputs

Identifier	Data type	Value/meaning
wDriveControlStatus	WORD	AC Drive Profile status word <ul style="list-style-type: none"> The status word contains information on the currents status of the drive controller. For a detailed description of the individual status bits, see subchapter entitled "Process data assignment for fieldbus communication". Display parameter: C01352/1
wStateDetermFailNoLow	WORD	Display of the status determining error (LOW word)
wStateDetermFailNoHigh	WORD	Display of the status determining error (HIGH word)
bDriveFail	BOOL	TRUE Drive controller in error status. <ul style="list-style-type: none"> "Fault" device status is active.
bDriveReady	BOOL	TRUE Controller is ready for operation. <ul style="list-style-type: none"> "SwitchedOn" device status is active. The drive is in this device status if the DC bus voltage is applied and the controller is still inhibited by the user (controller inhibit).
bClnhActive	BOOL	TRUE Controller inhibit is active.
bQSPLsActive	BOOL	TRUE Quick stop is active.
bSpeedCcw	BOOL	Current direction of rotation
		FALSE Clockwise rotation (Cw)
		TRUE Direction of rotation to the left (Ccw)
bSpeedActCompare	BOOL	Result of the speed comparison (detection of speed=0)
		TRUE During open-loop operation: Speed setpoint < Comparison value (C00024)
		During closed-loop operation: Actual speed value < Comparison value (C00024)
bOverLoadActive	BOOL	In preparation (output is not interconnected on the application level)
bUnderLoadActive	BOOL	In preparation (output is not interconnected on the application level)
blmaxActive	BOOL	"Current setpoint inside the limitation" status signal
		TRUE The current setpoint is internally limited (the drive controller operates at the maximum current limit).
bSpeedSetReached	BOOL	Status signal "setpoint = 0"
		TRUE Speed setpoint from the ramp function generator = 0
bSpeedActEqSet	BOOL	TRUE Actual speed value = speed setpoint
nMotorCurrent_a	INT	Current stator current/effective motor current <ul style="list-style-type: none"> Scaling: $16384 \equiv 100\% I_{\max_mot}$ (C00022)

Identifier	Data type	Value/meaning	
nMotorSpeedSet_a	INT	Speed setpoint <ul style="list-style-type: none">Scaling: 16384 \equiv 100 % reference speed (C00011)	
nMotorSpeedAct_a	INT	Actual speed value <ul style="list-style-type: none">Scaling: 16384 \equiv 100 % reference speed (C00011)The absolute value is output (the sign has no meaning).	
nMotorTorqueAct_a	INT	Actual torque <ul style="list-style-type: none">In the "VFC (+encoder)" operating mode of the motor control, this value is determined from the current motor current and corresponds to the actual torque only by approximation.Scaling: 16384 \equiv 100 % M_{\max} (C00057)The absolute value is output (the sign has no meaning).	
nDCVoltage_a	INT	Actual DC-bus voltage <ul style="list-style-type: none">Scaling: 16384 \equiv 1000 V	
nMotorVoltage_a	INT	Current motor voltage/inverter output voltage <ul style="list-style-type: none">Scaling: 16384 \equiv 1000 V	
MCK basic functions			
bMBrakeReleaseOut	BOOL	Holding brake control : Trigger signal for the holding brake control switching element via a digital output <ul style="list-style-type: none">Use bit 0 in C02582 to activate inverted switching element triggering.	
		FALSE	Apply brake.
		TRUE	Release brake.
bMBrakeReleased	BOOL	Holding brake control : "Brake released" considering the brake release time <ul style="list-style-type: none">When the holding brake is triggered to close, <i>bMBrakeReleased</i> is immediately set to FALSE even if the brake closing time has not yet elapsed!	
		TRUE	Brake released (after the brake release time has expired).
GP: GeneralPurpose The following outputs are interconnected with logic/arithmetic functions on application level for free usage. ▶ "GeneralPurpose" functions			
nGPAAnalogSwitchInOut_a	INT	Analog switch : Output signal	
nGPArithmetikOut_a	INT	Arithmetic : Output signal	
nGPMulDivOut_a	INT	Multiplication/Division : Output signal	
bGPDigitalDelayOut	BOOL	Binary delay element : Output signal	
bGPLogicOut	BOOL	Binary logic : Output signal	
bGPCompareOut	BOOL	Analog comparison : Output signal	
bGPSignalOut1 ... bGPSignalOut4	BOOL	Binary signal monitor : Output signals <ul style="list-style-type: none">The signal sources to be output are selected in C00411/1...4.A bit coded inversion of the output signals can be parameterised in C00412.	
nGPSignalOut1_a ... nGPSignalOut4_a	BOOL	Analog signal monitor : Output signals <ul style="list-style-type: none">The signal sources to be output are selected in C00410/1...4.Gain and offset for each output signal can be parameterised in C00413/1...8.	
bGPDFlipFlop_Out	BOOL	D-FlipFlop : Output signal	
bGPDFlipFlop_NegOut	BOOL	D-FlipFlop : Negated output signal	

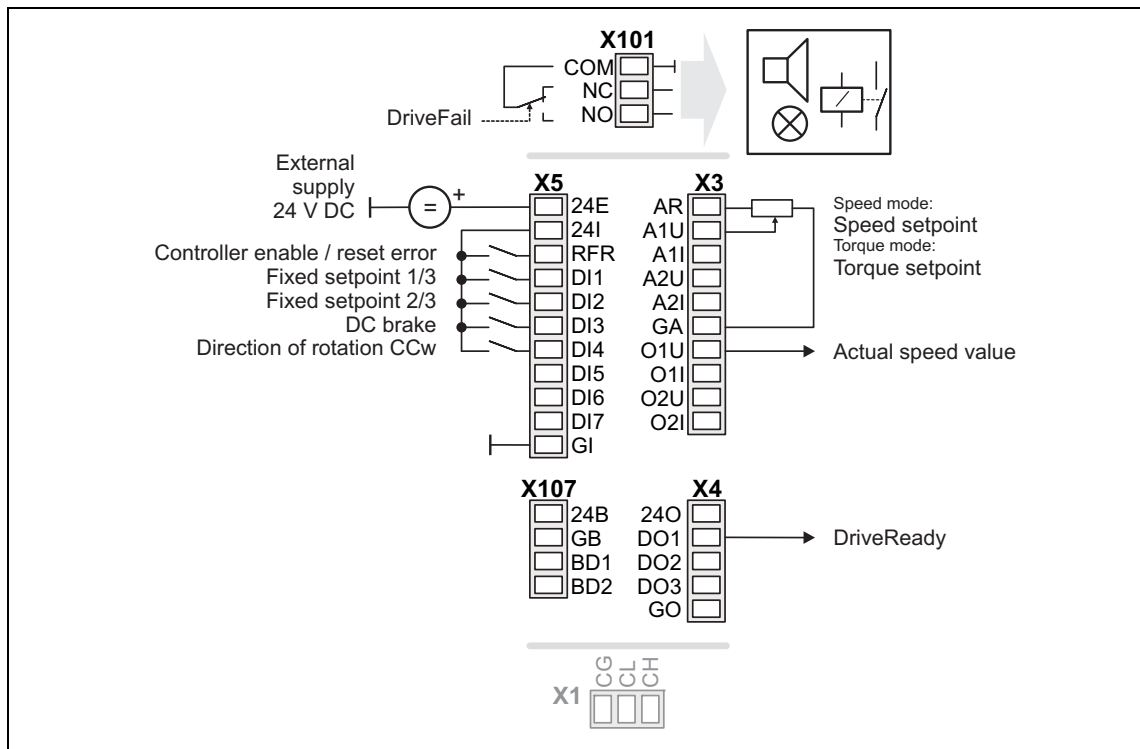
Identifier	Data type	Value/meaning
Free outputs The following outputs can freely be interconnected on the application level. The signals from the application level can be transferred to the I/O level via these outputs.		
bFreeOut1 ... bFreeOut8	BOOL	Free outputs for digital signals
wFreeOut1 ... wFreeOut4	WORD	Free outputs for 16-bit signals

8.3.4 Terminal assignment of the control modes

The following comparison provides information about which inputs/outputs of the application block **LA_NCtrl** are interconnected to the digital and analog input/output terminals of the drive controller in the different control modes.

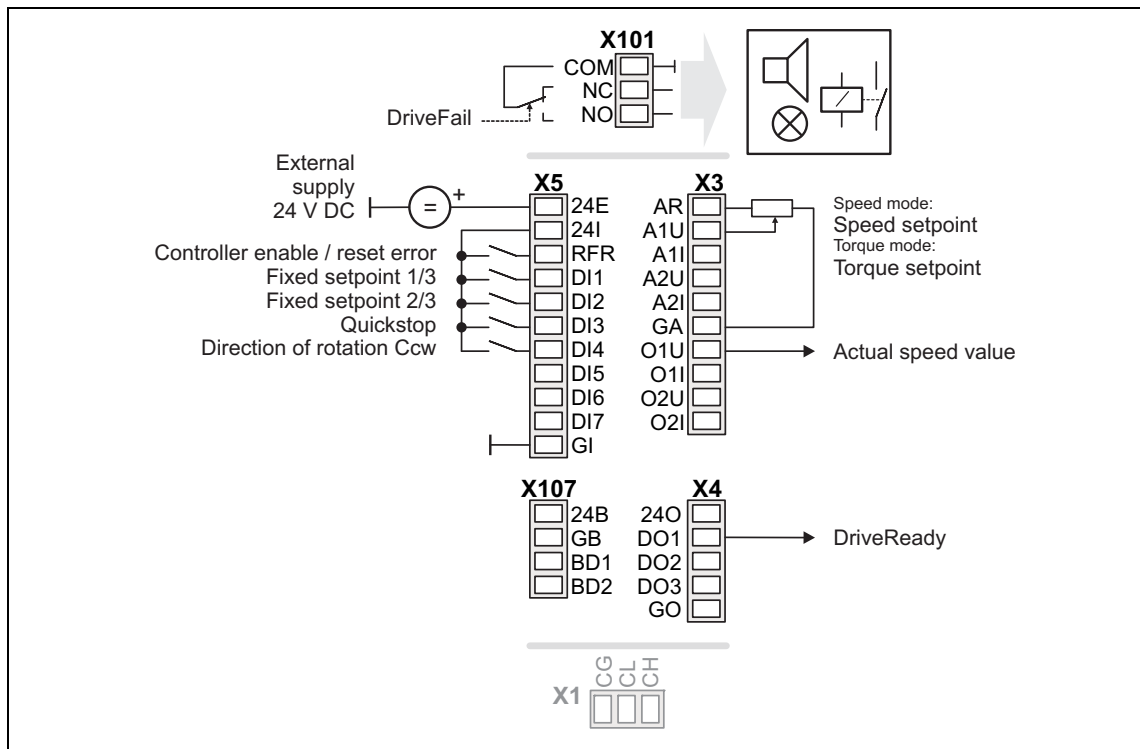
	Control mode (C00007)							
	10: Terminals 0	12: Terminals 2	14: Terminals 11	16: Terminal 16	20: Keypad	21: PC	30: CAN	40: MCI
Digital input terminals								
X5/RFR	Controller enable / Reset of error message bFailReset							
X5/DI1	Fixed setpoint 1/3 bJogSpeed1		Change of direction of rotation bSetSpeedCcw	Fixed setpoint 1/3 bJogSpeed1	-	-	Only if NetCtrl=0: fixed setpoint 1/3 bJogSpeed1	
X5/DI2	Fixed setpoint 2/3 bJogSpeed2		Activate manual DC-injection braking (DCB) bSetDCBrake	Fixed setpoint 2/3 bJogSpeed2	-	-	Only if NetCtrl=0: fixed setpoint 2/3 bJogSpeed2	
X5/DI3	Activate manual DC-injection braking (DCB) bSetDCBrake	Quick stop bSetQuickstop	Motor potentiometer: Increase speed bMPotUp	CW rotation quick stop bRLQCw	-	-	Only if NetCtrl=0: Activate manual DC-injection braking (DCB) bSetDCBrake	
X5/DI4	Change of direction of rotation bSetSpeedCcw		Motor potentiometer: Decrease speed bMPotDown	CCW rotation quick stop bRLQCcw	-	-	Only if NetCtrl=0: change of direction of rotation bSetSpeedCcw	
X5/DI5 ... DI7	-	-	-	-	-	-	-	-
Analog input terminals								
X3/A1U, A1I	Local setpoint nAuxSetValue_a Speed mode: 10 V ≡ 100 % reference speed (C00011) Torque mode: 10 V ≡ 100 % M _{max} (C00057); speed setpoint = 100 % (fixed)				-	-	Only if NetRef=0: Local setpoint nAuxSetValue_a Speed mode: 10 V ≡ 100 % reference speed (C00011) Torque mode: 10 V ≡ 100 % M _{max} (C00057)	
X3/A2U, A2I	-	-	-	-	-	-	-	-
Digital output terminals								
X4/DO1	Status "Drive is ready" bDriveReady							
X4/DO2 ... DO3	-	-	-	-	-	-	-	-
X107/BD1, BD2	-	-	-	-	-	-	-	-
X101/COM, NO	Status "Error is pending" bDriveFail							
Analog output terminals								
X3/O1U	Actual speed value nMotorSpeedAct_a 10 V ≡ 100 % reference speed (C00011)							
X3/O1I	-	-	-	-	-	-	-	-
X3/O2U								
X3/O2I								

8.3.4.1 Terminals 0



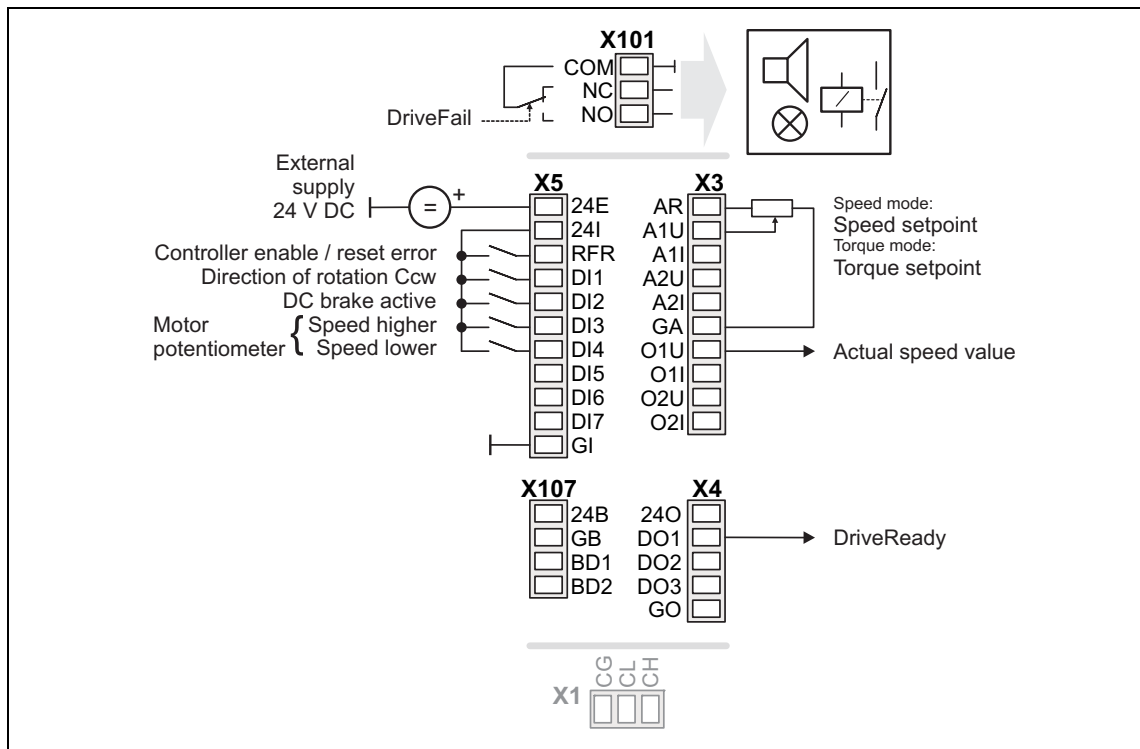
Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	LA_NCtrl.nAuxSetValue_a *
X5/DI1	LA_NCtrl.bJogSpeed1	X3/A1I	-
X5/DI2	LA_NCtrl.bJogSpeed2	X3/A2U	-
X5/DI3	LA_NCtrl.bSetDCBrake	X3/A2I	-
X5/DI4	LA_NCtrl.bSetSpeedCcw	X3/O1U	LA_NCtrl.nMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
		* 10 V ≙ 100 % reference speed (C00011)	
X107/BD1	-	X4/DO1	LA_NCtrl.bDriveReady
X107/BD2	-	X4/DO2	-
		X4/DO3	-

8.3.4.2 Terminals 2



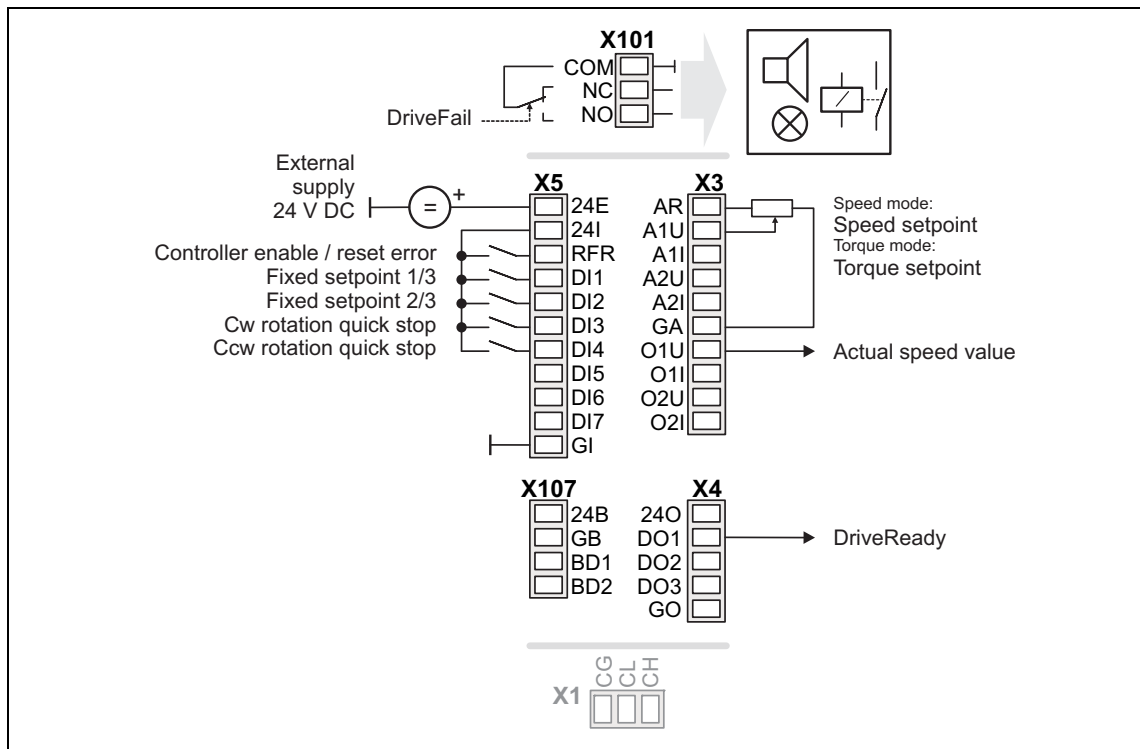
Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	LA_NCtrl.nAuxSetValue_a *
X5/DI1	LA_NCtrl.bJogSpeed1	X3/A1I	-
X5/DI2	LA_NCtrl.bJogSpeed2	X3/A2U	-
X5/DI3	LA_NCtrl.bSetQuickstop	X3/A2I	-
X5/DI4	LA_NCtrl.bSetSpeedCcw	X3/O1U	LA_NCtrl.nMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
		* 10 V ≙ 100 % reference speed (C00011)	
X107/BD1	-	X4/DO1	LA_NCtrl.bDriveReady
X107/BD2	-	X4/DO2	-
		X4/DO3	-

8.3.4.3 Terminals 11



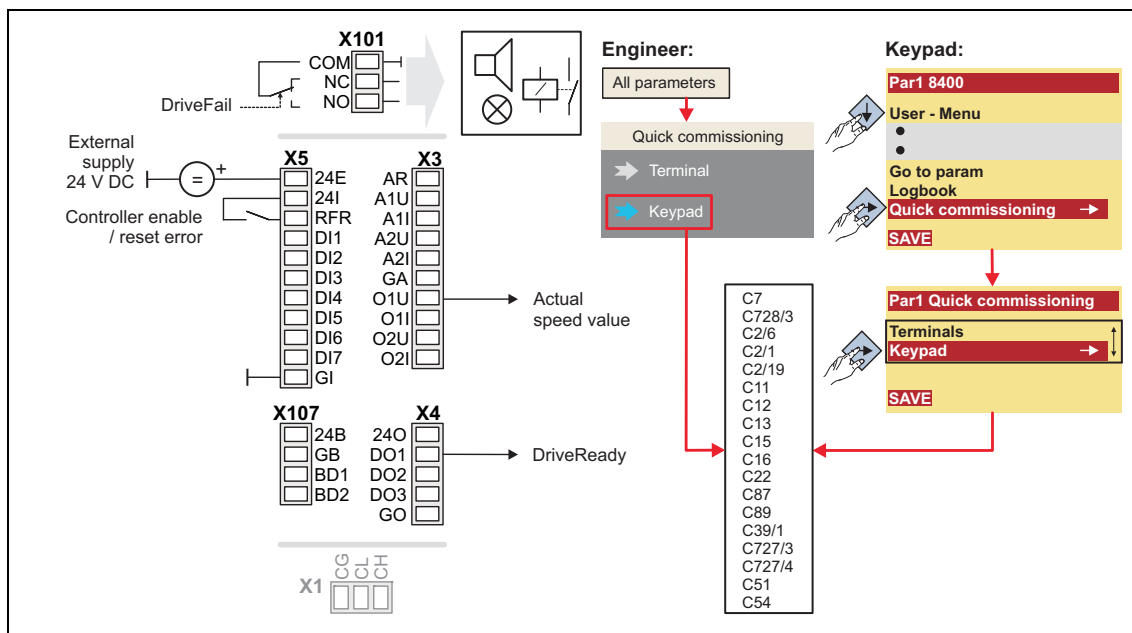
Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	LA_NCtrl.nAuxSetValue_a *
X5/DI1	LA_NCtrl.bSetSpeedCcw	X3/A1I	-
X5/DI2	LA_NCtrl.bSetDCBrake	X3/A2U	-
X5/DI3	LA_NCtrl.bMPotUp	X3/A2I	-
X5/DI4	LA_NCtrl.bMPotDown	X3/O1U	LA_NCtrl.nMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
		* 10 V ≙ 100 % reference speed (C00011)	
X107/BD1	-	X4/DO1	LA_NCtrl.bDriveReady
X107/BD2	-	X4/DO2	-
		X4/DO3	-

8.3.4.4 Terminal 16



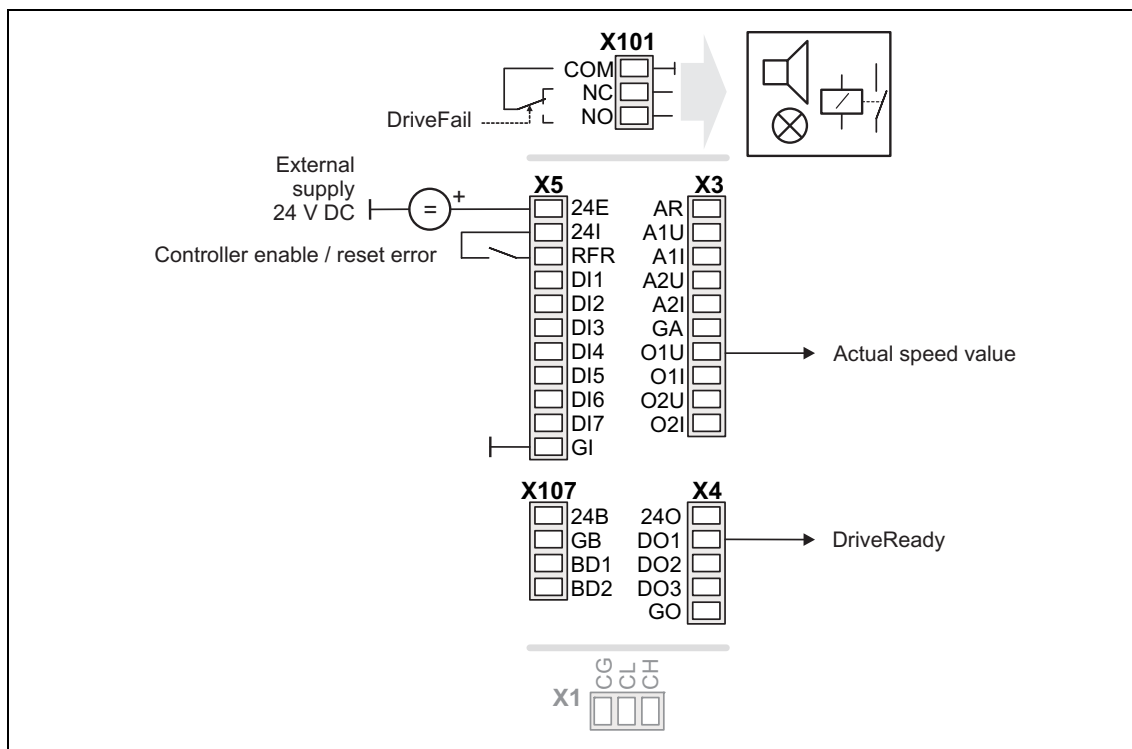
Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	LA_NCtrl.nAuxSetValue_a *
X5/DI1	LA_NCtrl.bJogSpeed1	X3/A1I	-
X5/DI2	LA_NCtrl.bJogSpeed2	X3/A2U	-
X5/DI3	LA_NCtrl.bRLQCw	X3/A2I	-
X5/DI4	LA_NCtrl.bRLQCcw	X3/O1U	LA_NCtrl.nMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
			* 10 V ≡ 100 % reference speed (C00011)
X107/BD1	-	X4/DO1	LA_NCtrl.bDriveReady
X107/BD2	-	X4/DO2	-
		X4/DO3	-

8.3.4.5 Keypad



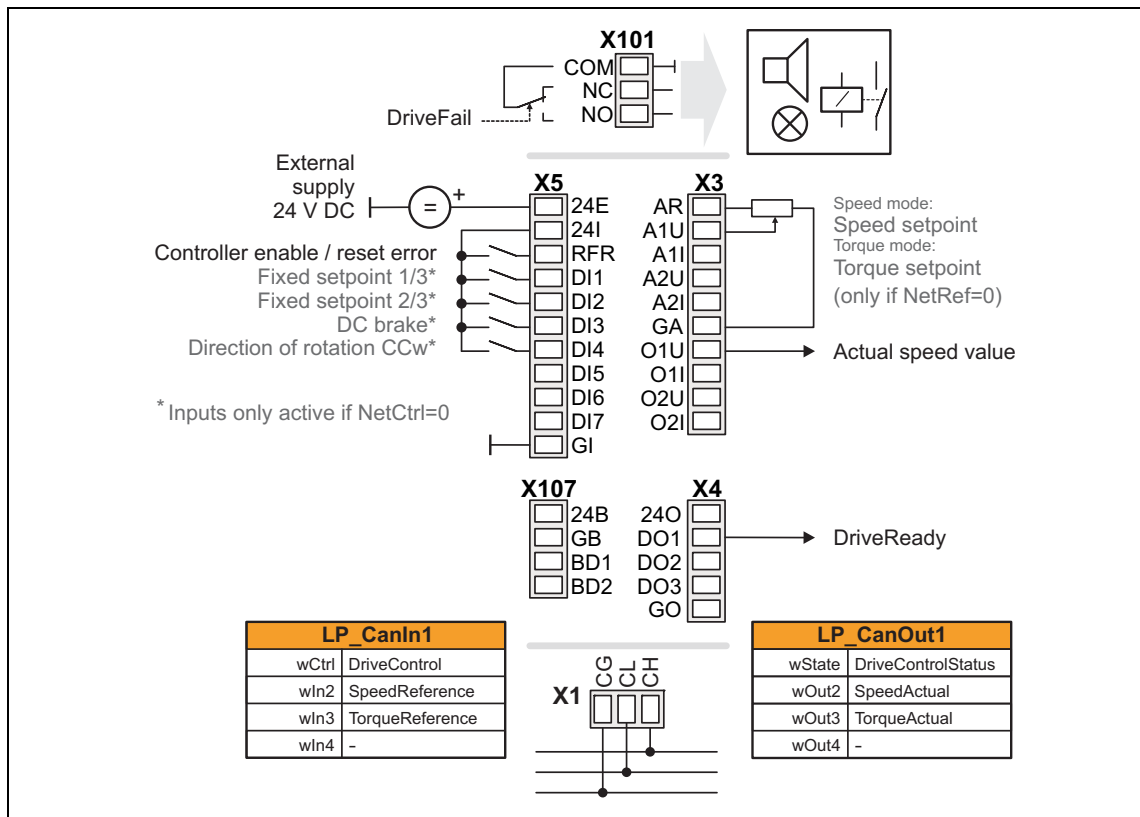
Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	-
X5/DI1	-	X3/A1I	-
X5/DI2	-	X3/A2U	-
X5/DI3	-	X3/A2I	-
X5/DI4	-	X3/O1U	LA_NCtrl.nMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
		* 10V ≙ 100% of reference speed (C00011)	
X107/BD1	-	X4/DO1	LA_NCtrl.bDriveReady
X107/BD2	-	X4/DO2	-
		X4/DO3	-

8.3.4.6 PC



Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	-
X5/DI1	-	X3/A1I	-
X5/DI2	-	X3/A2U	-
X5/DI3	-	X3/A2I	-
X5/DI4	-	X3/O1U	LA_NCtrl.nMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
		* 10V ≙ 100% of reference speed (C00011)	
X107/BD1	-	X4/DO1	LA_NCtrl.bDriveReady
X107/BD2	-	X4/DO2	-
		X4/DO3	-

8.3.4.7 CAN

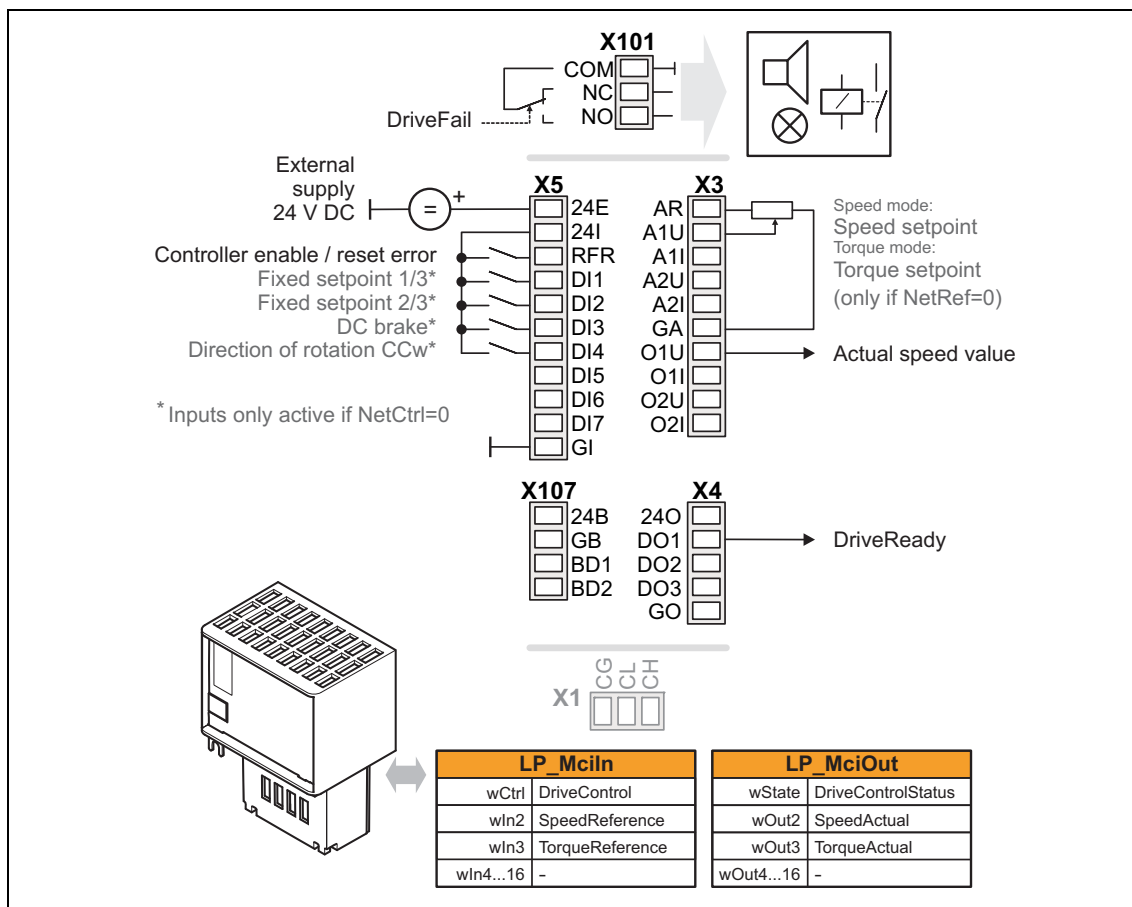


Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	LA_NCtrl.nAuxSetValue_a *
X5/DI1	LA_NCtrl.bJogSpeed1	X3/A1I	-
X5/DI2	LA_NCtrl.bJogSpeed2	X3/A2U	-
X5/DI3	LA_NCtrl.bSetDCBrake	X3/A2I	-
X5/DI4	LA_NCtrl.bSetSpeedCcw	X3/O1U	LA_NCtrl.NMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
		* 10V ≙ 100% of reference speed (C00011)	
X107/BD1	-	X4/DO1	LA_NCtrl.bDriveReady
X107/BD2	-	X4/DO2	-
		X4/DO3	-

► [Process data assignment for fieldbus communication](#) (450)

8.3.4.8

MCI



Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_NCtrl.bDriveFail		
X5/RFR	LA_NCtrl.bFailReset	X3/A1U	LA_NCtrl.nAuxSetValue_a *
X5/DI1	LA_NCtrl.bJogSpeed1	X3/A1I	-
X5/DI2	LA_NCtrl.bJogSpeed2	X3/A2U	-
X5/DI3	LA_NCtrl.bSetDCBrake	X3/A2I	-
X5/DI4	LA_NCtrl.bSetSpeedCcw	X3/O1U	LA_NCtrl.nMotorSpeedAct_a *
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
		* 10V ≙ 100% of reference speed (C00011)	
X107/BD1	-	X4/DO1	LA_NCtrl.bDriveReady
X107/BD2	-	X4/DO2	-
		X4/DO3	-

► [Process data assignment for fieldbus communication \(480\)](#)

8.3.5 Process data assignment for fieldbus communication

The fieldbus communication is connected (preconfigured) to the previously selected technology application by selecting the corresponding control mode in [C00007](#):

- "30: [CAN](#)" for the connection to the system bus (CAN)
- "40: [MCI](#)" for the connection to a plugged-in communication module (e.g. EtherNet/IP™)

The assignment of the process data words depends only on the application, not on the bus system used:

Input words	Name	Assignment
Word 1	DriveControl	Control word <ul style="list-style-type: none"> • For bit assignment see the table below. • Display parameter: C01351/1
Word 2	SpeedReference	Speed setpoint in [rpm] <ul style="list-style-type: none"> ▶ Scaling of speed and torque values
Word 3	TorqueReference	Torque setpoint in [Nm] <ul style="list-style-type: none"> ▶ Scaling of speed and torque values
Word 4	-	Not preconfigured
Words 5 ... 16	-	Not preconfigured <ul style="list-style-type: none"> • Only available in control mode "40: MCI".

Control word	Name	Function
Bit 0	Run Forward	Relationships between Run1 and Run2 and trigger events can be found in the chapter " Run/Stop event ".
Bit 1	Run Backward	
Bit 2	Fault Reset	071 ≡ Reset error 0 ≡ No response
Bit 3	Reserved	-
Bit 4	Reserved	-
Bit 5	NetCtrl	Run/Stop control: 0 ≡ via local setting in the device or terminal 1 ≡ via fieldbus (e.g. by the scanner)
Bit 6	NetRef	Reference speed/reference torque: 0 ≡ via local setting in the device or terminal 1 ≡ via fieldbus (e.g. by the scanner)
Bit 7 ... 15	Reserved	-

Output words	Name	Assignment
Word 1	DriveControlStatus	Status word <ul style="list-style-type: none"> • For bit assignment see the table below. • Display parameter: C01352/1
Word 2	SpeedActual	Actual speed value in [rpm] <ul style="list-style-type: none"> ▶ Scaling of speed and torque values
Word 3	TorqueActual	Actual torque in [Nm] <ul style="list-style-type: none"> ▶ Scaling of speed and torque values
Word 4	-	Not preconfigured
Words 5 ... 16	-	Not preconfigured <ul style="list-style-type: none"> • Only available in control mode "40: MCI".

Status word	Name	Status
Bit 0	Faulted	0 ≡ No errors 1 ≡ Errors have occurred
Bit 1	Warning	0 ≡ No warnings 1 ≡ Warnings have occurred
Bit 2	Running1 (Fwd)	Relationships between Run1 and Run2 and trigger events can be found in the chapter " Run/Stop event ".
Bit 3	Running2 (Rev)	
Bit 4	Ready	0 ≡ Different status than in case of "1" 1 ≡ Ready or Enabled or Stopping
Bit 5	Ctrl from Net	Run/Stop control: 0 ≡ via local setting in the device or terminal 1 ≡ via fieldbus (e.g. by the scanner)
Bit 6	Ref from Net	Reference speed/reference torque: 0 ≡ via local setting in the device or terminal 1 ≡ via fieldbus (e.g. by the scanner)
Bit 7	At Reference	1 ≡ The drive currently runs with reference speed (speed mode) or reference torque (Torque mode)
Bit 8	Drive State	The "Drive State" is coded as follows: 0: Manufacturer-specific (not used with 8400) 1: Start-up (drive initialisation) 2: Not_Ready (mains voltage switched off) 3: Ready (mains voltage switched-on) 4: Enabled (drive has received "Run" command) 5: Stopping (drive has received "Stop" command and is stopped) 6: Fault_Stop (drive is stopped due to an error) 7: Faulted (errors have occurred)
Bit 9	Drive State	
Bit 10	Drive State	
Bit 11	Drive State	
Bit 12	Drive State	
Bit 13	Drive State	
Bit 14	Drive State	
Bit 15	Drive State	

8.3.5.1 Run/Stop event

Relationships between Run1 and Run2:

	Contactor	Starter	Starter Reverser	Speed	Soft start	Drive
Run1	Close	Run	RunFwd	RunLow	RunRamp1	RunFwd
Run2	No Action	No Action	RunRev	RunHigh	RunRamp2	RunRev

Run1 and Run2 trigger:

Run1	Run2	Trigger event	Run type
0	0	Stop	No Action
0 → 1	0	Run	Run1
0	0 → 1	Run	Run2
0 → 1	0 → 1	No Action	No Action
1	1	No Action	No Action
1 → 0	1	Run	Run2
1	1 → 0	Run	Run1

8.3.5.2 Scaling of speed and torque values

Scaling of the speed values

The speed setpoint is defined by the bus in [rpm]. The conversion then takes place in the controller as all speed-related signals are processed to a reference variable in percent. An adjustable scaling factor serves to make an additional scaling.

Equation for scaling the speed setpoint		
$\text{Speed setpoint}_{\text{Application}} = \text{Speed setpoint}_{\text{Bus}}[\text{rpm}] \cdot \frac{16384}{\text{Reference speed}[\text{rpm}]} \cdot \frac{1}{2^{\text{Scaling factor}}}$		
Parameter	Name	Description
C00011	Appl.: Reference speed	Reference variable for speed-related signals
C01353/1	ACDrive: Speed scaling	In the Lenze setting "0", no scaling takes place ($2^0 = 1$)

For the output of the actual speed value to the bus, the following conversion is made:

Equation for scaling the actual speed value		
$\text{Actual speed value}_{\text{Bus}}[\text{rpm}] = \text{Actual speed value}_{\text{Application}} \cdot \frac{\text{Reference speed}[\text{rpm}]}{16384} \cdot 2^{\text{Scaling factor}}$		
Parameter	Name	Description
C00011	Appl.: Reference speed	Reference variable for speed-related signals
C01353/1	ACDrive: Speed scaling	In the Lenze setting "0", no scaling takes place ($2^0 = 1$)

Scaling of the torque values

The torque setpoint is defined by the bus in [Nm]. The conversion then takes place in the controller as all torque-related signals are processed to a reference variable in percent. An adjustable scaling factor serves to make an additional scaling.

Equation for scaling the torque setpoint		
$\text{Torque setpoint}_{\text{Application}} = \text{Torque setpoint}_{\text{Bus}}[\text{Nm}] \cdot \frac{16384 \cdot 100}{\text{Maximum torque}[0.01 \text{ Nm}]} \cdot \frac{1}{2^{\text{Scaling factor}}}$		
Parameter	Name	Description
C00057	Maximum torque	Reference variable for torque-related signals
C01353/2	ACDrive: Torque scaling	In the Lenze setting "0", no scaling takes place ($2^0 = 1$)

For the output of the actual torque value to the bus, the following conversion is made:

Equation for scaling the actual torque		
$\text{Actual torque}_{\text{Bus}}[\text{Nm}] = \text{Actual torque}_{\text{Application}} \cdot \frac{\text{Maximum torque}[0.01 \text{ Nm}]}{16384 \cdot 100} \cdot 2^{\text{Scaling factor}}$		
Parameter	Name	Description
C00057	Maximum torque	Reference variable for torque-related signals
C01353/2	ACDrive: Torque scaling	In the Lenze setting "0", no scaling takes place ($2^0 = 1$)

8.3.6 AC Drive Profile diagnostic parameters

In the **All parameters** tab, the parameters for diagnostic purposes listed in the following table are displayed in the **AC Drive Profile** category.



Note!

These parameter are set by the EtherNet/IP™ communication module and should not be written by the user.

Parameter	Info	Lenze setting
C01350/1	ACDrive: DriveMode	1: Speed mode
C01351/1	ACDrive: Control word	-
C01352/1	ACDrive: Status word	-
C01353/1	ACDrive: Speed scaling	0
C01353/2	ACDrive: Torque scaling	0
Highlighted in grey = display parameter		

8.3.7 Setting parameters (short overview)

Parameter	Info	Lenze setting	
		Value	Unit
C00012	Accel. time - main setpoint	2.000	s
C00013	Decel. time - main setpoint	2.000	s
C00019	Auto-DCB: Threshold	3	rpm
C00024	LS_DriveInterface: bNActCompare	0.00	%
C00036	DCB braking: Current	50.00	%
C00039/1	Fixed setpoint 1	40.00	%
C00039/2	Fixed setpoint 2	60.00	%
C00039/3	Fixed setpoint 3	80.00	%
C00039/4...15	Fixed setpoint 4 ... 15	0.00	%
C00101/1...15	Add. accel. time 1 ... 15	0.000	s
C00103/1...15	Add. decel. time 1 ... 15	0.000	s
C00105	Decel. time - quick stop	2.000	s
C00106	Auto-DCB: Hold time	0.500	s
C00107	DCB braking: Hold time	999.000	s
C00134	L_NSet_1: Ramp smoothing	0: Off	
C00182	L_NSet_1: S-ramp time PT1	20.00	s
C00190	L_NSet_1: Setpoint arithmetic	0: Out = Set	
C00220	L_NSet_1: Acceleration time - add. setpoint	0.000	s
C00221	L_NSet_1: Deceleration time - add. setpoint	0.000	s
C00222	L_PCTRL_1: Vp	1.0	
C00223	L_PCTRL_1: Tn	400	ms
C00224	L_PCTRL_1: Kd	0.0	

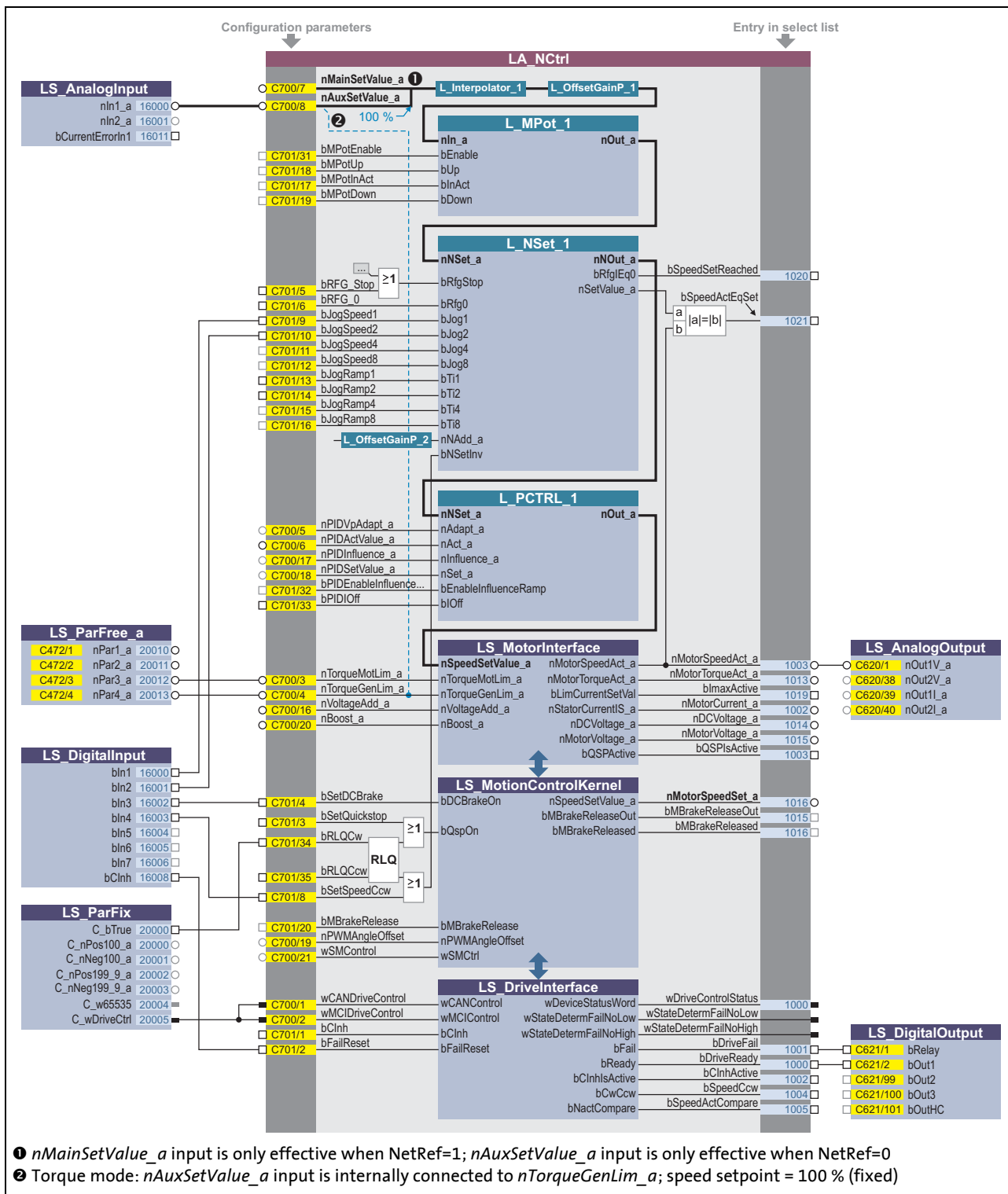
Parameter	Info	Lenze setting	
		Value	Unit
C00225	L_PCTRL_1: MaxLimit	199.99	%
C00226	L_PCTRL_1: MinLimit	-199.99	%
C00227	L_PCTRL_1: Acceleration time	0.010	s
C00228	L_PCTRL_1: Deceleration time	0.010	s
C00233	L_PCTRL_1: Root function	0: Off	
C00241	L_NSet_1: Hyst. NSet reached	0.50	%
C00242	Operating mode of process controller	0: Off	
C00243	L_PCTRL_1: Accel. time influence	5.000	s
C00244	L_PCTRL_1: Deceleration time influence	5.000	s
C00632/1	L_NSet_1: Blocking speed 1 max	0.00	%
C00632/2	L_NSet_1: Blocking speed 2 max	0.00	%
C00632/3	L_NSet_1: Blocking speed 3 max	0.00	%
C00633/1	L_NSet_1: Blocking speed 1 min	0.00	%
C00633/2	L_NSet_1: Blocking speed 2 min	0.00	%
C00633/3	L_NSet_1: Blocking speed 3 min	0.00	%
C00635	L_NSet_1: nMaxLimit	199.99	%
C00636	L_NSet_1: nMinLimit	-199.99	%
C00670	L_OffsetGainP_1: Gain	1.0000	
C00671	L_OffsetGainP_2: Gain	1.0000	
C00672	L_OffsetGainP_3: Gain	1.0000	
C00696	L_OffsetGainP_1: Offset	0.00	%
C00697	L_OffsetGainP_2: Offset	0.00	%
C00698	L_OffsetGainP_3: Offset	0.00	%
C00800	L_MPot_1: Upper limit	100.00	%
C00801	L_MPot_1: Lower limit	-100.00	%
C00802	L_MPot_1: Acceleration time	10.0	s
C00803	L_MPot_1: Deceleration time	10.0	s
C00804	L_MPot_1: Inactive fct.	0: Retain value	
C00805	L_MPot_1: Init fct.	0: Load last value	
C00806	Use of motor potentiometer	0: No	

Related topics:

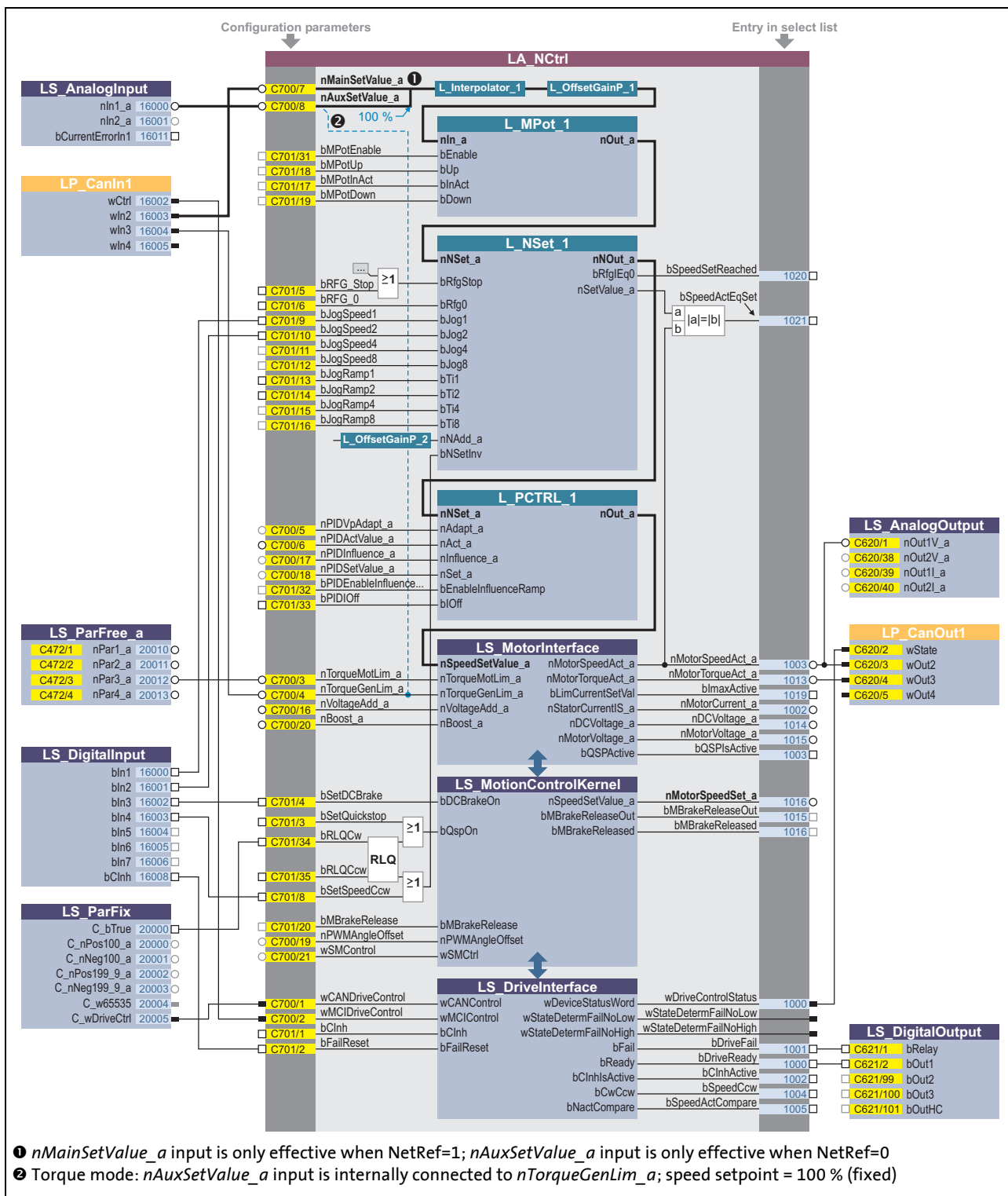
► ["GeneralPurpose" functions](#) (📖 546)

8.3.8 Configuration parameters

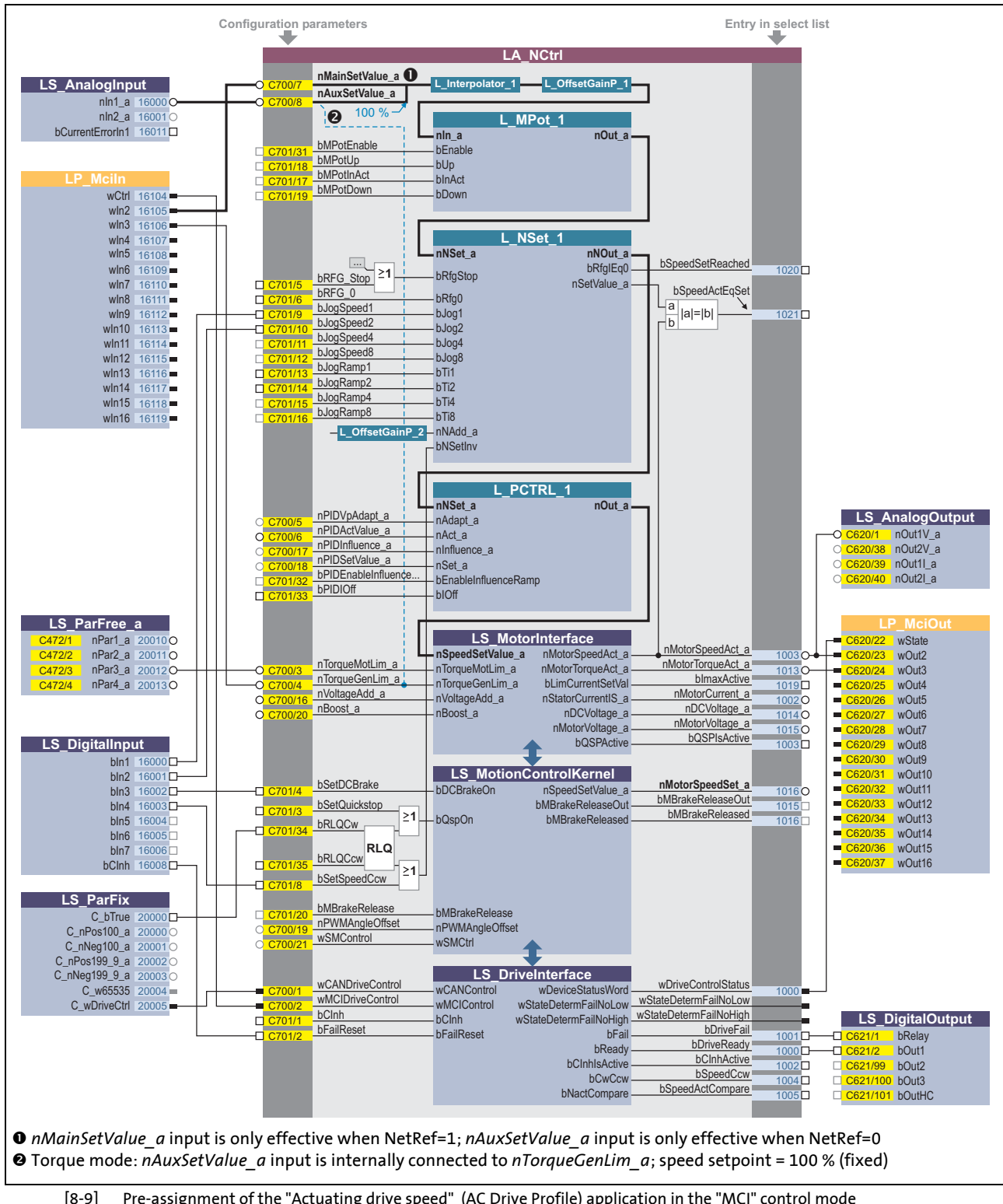
If required, the subcodes of [C00700](#) and [C00701](#) serve to change the pre-configured assignment of the application inputs:



[8-7] Pre-assignment of the "Actuating drive speed" (AC Drive Profile) application in the "Terminals 0" control mode

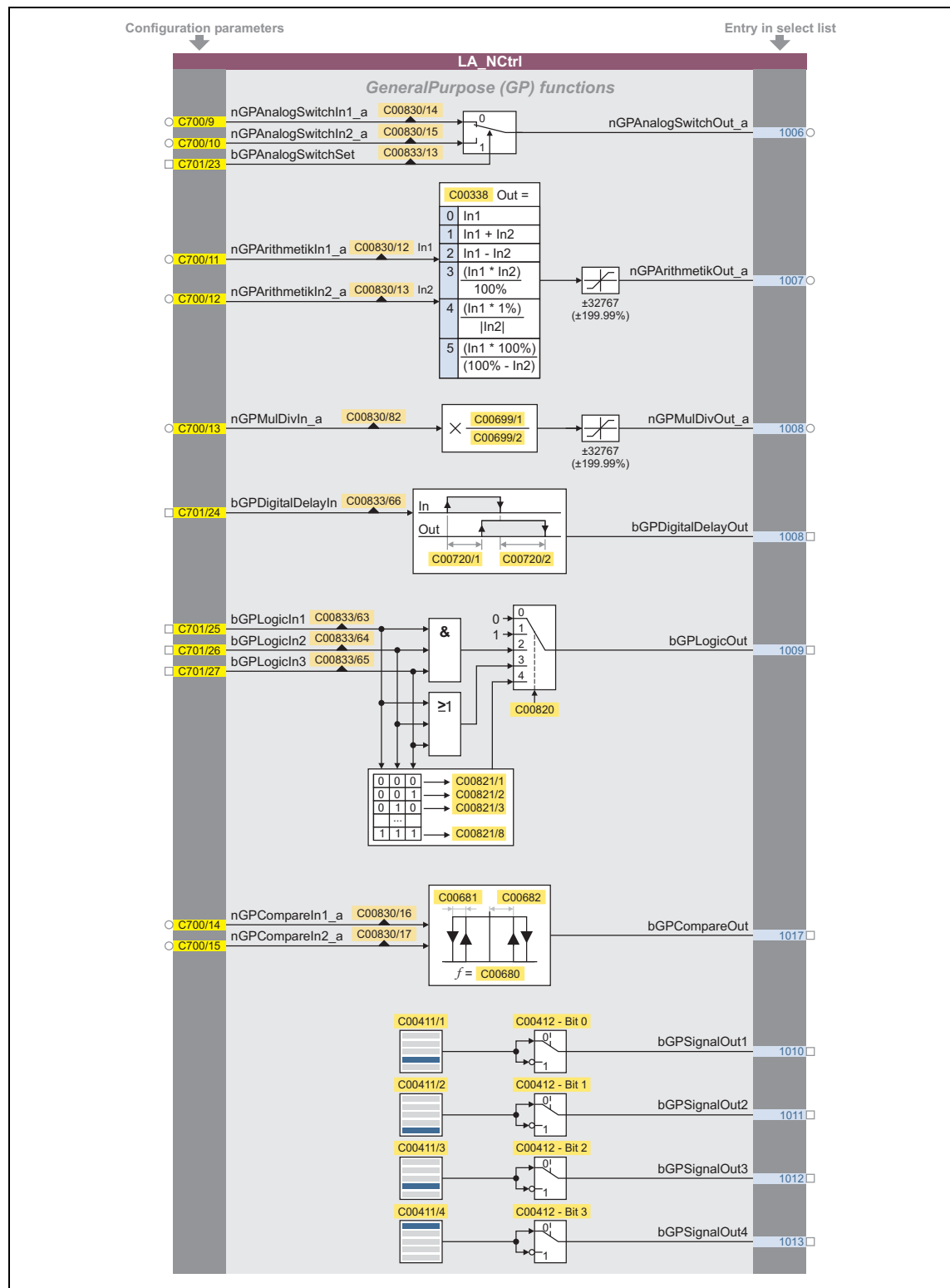


[8-8] Pre-assignment of the "Actuating drive speed" (AC Drive Profile) application in the "CAN" control mode

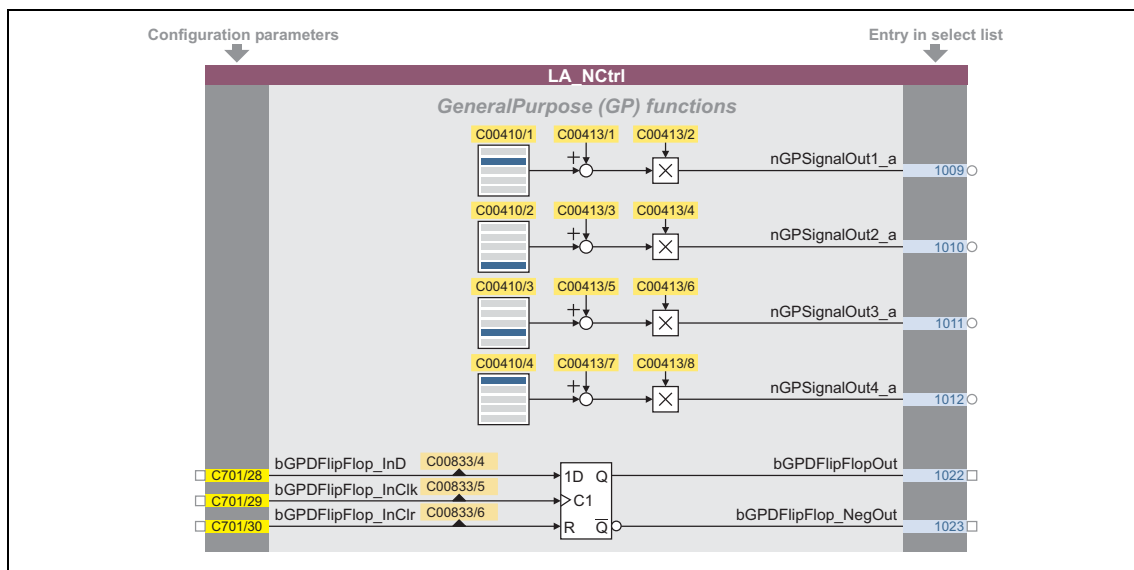


[8-9] Pre-assignment of the "Actuating drive speed" (AC Drive Profile) application in the "MCI" control mode

Configuration parameters for "GeneralPurpose" functions



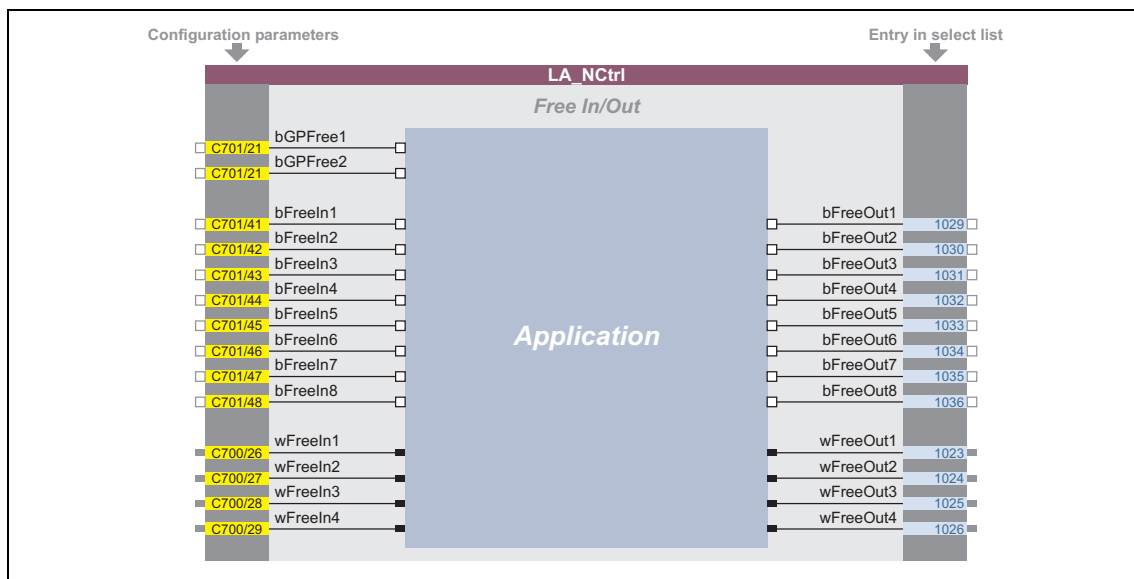
[8-10] "GeneralPurpose" functions



[8-11] "GeneralPurpose" functions (continuation)

Free inputs and outputs

These inputs can be freely interconnected in the application level. They can be used to transfer signals from the I/O level to the application level and vice versa.



[8-12] Free inputs/outputs

Related topics:

- ▶ [User-defined terminal assignment](#) (421)
- ▶ ["GeneralPurpose" functions](#) (546)

8.4 TA "Table positioning"

Numerous functions for the motion control of a single axis can be executed with the "Table positioning" technology application. For this, the technology application accesses the basic functions implemented in the **Motion Control Kernel** which are described in detail in the main chapter "[Basic drive functions \(MCK\)](#)". (📖 552)

- Manual jog
- Retracting from limit switches
- Reference setting/homing in 18 different modes (*in preparation*)
- Positioning (absolute, relative)
- Continuous travel (speed mode)
- Speed override
- Acceleration override
- Profile sequence block control
- Travel block restart within the profile (online profile start)
- Specification of target position via process signal interface (e.g. via fieldbus)

Further functions

- Up to 15 travel sets can be set via parameters
- Parameterisation of the profile data in physical units or relative values
- Adjustable torque limitation
- Freely selectable, variable ramp shape
- Motor potentiometer function
- Software limit position monitoring
- Following error monitoring (with static limits)
- Automatic holding brake control
- Quick stop (QSP) with adjustable ramp time
- Enable of individual functions via control word
- Status and diagnostic displays
- Operating mode changeover (manual jog, homing, speed follower, positioning)
- Integrated, freely available "GeneralPurpose" functions:
Analog switch, arithmetic, multiplication/division, binary delay element, binary logic, analog comparison, D-FlipFlop, counter
- **From version 12.00.00**, the application interconnection can be extended by an internal sequence control using the FB [L_Sequencer_1](#) if required.

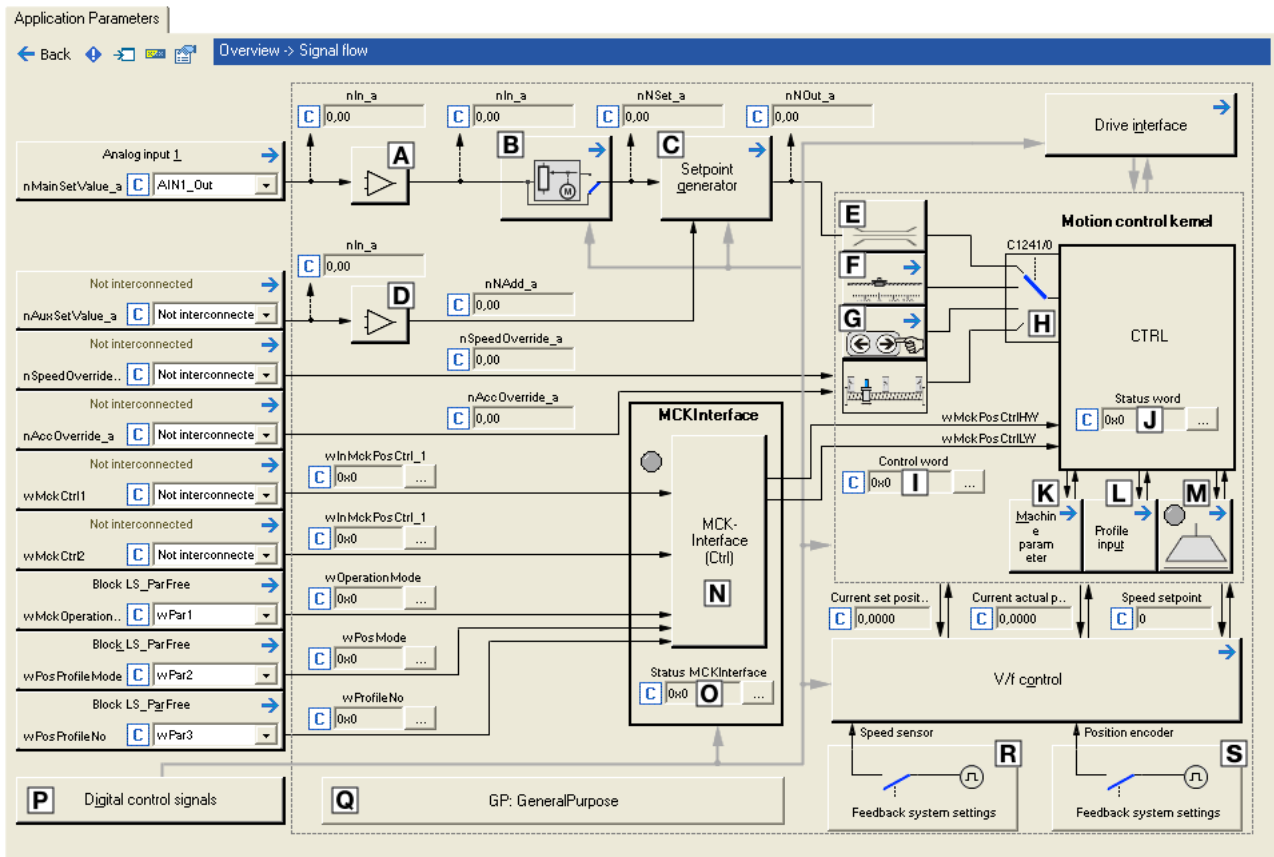
Related topics:

- ▶ [Commissioning of the "Table positioning" technology application](#) (📖 67)

8.4.1 Basic signal flow

The main element of the technology application is the **Motion Control Kernel**.

- The **Motion Control Kernel** is controlled via a 32-bit double control word. All motion profiles in the different operating modes can be controlled with this interface.
- Upstream to the **Motion Control Kernel** there is a so-called **MCKInterface** called which provides additional process inputs for the application in order to control the **Motion Control Kernel**.



[8-13] Signal flow of the table positioning

- | | |
|---|---|
| [A] Offset and gain (L_OffsetGainP_1) | [I] MCK control word |
| [B] Motor potentiometer function (L_MPot_1) | [J] MCK status word |
| [C] Setpoint generator (L_NSet_1) | [K] Selection of the machine parameters |
| [D] Offset and gain (L_OffsetGainP_2) | [L] Profile entry for the "Positioning" basic function. |
| [E] Speed setpoint input limitation | [M] Holding brake control |
| [F] Basic function " Homing " | [N] MCKInterface |
| [G] Basic function " Manual jog " | [O] Status word of the MCKInterface |
| [H] Operating mode changeover (is executed by the MCKInterface) | [P] Terminal assignment & display of digital control signals |
| [Q] Integrated disposable " GeneralPurpose " functions: Analog switch, arithmetic, multiplication/division, binary delay element, binary logic, analog comparison, D-flipflop | |

8.4.1.1 Possibilities for the position selection

The following options are available for the selection of different positions:

1. Changeover of profiles
2. Changing the profile position via parameter data (SDO)
3. Changing the profile position via process data (PDO)
 - The profile position is defined in [increments] or in the application unit [units].

	Changeover of profiles	Changing the profile position via SDO	Changing the profile position via PDO	
Number of positions	max. 15	n > 15	n > 15	
Position selection	Parameterisation in the profile	Selection via SDO	Selection via PDO	
Unit	units	units	Increments	units
Remainder allowance	in the drive	in the drive	in the PLC	in the drive



Note!

Setting the machine parameters is a basic prerequisite for the operating modes "[Homing](#)", "[Manual jog](#)" and "[Positioning](#)".

The more precisely the machine parameters are set, the better the results of positioning!

► [Machine parameters](#) (📖 582)

Possibility 1: Changeover of profiles

A total of 15 profiles is available in the 8400 TopLine.

- A profile describes a motion task that can be converted into a rotary motion by the **Motion Control Kernel** in the "Positioning" operating mode.
- A detailed explanation of all profile parameters can be found in the subchapter "[Profile entry](#)". ([📖 637](#)) of the description of the "Positioning" basic drive function.
- The selection of the profile to be executed can either be executed as a data word via the input *wPosProfileNo* or binary coded via the inputs *bPosProfileNo_1* ... *bPosProfileNo_4*.
- The chosen profile is started via the process input *bPosExecute* of the FB [L_MckCtrlInterface](#) or the control bit "PosExecute" in the [MCK control word](#).

Possibility 2: Changing the profile position via parameter data (SDO)

The parameter data channel of a fieldbus can also be used to change the position in a profile.

- The position of the profiles 1 ... 15 are stored in the subcodes 1 ... 15 of the code [C01301](#).
- More than 15 positions are available via the profile changeover (as described under possibility 1).

Possibility 3: Changing the profile position via process data (PDO)

For selecting the position in [increments], the *dnPosProfilePosition_p* input at the application block is available.

**Note!**

For selecting the position in [units], the two inputs *wPosProfileUnitsLW* and *wPosProfileUnitsHW* at the application block are available.

- In the application level, the position in the FB [L_MckCtrlInterface](#) is converted from [units] to [increments] again and output to *dnPosSetOut_p*. For this purpose, the respective mode for position calculation must be selected in [C01296/1](#).
- Since the conversion is not executed within one controller cycle, the data at the *dnPosSetOut_p* output can be out-of-date. The *bPosSetDataValid* output is set to TRUE when the conversion is completed and the position in increments is valid. Then, the position can be transmitted to the profile (see the following section).

The acceptance of the position into the currently selected profile is executed with a FALSE-TRUE edge at the *bPosSetProfilePosition* input.

- If bit 2 is set in [C01297](#), the applied setpoint position is accepted into the currently selected profile and the profile is started directly when setting the process input *bPosExecute* to TRUE or setting the control bit "PosExecute" in the [MCK control word](#).
- If bit 3 is set in [C01297](#), the setpoint positions at the MCKInterface are automatically accepted into the profile with the applied profile number if a change of data is detected at the corresponding input for the setpoint position.
- The accepted position is stored in the code [C01301/x](#) in the application unit [units]. By reading out the code, you can check if the position was correctly accepted into the profile.

**Note!**

How to store changed profile parameters safely against mains failure in the memory module: Set [C00002/11](#) = "1: On / Start".

8.4.2 Internal interfaces | application block "LA_TabPos"

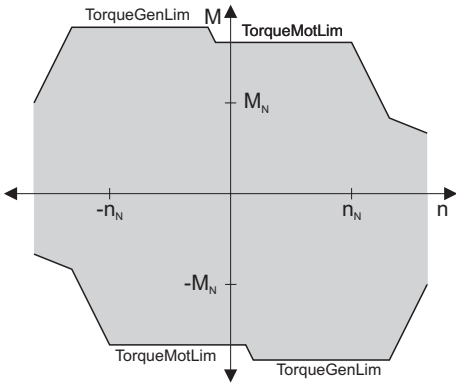
**Note!**

The connectors grayed out in the following table are hidden in the function block editor in the Lenze setting.

- These connections can be shown via the **Connector visibilities** command in the *Context menu* of the application block.

Inputs

Identifier	Data type	Information/possible settings
wCANDriveControl	WORD	Control word via system bus (CAN) for device control <ul style="list-style-type: none"> • See the "wCANControl/wMCIControl control words" subchapter of the chapter on device control for a detailed description of the individual control bits.
wMCIDriveControl	WORD	Control word via communication module (e.g. PROFIBUS) for device control <ul style="list-style-type: none"> • See the "wCANControl/wMCIControl control words" subchapter of the chapter on device control for a detailed description of the individual control bits.
wSMControl	WORD	Interface to the optional safety system. <ul style="list-style-type: none"> • Setting control bit 0 ("SafeStop1") in this control word causes e.g. the automatic deceleration of the drive to standstill within this application (in the Motion Control Kernel). • See the subchapter "Interface to safety system" of the chapter on basic drive functions for a detailed description of the individual control bits.
bCInh	BOOL	Enable/Inhibit controller
		<div>FALSE</div> <div>Enable controller: The controller switches to the "OperationEnabled" device status if no other source for controller inhibit is active. <ul style="list-style-type: none"> • C00158 provides a bit coded representation of all active sources/triggers of a controller inhibit. </div>
bFailReset	BOOL	Reset error message
		<div>In the Lenze setting this input is connected to the digital input controller enable so that a possibly existing error message is reset together with the controller enable (if the cause for the fault is eliminated).</div> <div>TRUE</div> <div>The current fault is reset, if the cause for the fault is eliminated. <ul style="list-style-type: none"> • If the fault still exists, the error status remains unchanged. </div>
bSetQuickstop	BOOL	Enable quick stop (QSP) <ul style="list-style-type: none"> • Also see device command "Activate/deactivate quick stop".
		<div>TRUE</div> <div>Activate quick stop <ul style="list-style-type: none"> • Motor control is decoupled from the setpoint selection and, within the deceleration time parameterised in C00105, the motor is brought to a standstill ($n_{act} = 0$). • The motor is kept at a standstill during closed-loop operation. • A pulse inhibit is set if the auto-DCB function has been activated via C00019. </div>
		<div>FALSE</div> <div>Deactivate quick stop <ul style="list-style-type: none"> • The quick stop is deactivated if no other source for the quick stop is active. • C00159 displays a bit code of active sources/causes for the quick stop. </div>

Identifier	Data type	Information/possible settings				
nTorqueMotLim_a nTorqueGenLim_a	INT	<p>Torque limitation in motor mode and in generator mode</p> <ul style="list-style-type: none">• These input signals are directly transferred to the motor control to limit the controller's maximum torque in motor and generator mode.• The drive cannot output a higher torque in motor/generator mode than set here.• The applied values (any polarity) are internally interpreted as absolute values.• If V/f characteristic control (VFCplus) is selected, limitation is <u>indirectly</u> performed via a so-called I_{\max} controller.• If sensorless vector control (SLVC) or servo control (SC) is selected, limitation has a <u>direct</u> effect on the torque-producing current component.• Scaling: $16384 \equiv 100 \% M_{\max}$ (C00057) <p>Note: Setting this input is ineffective in the reference modes 14 and 15 ("Homing to positive stop").</p> <p>Torque limits in motor and generator mode:</p> 				
bSetSpeedCcw	BOOL	<p>Change of direction of rotation</p> <ul style="list-style-type: none">• For instance if a motor or gearbox is fixed laterally reversed to a machine part, but the setpoint selection should still be executed for the positive direction of rotation. <table><tr><td>FALSE</td><td>Clockwise rotation (Cw)</td></tr><tr><td>TRUE</td><td>Direction of rotation to the left (Ccw)</td></tr></table>	FALSE	Clockwise rotation (Cw)	TRUE	Direction of rotation to the left (Ccw)
FALSE	Clockwise rotation (Cw)					
TRUE	Direction of rotation to the left (Ccw)					
nMainSetValue_a	INT	<p>Main speed setpoint</p> <ul style="list-style-type: none">• Offset and gain of this input signal can be set in C00696 and C00670 for a simple signal adjustment of a setpoint encoder.• Scaling: $16384 \equiv 100 \%$ reference speed (C00011)• The main setpoint is transformed to a speed setpoint in the setpoint encoder via a ramp function generator with linear or S-shaped ramps.• Upstream to the ramp function generator, a blocking speed masking function and a setpoint MinMax limitation are effective.• For a detailed functional description see the L_NSet FB.				
nAuxSetValue_a	INT	<p>Additional speed setpoint</p> <ul style="list-style-type: none">• Offset and gain of this input signal can be set in C00697 and C00671 for a simple signal adjustment of a setpoint encoder.• Scaling: $16384 \equiv 100 \%$ reference speed (C00011)• The additional speed setpoint can be linked arithmetically with the main speed setpoint behind the ramp function generator.• The additional speed setpoint can be shown via ramp times of a second ramp function generator.• For a detailed functional description see the L_NSet FB.				
bJogSpeed1 bJogSpeed2	BOOL	<p>Selection inputs for fixed changeover setpoints (JOG setpoints) for the main setpoint</p> <ul style="list-style-type: none">• Selection inputs are binary coded.				

Identifier	Data type	Information/possible settings
bJogSpeed1 bJogSpeed2	BOOL	<p>Selection inputs for fixed changeover setpoints (JOG setpoints) for the main setpoint</p> <ul style="list-style-type: none"> • A fixed setpoint for the setpoint generator can be activated instead of the main setpoint via these selection inputs. • The two selection inputs are binary coded, therefore you can select 3 fixed setpoints. • In the case of binary coded selection "0" (all inputs = FALSE or not assigned), main setpoint <i>nMainSetValue_a</i> is active. • The selection of the fixed setpoints is carried out in C00039/1...3 in [%] based on the reference speed (C00011). • For a detailed functional description see the L_NSet FB.
Motor potentiometer Alternatively to the input signal <i>nMainSetValue_a</i> , the main setpoint can also be generated by a motor potentiometer function. <ul style="list-style-type: none"> • In the Lenze setting, the motor potentiometer function is deactivated. • Activation is possible via C00806 or via the <i>bMPotEnable</i> input. • The behaviour of the motor potentiometer during switch-on of the drive system can be selected in C00805. • For a detailed functional description see the L_MPot FB. 		
bMPotEnable	BOOL	<p>Activating the motor potentiometer function</p> <ul style="list-style-type: none"> • This input and C00806 are OR'd.
		<p>TRUE The motor potentiometer function is active; the speed setpoint can be changed via the <i>bMPotUp</i> and <i>bMPotDown</i> control inputs.</p>
bMPotUp	BOOL	<p>Increasing the speed setpoint</p>
		<p>TRUE Approach the upper speed limit value set in C00800 with the acceleration time set in C00802.</p>
bMPotDown	BOOL	<p>Decreasing the speed setpoint</p>
		<p>TRUE Approach the lower speed limit value set in C00801 with the deceleration time set in C00803.</p>
MCK basic functions		
bMBrakeRelease	BOOL	<p>Holding brake control: Release/apply brake</p> <ul style="list-style-type: none"> • In conjunction with the operating mode selected in C02580 (Lenze setting: "Brake control off").
		<p>FALSE Apply brake.</p> <ul style="list-style-type: none"> • During automatic operation, the internal brake logic controls the brake.
		<p>TRUE Release brake manually (forced release).</p> <ul style="list-style-type: none"> • Note! The brake can also be released if the controller is inhibited! • During automatic operation, the internal brake logic is deactivated and the brake is released (supervisor operation). If a controller inhibit has been set by the brake control, it will be deactivated. • In semi-automatic operation, the brake is released including feedforward control.
wMckCtrl1 wMckCtrl2	WORD	<p>Direct selection of MCK control words</p> <ul style="list-style-type: none"> • E.g. via a master control which has been connected to the fieldbus, too. For this purpose, the control word inputs can directly be connected to the <i>LP_McIn</i> or <i>LP_CanIn</i> fieldbus interface. • See the "MCK control word" chapter for a detailed description of the individual control bits.

Identifier	Data type	Information/possible settings
wMckOperationMode	WORD	Selection of the operating mode of the Motion Control Kernel <ul style="list-style-type: none"> Only bit 0 ... bit 3 of wMckOperationMode is evaluated. If an invalid operating mode is selected, the response set in C00595/11 is activated (Lenze setting: "Warning"). The current operating mode is displayed in C01243.
		0 Speed follower
		1 Homing
		2 Manual jog
		3 Positioning
		4 Stop
		5 Position follower
		6 ... 15 Reserved for future extensions
bMckOperationMode_1 ... bMckOperationMode_8	BOOL	Binary-coded selection of the operating mode of the Motion Control Kernel <ul style="list-style-type: none"> See the "MCK control word" chapter for a detailed description of the individual control bits. If an invalid operating mode is selected, the response set in C00595/11 is activated (Lenze setting: "Warning"). The current operating mode is displayed in C01243.
bPosCtrlOn	BOOL	Position control/Angle control <ul style="list-style-type: none"> Pre-configured assignment: TRUE (position control active)
		FALSE Deactivate position control/angle control
		TRUE Activate position control/angle control
nPosCtrlOutLimit_a	INT	Limitation of the position controller output <ul style="list-style-type: none"> Scaling: 16384 \equiv 100 % reference speed (C00011) Pre-configured assignment: 100 %
nPosCtrlAdapt_a	INT	Adaptation of the position controller gain <ul style="list-style-type: none"> Scaling: 16384 \equiv 100 % Vp (C00254) Pre-configured assignment: 100 %
bLimitSwitchPos bLimitSwitchNeg	BOOL	Limit position monitoring : Inputs for positive/negative limit switch
bReleaseLimitSwitch	BOOL	Manual jog : Retract operated limit switch
		TRUE Retract operated limit switch (in opposite direction)
bManJogPos bManJogNeg	BOOL	Manual jog : bManJogPos = TRUE: Manual jog right bManJogNeg = TRUE: Manual jog left Both inputs = TRUE: No change compared to previous state Both inputs = FALSE: Stop manual jog
bManJogExecute2ndVel	BOOL	Manual jog : Changeover to speed 2
		FALSE Speed 1 (C01231/1) active
		TRUE Speed 2 (C01231/2) active
bEnableSpeedOverride	BOOL	Speed override
		TRUE Activate speed override
nSpeedOverride_a	INT	Value for Speed override <ul style="list-style-type: none"> Percentage multiplier for the currently active speed. 16384 \equiv 100 % of the maximum traversing speed (display in C01211/1). If the override value is 0 %, the drive is brought to a standstill.
bEnableAccOverride	BOOL	Acceleration override
		TRUE Activate acceleration override

Identifier	Data type	Information/possible settings				
nAccOverride_a	INT	Value for Acceleration override <ul style="list-style-type: none">Percentage multiplier for the currently active acceleration.16384 ≡ 100 % of the parameterised acceleration of the corresponding operating mode.If the override value is 0 %, acceleration ceases.				
bHomeStartStop	BOOL	Homing : Start/stop homing <table><tr><td>TRUE</td><td>Start homing</td></tr><tr><td>TRUE⇒FALSE</td><td>Stop homing</td></tr></table>	TRUE	Start homing	TRUE⇒FALSE	Stop homing
TRUE	Start homing					
TRUE⇒FALSE	Stop homing					
bHomeSetPosition	BOOL	Homing : Set home position <table><tr><td>TRUE</td><td>Set home position</td></tr></table>	TRUE	Set home position		
TRUE	Set home position					
bHomeResetPosition	BOOL	Homing : Reset home position <table><tr><td>TRUE</td><td>Reset the "Reference known" status</td></tr></table>	TRUE	Reset the "Reference known" status		
TRUE	Reset the "Reference known" status					
bHomeMark	BOOL	Homing : Input for reference switch (pre-switch off mark) <ul style="list-style-type: none">This input responds to the FALSE status (fail-safe) and is to be connected to the corresponding digital input to which the reference switch is connected.				
bPosSetProfilePosition	BOOL	Position teaching : MCK setpoint position <table><tr><td>TRUE</td><td>Teach MCK setpoint position into the selected profile.</td></tr></table>	TRUE	Teach MCK setpoint position into the selected profile.		
TRUE	Teach MCK setpoint position into the selected profile.					
bPosSetActualPosition	BOOL	Position teaching : Current position <table><tr><td>TRUE</td><td>Teach current position into the selected profile.</td></tr></table>	TRUE	Teach current position into the selected profile.		
TRUE	Teach current position into the selected profile.					
bPosExecute	BOOL	Positioning : Start travelling <table><tr><td>FALSE⇌TRUE</td><td>Execute selected profile</td></tr></table>	FALSE⇌TRUE	Execute selected profile		
FALSE⇌TRUE	Execute selected profile					
bPosFinishTarget	BOOL	Positioning : Complete cancelled profile <table><tr><td>FALSE⇌TRUE</td><td>A positioning process previously cancelled, e.g. by <i>bPosStop</i> or due to a device error, is resumed by travelling to the original target.</td></tr></table>	FALSE⇌TRUE	A positioning process previously cancelled, e.g. by <i>bPosStop</i> or due to a device error, is resumed by travelling to the original target.		
FALSE⇌TRUE	A positioning process previously cancelled, e.g. by <i>bPosStop</i> or due to a device error, is resumed by travelling to the original target.					
bPosDisableFollowProfile	BOOL	Positioning : Do not execute sequence profile (switch-off profile linkage) <table><tr><td>TRUE</td><td>Evaluation of the sequence profile number parameterised in C01307/1...15 for the selected profile is suppressed.</td></tr></table>	TRUE	Evaluation of the sequence profile number parameterised in C01307/1...15 for the selected profile is suppressed.		
TRUE	Evaluation of the sequence profile number parameterised in C01307/1...15 for the selected profile is suppressed.					
bPosStop	BOOL	Positioning : Cancel travelling <table><tr><td>TRUE</td><td>Stop positioning From version 02.00.00, more travel requests will be inhibited ("PosExecute" will be blocked).</td></tr></table>	TRUE	Stop positioning From version 02.00.00 , more travel requests will be inhibited ("PosExecute" will be blocked).		
TRUE	Stop positioning From version 02.00.00 , more travel requests will be inhibited ("PosExecute" will be blocked).					

Identifier	Data type	Information/possible settings																						
wPosProfileMode	WORD	<p>Override of the positioning mode set in the profile data</p> <ul style="list-style-type: none">• Via this input, an override of the positioning mode parameterised in C01300/1...15 for the selected profile is possible.• The value set in C01300/1...15 is not overwritten in this case.• Only bit 0 ... bit 3 of <i>wPosMode</i> are evaluated.• If <i>wPosMode</i> = 0 is selected, the positioning mode set in C01300/1...15 is used. <table><tr><td>0</td><td>Positioning mode = setting in C01300/1...15</td></tr><tr><td>1</td><td>Absolute (shortest path)</td></tr><tr><td>2</td><td>Continuous</td></tr><tr><td>3</td><td>Relative</td></tr><tr><td>4</td><td>absolute (Cw)</td></tr><tr><td>5</td><td>absolute (Ccw)</td></tr><tr><td>8</td><td>Absolute (shortest path) to TP</td></tr><tr><td>9</td><td>Continuous to TP</td></tr><tr><td>10</td><td>Relative to TP</td></tr><tr><td>11</td><td>Absolute (Cw) on TP</td></tr><tr><td>12</td><td>Absolute (Ccw) on TP</td></tr></table> <p>All other possible settings are reserved for future extensions!</p>	0	Positioning mode = setting in C01300/1...15	1	Absolute (shortest path)	2	Continuous	3	Relative	4	absolute (Cw)	5	absolute (Ccw)	8	Absolute (shortest path) to TP	9	Continuous to TP	10	Relative to TP	11	Absolute (Cw) on TP	12	Absolute (Ccw) on TP
0	Positioning mode = setting in C01300/1...15																							
1	Absolute (shortest path)																							
2	Continuous																							
3	Relative																							
4	absolute (Cw)																							
5	absolute (Ccw)																							
8	Absolute (shortest path) to TP																							
9	Continuous to TP																							
10	Relative to TP																							
11	Absolute (Cw) on TP																							
12	Absolute (Ccw) on TP																							
wPosProfileNo	WORD	<p>Stipulation of the profile to be executed</p> <ul style="list-style-type: none">• Optionally as a data word or binary coded.																						
bPosProfileNo_1 ... bPosProfileNo_8	BOOL																							
dnPosProfilePosition_p	DINT	<p>Selection of the target position in [increments]</p> <ul style="list-style-type: none">• The mode for calculating the position is selected in C01296/1.																						
wPosProfileUnitsLW wPosProfileUnitsHW	WORD	<p>Selection of the target position in [units]</p> <ul style="list-style-type: none">• <i>wPosProfileUnitsLW</i> = Low word, <i>wPosProfileUnitsHW</i> = High word• The mode for calculating the position is selected in C01296/1.																						
GP: GeneralPurpose The following inputs are interconnected with logic/arithmetic functions on application level for free usage. ▶ "GeneralPurpose" functions																								
nGPAAnalogSwitchIn1_a nGPAAnalogSwitchIn2_a	INT	<p>Analog switch: Input signals</p> <ul style="list-style-type: none">• The input signal selected via the selection input <i>bGPAAnalogSwitchSet</i> is output at output <i>nGPAAnalogSwitchOut_a</i>.																						
bGPAAnalogSwitchSet	BOOL	<p>Analog switch: Selection input</p> <table><tr><td>FALSE</td><td><i>nGPAAnalogSwitchOut_a</i> = <i>nGPAAnalogSwitchIn1_a</i></td></tr><tr><td>TRUE</td><td><i>nGPAAnalogSwitchOut_a</i> = <i>nGPAAnalogSwitchIn2_a</i></td></tr></table>	FALSE	<i>nGPAAnalogSwitchOut_a</i> = <i>nGPAAnalogSwitchIn1_a</i>	TRUE	<i>nGPAAnalogSwitchOut_a</i> = <i>nGPAAnalogSwitchIn2_a</i>																		
FALSE	<i>nGPAAnalogSwitchOut_a</i> = <i>nGPAAnalogSwitchIn1_a</i>																							
TRUE	<i>nGPAAnalogSwitchOut_a</i> = <i>nGPAAnalogSwitchIn2_a</i>																							
nGPArithmetikIn1_a nGPArithmetikIn2_a	INT	<p>Arithmetic: Input signals</p> <ul style="list-style-type: none">• The arithmetic function is selected in C00338.• The result is output at output <i>nGPArithmetikOut_a</i>.																						
nGPMulDivIn_a	INT	<p>Multiplication/Division: Input signal</p> <ul style="list-style-type: none">• The factor for the multiplication can be set in C00699/1 (numerator) and C00699/2 (denominator).• The result is output at output <i>nGPMulDivOut_a</i>.																						
bGPDigitalDelayIn	BOOL	<p>Binary delay element: Input signal</p> <ul style="list-style-type: none">• The on-delay can be set in C00720/1.• The off-delay can be set in C00720/2.• The time-delayed input signal is output at output <i>bGPDigitalDelayOut</i>.																						

Identifier	Data type	Information/possible settings
bGPLogicIn1 bGPLogicIn2 bGPLogicIn3	BOOL	Binary logic: Input signals <ul style="list-style-type: none"> The logic operation is selected in C00820. The result is output at output <i>bGPLogicOut</i>.
nGPCompareIn1_a nGPCompareIn2_a	INT	Analog comparison: Input signals <ul style="list-style-type: none"> The comparison operation is selected in C00680. Hysteresis and window size can be set in C00680 and C00682. If the comparison statement is true, the output <i>bGPCompareOut</i> will be set to TRUE.
bGPDFlipFlop_InD bGPDFlipFlop_InClk bGPDFlipFlop_InClr	BOOL	D-FlipFlop: Input signals <ul style="list-style-type: none"> Data, clock and reset input
bGPCounter1ClkUp	BOOL	Counter: Clock input <ul style="list-style-type: none"> With each edge, the module counts up by "1". Only FALSE-TRUE edges are evaluated. Note: The static state "1" is not permissible at this input.
bGPCounter1ClkDown	BOOL	Counter: Clock input <ul style="list-style-type: none"> With each edge, the module counts down by "1". Only FALSE-TRUE edges are evaluated. Note: The static state "1" is not permissible at this input.
bGPCounter1Load	BOOL	Counter: Loading input <ul style="list-style-type: none"> The input has the highest priority.
		TRUE Accept the starting value <i>wGPCounter1LdVal</i> .
wGPCounter1LdVal	WORD	Counter: Starting value <ul style="list-style-type: none"> Assigned value is internally interpreted as "INT" data type (-32767 ... +32767), i.e. the most significant bit determines the sign.
wGPCounter1CmpVal	WORD	Counter: Comparison value <ul style="list-style-type: none"> Assigned value is internally interpreted as "INT" data type (-32767 ... +32767), i.e. the most significant bit determines the sign.
Free inputs The following inputs can freely be interconnected on the application level. The signals can be transferred from the I/O level to the application level via these inputs.		
bFreeIn1 ... bFreeIn8	BOOL	Free inputs for digital signals
wFreeIn1 ... wFreeIn4	WORD	Free inputs for 16-bit signals
dnFreeIn1_p ... dnFreeIn2_p	DINT	Free inputs for 32-bit signals

Outputs

Identifier	Data type	Value/meaning
wDriveControlStatus	WORD	Status word of the controller <ul style="list-style-type: none"> The status word contains information on the current status of the drive controller. See the "wDeviceStatusWord status word" subchapter of the chapter on device control for a detailed description of the bit assignment.
wStateDetermFailNoLow	WORD	Display of the status determining error (LOW word)
wStateDetermFailNoHigh	WORD	Display of the status determining error (HIGH word)
bDriveFail	BOOL	TRUE Drive controller in error status. <ul style="list-style-type: none"> "Fault" device status is active.

Identifier	Data type	Value/meaning	
bDriveReady	BOOL	TRUE	Controller is ready for operation. <ul style="list-style-type: none">• "SwitchedOn" device status is active.• The drive is in this device status if the DC bus voltage is applied and the controller is still inhibited by the user (controller inhibit).
bCInhActive	BOOL	TRUE	Controller inhibit is active.
bQSPLsActive	BOOL	TRUE	Quick stop is active.
bSpeedCcw	BOOL	Current direction of rotation	
		FALSE	Clockwise rotation (Cw)
		TRUE	Direction of rotation to the left (Ccw)
bSpeedActCompare	BOOL	Result of the speed comparison (detection of speed=0)	
		TRUE	During open-loop operation: Speed setpoint < Comparison value (C00024)
			During closed-loop operation: Actual speed value < Comparison value (C00024)
blmaxActive	BOOL	"Current setpoint inside the limitation" status signal	
		TRUE	The current setpoint is internally limited (the drive controller operates at the maximum current limit).
bSpeedSetReached	BOOL	Status signal "setpoint = 0"	
		TRUE	Speed setpoint from the ramp function generator = 0
nMotorCurrent_a	INT	Current stator current/effective motor current <ul style="list-style-type: none">• Scaling: $16384 \equiv 100 \% I_{\max_mot}$ (C00022)	
nMotorSpeedSet_a	INT	Speed setpoint <ul style="list-style-type: none">• Scaling: $16384 \equiv 100 \%$ reference speed (C00011)	
nMotorSpeedAct_a	INT	Actual speed value <ul style="list-style-type: none">• Scaling: $16384 \equiv 100 \%$ reference speed (C00011)	
nMotorTorqueAct_a	INT	Actual torque <ul style="list-style-type: none">• In the "VFC (+encoder)" operating mode of the motor control, this value is determined from the current motor current and corresponds to the actual torque only by approximation.• Scaling: $16384 \equiv 100 \% M_{\max}$ (C00057)	
nDCVoltage_a	INT	Actual DC-bus voltage <ul style="list-style-type: none">• Scaling: $16384 \equiv 1000 \text{ V}$	
nMotorVoltage_a	INT	Current motor voltage/inverter output voltage <ul style="list-style-type: none">• Scaling: $16384 \equiv 1000 \text{ V}$	
MCK basic functions			
bMBrakeReleaseOut	BOOL	Holding brake control : Trigger signal for the holding brake control switching element via a digital output <ul style="list-style-type: none">• Use bit 0 in C02582 to activate inverted switching element triggering.	
		FALSE	Apply brake.
		TRUE	Release brake.
bMBrakeReleased	BOOL	Holding brake control : "Brake released" considering the brake release time <ul style="list-style-type: none">• When the holding brake is triggered to close, <i>bMBrakeReleased</i> is immediately set to FALSE even if the brake closing time has not yet elapsed!	
		TRUE	Brake released (after the brake release time has expired).
wMckState1 wMckState2	WORD	Output of the MCK status words <ul style="list-style-type: none">• For a detailed description of each status bit see chapter "MCK status word".	
wMckActOperationMode	WORD	Active setpoint-generating state of the MCK. <ul style="list-style-type: none">• Bits B0 ... B3 contain the information of the MCK status word.• Bits B4 ... B15 are fixed at "0".	

Identifier	Data type	Value/meaning	
bHomeDone	BOOL	TRUE	Homing has been executed.
bHomePosAvailable	BOOL	TRUE	Home position is known.
bProfileDone	BOOL	TRUE	Target position from the profile has been approached.
bProfileBusy	BOOL	TRUE	Profile positioning is active.
bAccelerating	BOOL	TRUE	Acceleration phase active.
bConstantDuty	BOOL	TRUE	Constant phase active.
bDecelerating	BOOL	TRUE	Braking phase active.
bDwellTime	BOOL	TRUE	Settling in target position is active
bInTarget	BOOL	TRUE	Target position (actual value) is in the target window.
wActProfileNo	WORD	Current profile number • Bit B0 ... B7 contain the information of the MCK status word . • Bits B8 ... B15 are fixed at "0".	
wActPosMode	WORD	Current positioning mode • Bit B0 ... B3 contain the information of the MCK status word . • Bits B4 ... B15 are fixed at "0".	
dnTargetPos_p	DINT	Target position in [increments] • 65535 \equiv 1 revolution of the motor shaft	
dnSetPos_p	DINT	Absolute position setpoint	
dnPosAct_p	DINT	Current position of the motor shaft in [increments]	
dnDeltaPosAct_p	DINT	Current following error in [increments] • Following error = Difference between set position and actual position	
wPosOutUnitsLW wPosOutUnitsHW	WORD	Output of the target position in [units] • <i>wPosOutUnitsLW</i> = Low-Word, <i>wPosOutUnitsHW</i> = High-Word • The mode for calculating the position is selected in C01296/2 .	

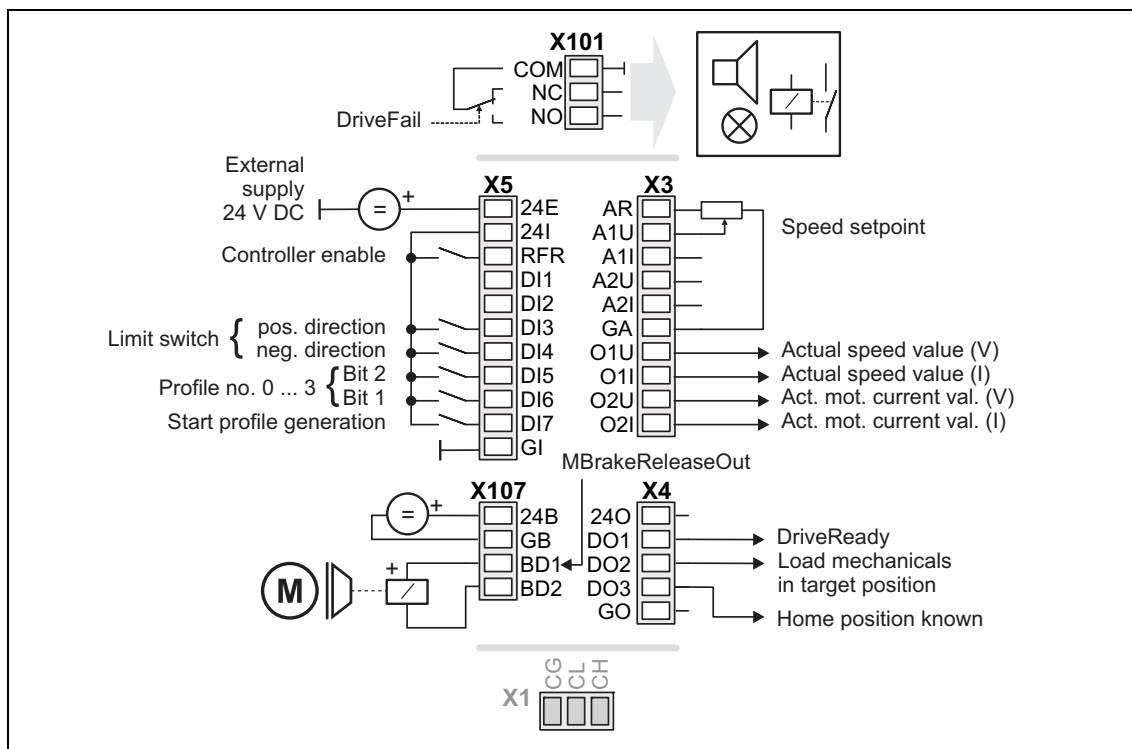
Identifier	Data type	Value/meaning		
GP: GeneralPurpose The following outputs are interconnected with logic/arithmetic functions on application level for free usage. ▶ "GeneralPurpose" functions				
nGPAAnalogSwitchInOut_a	INT	Analog switch : Output signal		
nGPArithmetikOut_a	INT	Arithmetic : Output signal		
nGPMulDivOut_a	INT	Multiplication/Division : Output signal		
bGPDigitalDelayOut	BOOL	Binary delay element : Output signal		
bGPLogicOut	BOOL	Binary logic : Output signal		
bGPCompareOut	BOOL	Analog comparison : Output signal		
bGPSignalOut1 ... bGPSignalOut4	BOOL	Binary signal monitor : Output signals <ul style="list-style-type: none">• The signal sources to be output are selected in C00411/1...4.• A bit coded inversion of the output signals can be parameterised in C00412.		
nGPSignalOut1_a ... nGPSignalOut4_a	BOOL	Analog signal monitor : Output signals <ul style="list-style-type: none">• The signal sources to be output are selected in C00410/1...4.• Gain and offset for each output signal can be parameterised in C00413/1...8.		
bGPDFlipFlop_Out	BOOL	D-FlipFlop : Output signal		
bGPDFlipFlop_NegOut	BOOL	D-FlipFlop : Negated output signal		
bGPCounter1Equal	BOOL	Counter : Status signal "Comparison value reached" <table><tr><td>TRUE</td><td>Comparison value <i>wGPCounter1CmpVal</i> reached.</td></tr></table>	TRUE	Comparison value <i>wGPCounter1CmpVal</i> reached.
TRUE	Comparison value <i>wGPCounter1CmpVal</i> reached.			
wGPCounter1Out	WORD	Counter : Counter content <ul style="list-style-type: none">• Internal limitation to ± 32767• The most significant bit determines the sign!		
Free outputs The following outputs can freely be interconnected on the application level. The signals from the application level can be transferred to the I/O level via these outputs.				
bFreeOut1 ... bFreeOut8	BOOL	Free outputs for digital signals		
wFreeOut1 ... wFreeOut4	WORD	Free outputs for 16-bit signals		
dnFreeOut1_p dnFreeOut2_p	WORD	Free outputs for 32-bit signals		

8.4.3 Terminal assignment of the control modes

The following comparison provides information about which inputs/outputs of the application block **LA_TabPos** are interconnected to the digital and analog input/output terminals of the drive controller in the different control modes.

	Control mode (C00007)							
	10: Terminals 0	12: Terminals 2	14: Terminals 11	16: Terminal 16	20: Keypad	21: PC	30: CAN	40: MCI
Digital input terminals								
X5/RFR	Controller enable / Reset of error message bFailReset							
X5/DI1	-	-	Positive limit switch bLimitSwitchPos	-	-	-	-	-
X5/DI2	-	-	Negative limit switch bLimitSwitchNeg	-	-	-	-	-
X5/DI3	Positive limit switch bLimitSwitchPos	-	-	Manual jog in positive direction bManJogPos	-	-	Positive limit switch bLimitSwitchPos	
X5/DI4	Negative limit switch bLimitSwitchNeg	Positioning profile, array bit (valency 4) bPosProfileNo_4		Manual jog in negative direction bManJogNeg	-	-	Negative limit switch bLimitSwitchNeg	
X5/DI5	Positioning profile, array bit (valency 2) bPosProfileNo_2				-	-	Home position bHomeMark	
X5/DI6	Positioning profile, array bit (valency 1) bPosProfileNo_1				-	-	Quick stop bSetQuickstop	
X5/DI7	Start of profile generation bPosExecute				-	-	Status word - bit 7 LP_CanOut1: bState_B7	Status word - bit 7 LP_MciOut: bState_B7
Analog input terminals								
X3/A1U	Main speed setpoint nMainSetValue_a 10 V ≡ 100 % reference speed (C00011)				-	-	Main speed setpoint nMainSetValue_a 10 V ≡ 100 % reference speed (C00011)	
X3/A1I								
X3/A2U	-	-	-	-	-	-	-	-
X3/A2I	-	-	-	-	-	-	-	-
Digital output terminals								
X4/DO1	Status "Drive is ready" (bDriveReady)							
X4/DO2	Status "Target position (actual value) is in the target window" (bInTarget)							
X4/DO3	Status "Home position is known"(bHomePosAvailable)						Status "Maximum current limit" (bImaxActive)	
X107/BD1, BD2	Control of the holding brake (bMBrakeReleaseOut)							
X101/COM, NO	Status "Error is pending" (bDriveFail)							
Analog output terminals								
X3/O1U	Actual speed value nMotorSpeedAct_a 10 V ≡ 100 % reference speed (C00011)							
X3/O1I								
X3/O2U	Actual motor current nMotorCurrent_a 10V ≡ 100% of I _{max_mot} (C00022)							
X3/O2I								

8.4.3.1 Terminals 0

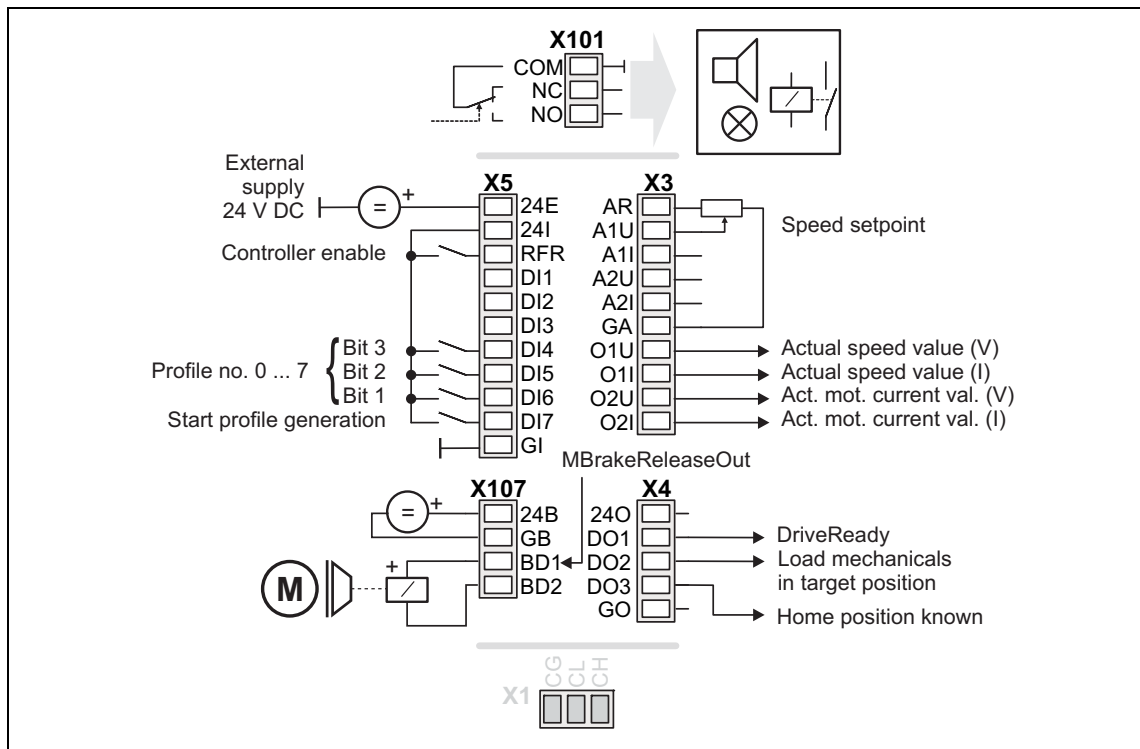


Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_TabPos.bDriveFail		
X5/RFR	LA_TabPos.bFailReset	X3/A1U	LA_TabPos.nMainSetValue_a 10 V ≙ 100 % reference speed (C00011)
X5/DI1	-	X3/A1I	-
X5/DI2	-	X3/A2U	-
X5/DI3	LA_TabPos.bLimitSwitchPos	X3/A2I	-
X5/DI4	LA_TabPos.bLimitSwitchNeg	X3/O1U	LA_TabPos.nMotorSpeedAct_a 10 V ≙ 100 % reference speed (C00011)
X5/DI5	LA_TabPos.bPosProfileNo_2	X3/O1I	-
X5/DI6	LA_TabPos.bPosProfileNo_1	X3/O2U	LA_TabPos.nMotorCurrent_a 10V ≙ 100% of I _{max_mot} (C00022)
X5/DI7	LA_TabPos.bPosExecute	X3/O2I	-
X107/BD1	LA_TabPos.bMBrakeReleaseOut	X4/DO1	LA_TabPos.bDriveReady
X107/BD2	-	X4/DO2	LA_TabPos.bInTarget
		X4/DO3	LA_TabPos.bHomePosAvailable

When the profile is defined, the operating mode in the Lenze setting is changed simultaneously:

bPosProfileNo_2 (DI5)	bPosProfileNo_1 (DI6)	Selected profile	Activation of operating mode
FALSE	FALSE	0	Speed follower
FALSE	TRUE	1	Homing
TRUE	FALSE	2	Manual jog
TRUE	TRUE	3	Positioning

8.4.3.2 Terminals 2

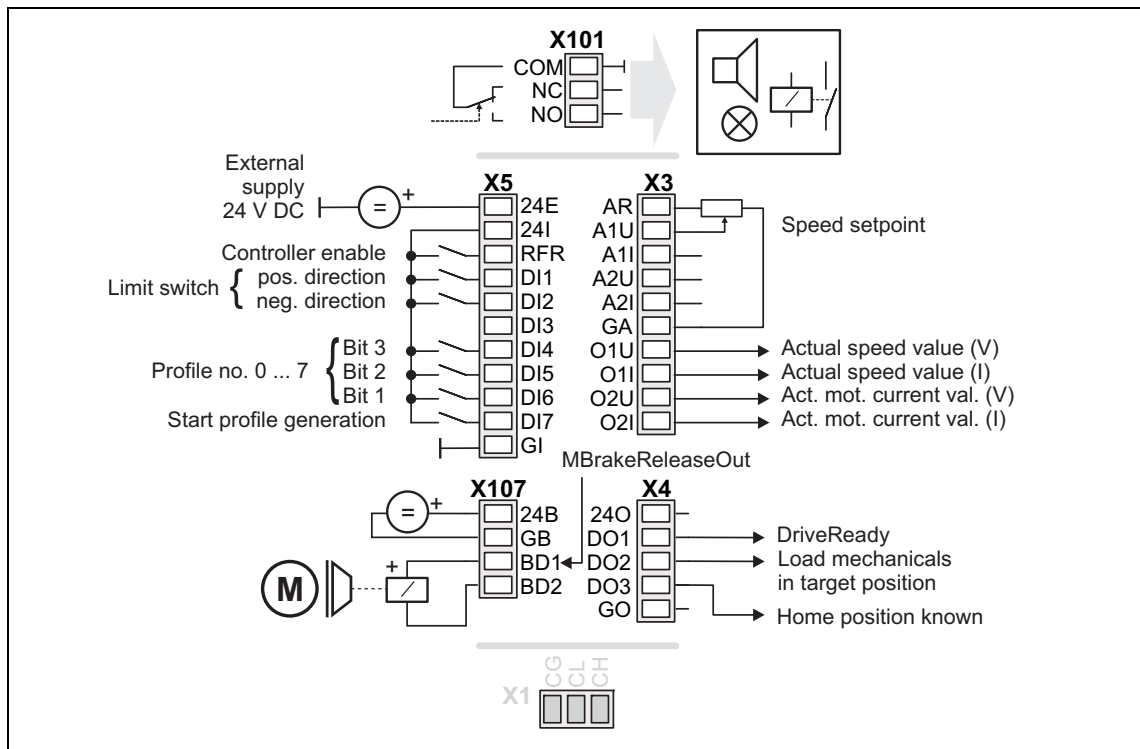


Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_TabPos.bDriveFail		
X5/RFR	LA_TabPos.bFailReset	X3/A1U	LA_TabPos.nMainSetValue_a 10 V ≙ 100 % reference speed (C00011)
X5/DI1	-	X3/A1I	-
X5/DI2	-	X3/A2U	-
X5/DI3	-	X3/A2I	-
X5/DI4	LA_TabPos.bPosProfileNo_4	X3/O1U	LA_TabPos.nMotorSpeedAct_a 10 V ≙ 100 % reference speed (C00011)
X5/DI5	LA_TabPos.bPosProfileNo_2	X3/O1I	-
X5/DI6	LA_TabPos.bPosProfileNo_1	X3/O2U	LA_TabPos.nMotorCurrent_a 10V ≙ 100% of I _{max_mot} (C00022)
X5/DI7	LA_TabPos.bPosExecute	X3/O2I	-
X107/BD1	LA_TabPos.bBrakeReleaseOut	X4/DO1	LA_TabPos.bDriveReady
X107/BD2	-	X4/DO2	LA_TabPos.bInTarget
		X4/DO3	LA_TabPos.bHomePosAvailable

When the profile is defined, the operating mode in the Lenze setting is changed simultaneously:

bPosProfileNo_4 (DI4)	bPosProfileNo_2 (DI5)	bPosProfileNo_1 (DI6)	Selected profile	Activation of operating mode
FALSE	FALSE	FALSE	0	Speed follower
FALSE	FALSE	TRUE	1	Homing
FALSE	TRUE	FALSE	2	Manual jog
FALSE	TRUE	TRUE	3	Positioning
...
TRUE	TRUE	TRUE	7	...

8.4.3.3 Terminals 11

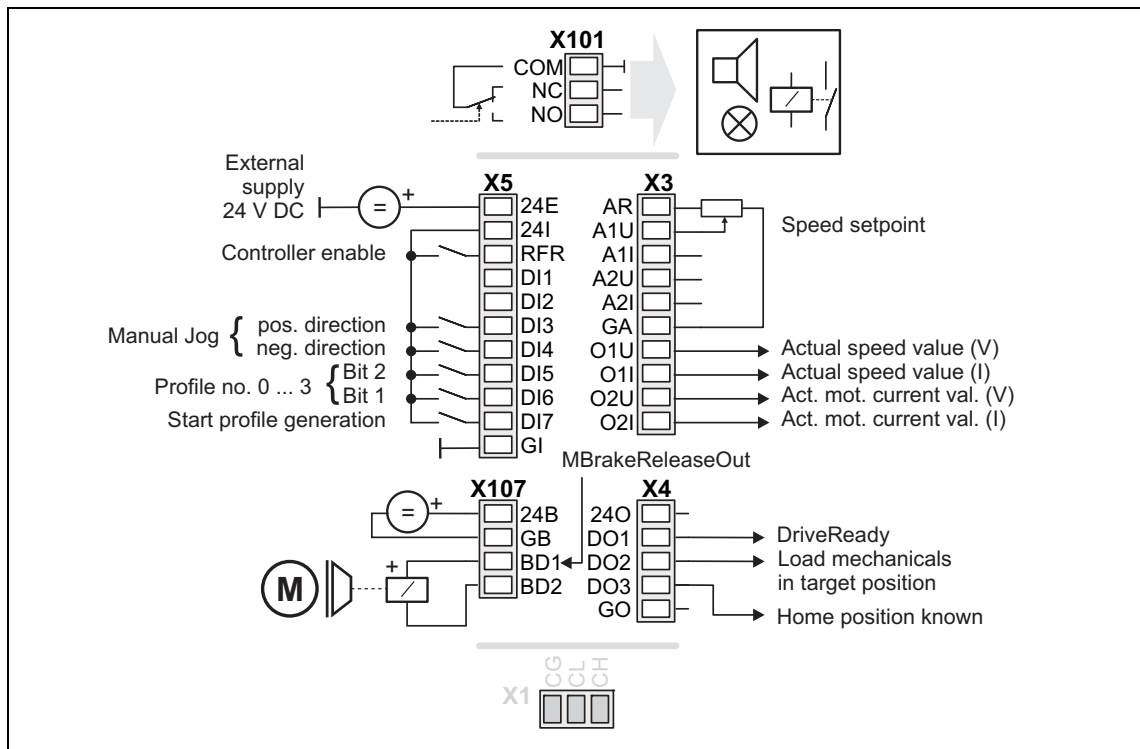


Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_TabPos.bDriveFail		
X5/RFR	LA_TabPos.bFailReset	X3/A1U	LA_TabPos.nMainSetValue_a 10 V ≙ 100 % reference speed (C00011)
X5/DI1	LA_TabPos.bLimitSwitchPos	X3/A1I	-
X5/DI2	LA_TabPos.bLimitSwitchNeg	X3/A2U	-
X5/DI3	-	X3/A2I	-
X5/DI4	LA_TabPos.bPosProfileNo_4	X3/O1U	LA_TabPos.nMotorSpeedAct_a 10 V ≙ 100 % reference speed (C00011)
X5/DI5	LA_TabPos.bPosProfileNo_2	X3/O1I	-
X5/DI6	LA_TabPos.bPosProfileNo_1	X3/O2U	LA_TabPos.nMotorCurrent_a 10V ≙ 100% of I _{max_mot} (C00022)
X5/DI7	LA_TabPos.bPosExecute	X3/O2I	-
X107/BD1	LA_TabPos.bMBrakeReleaseOut	X4/DO1	LA_TabPos.bDriveReady
X107/BD2	-	X4/DO2	LA_TabPos.bInTarget
		X4/DO3	LA_TabPos.bHomePosAvailable

When the profile is defined, the operating mode in the Lenze setting is changed simultaneously:

bPosProfileNo_4 (DI4)	bPosProfileNo_2 (DI5)	bPosProfileNo_1 (DI6)	Selected profile	Activation of operating mode
FALSE	FALSE	FALSE	0	Speed follower
FALSE	FALSE	TRUE	1	Homing
FALSE	TRUE	FALSE	2	Manual jog
FALSE	TRUE	TRUE	3	Positioning
...
TRUE	TRUE	TRUE	7	...

8.4.3.4 Terminal 16

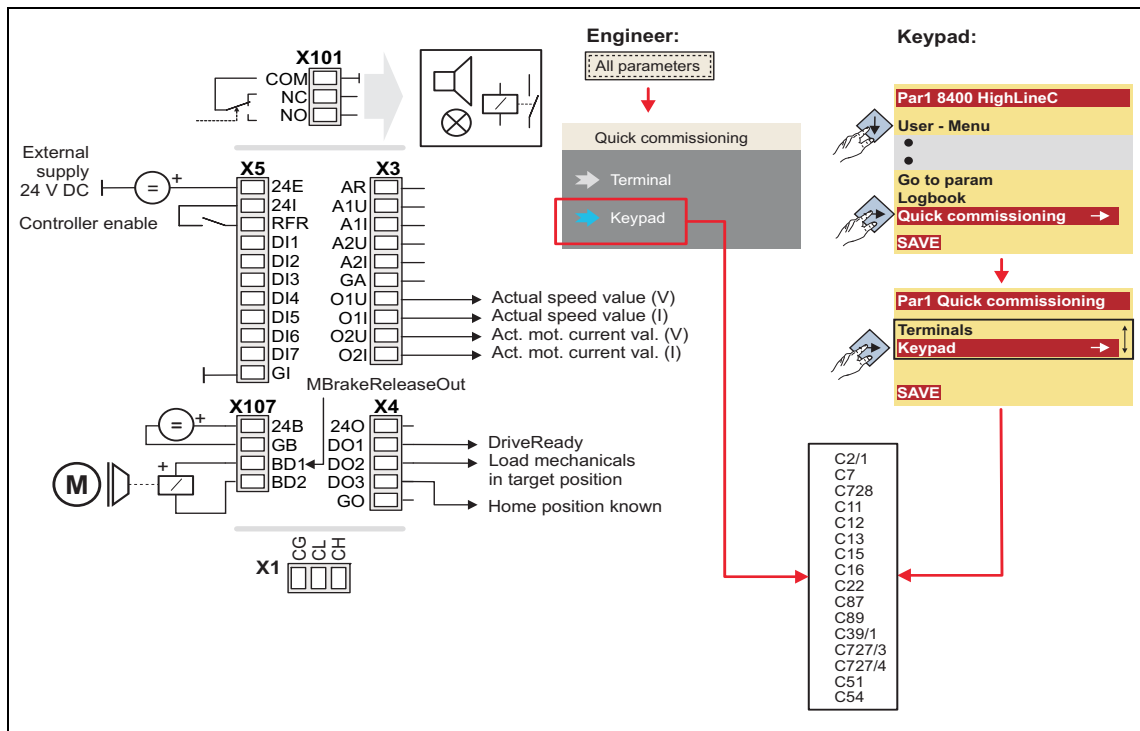


Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_TabPos.bDriveFail		
X5/RFR	LA_TabPos.bFailReset	X3/A1U	LA_TabPos.nMainSetValue_a 10 V \equiv 100 % reference speed (C00011)
X5/DI1	-	X3/A1I	-
X5/DI2	-	X3/A2U	-
X5/DI3	LA_TabPos.bManJogPos	X3/A2I	-
X5/DI4	LA_TabPos.bManJogNeg	X3/O1U	LA_TabPos.nMotorSpeedAct_a 10 V \equiv 100 % reference speed (C00011)
X5/DI5	LA_TabPos.bPosProfileNo_2	X3/O1I	-
X5/DI6	LA_TabPos.bPosProfileNo_1	X3/O2U	LA_TabPos.nMotorCurrent_a 10V \equiv 100% of I_{max_mot} (C00022)
X5/DI7	LA_TabPos.bPosExecute	X3/O2I	-
X107/BD1	LA_TabPos.bMBrakeReleaseOut	X4/DO1	LA_TabPos.bDriveReady
X107/BD2	-	X4/DO2	LA_TabPos.bInTarget
		X4/DO3	LA_TabPos.bHomePosAvailable

When the profile is defined, the operating mode in the Lenze setting is changed simultaneously:

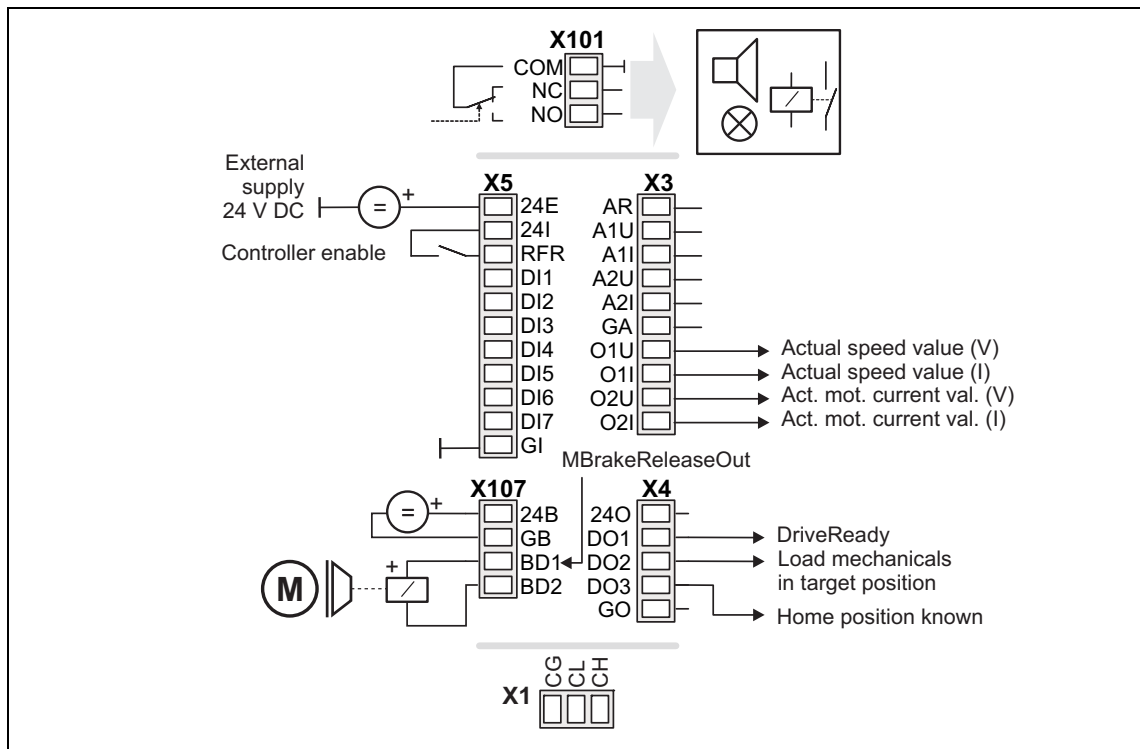
bPosProfileNo_2 (DI5)	bPosProfileNo_1 (DI6)	Selected profile	Activation of operating mode
FALSE	FALSE	0	Speed follower
FALSE	TRUE	1	Homing
TRUE	FALSE	2	Manual jog
TRUE	TRUE	3	Positioning

8.4.3.5 Keypad



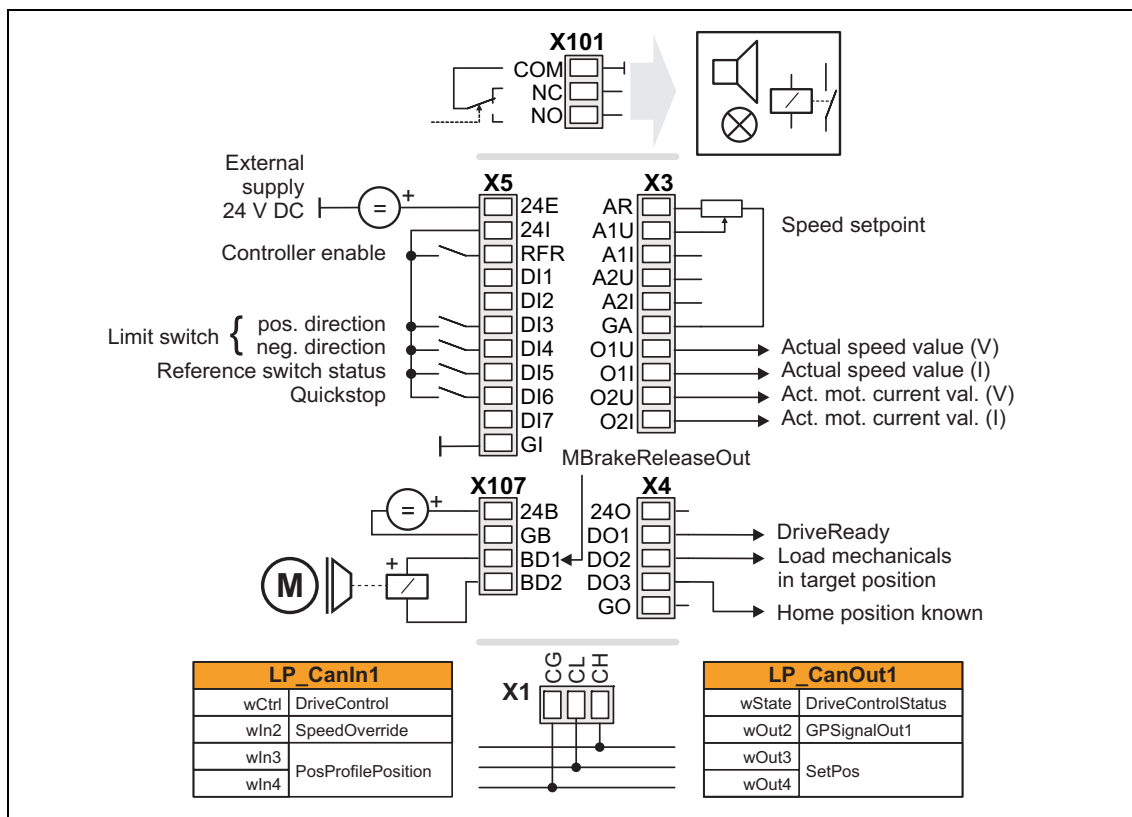
Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_TabPos.bDriveFail		
X5/RFR	LA_TabPos.bFailReset	X3/A1U	LA_TabPos.nMainSetValue_a 10 V ≡ 100 % reference speed (C00011)
X5/DI1	-	X3/A1I	-
X5/DI2	-	X3/A2U	-
X5/DI3	-	X3/A2I	-
X5/DI4	-	X3/O1U	LA_TabPos.nMotorSpeedAct_a 10 V ≡ 100 % reference speed (C00011)
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	LA_TabPos.nMotorCurrent_a 10V ≡ 100% of I _{max_mot} (C00022)
X5/DI7	-	X3/O2I	-
X107/BD1	LA_TabPos.bBrakeReleaseOut	X4/DO1	LA_TabPos.bDriveReady
X107/BD2	-	X4/DO2	LA_TabPos.bInTarget
		X4/DO3	LA_TabPos.bHomePosAvailable

8.4.3.6 PC



Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_TabPos.bDriveFail		
X5/RFR	LA_TabPos.bFailReset	X3/A1U	-
X5/DI1	-	X3/A1I	-
X5/DI2	-	X3/A2U	-
X5/DI3	-	X3/A2I	-
X5/DI4	-	X3/O1U	LA_TabPos.nMotorSpeedAct_a 10 V = 100 % reference speed (C00011)
X5/DI5	-	X3/O1I	
X5/DI6	-	X3/O2U	LA_TabPos.nMotorCurrent_a 10V = 100% of I _{max_mot} (C00022)
X5/DI7	-	X3/O2I	
X107/BD1	LA_TabPos.bMBrakeReleaseOut	X4/DO1	LA_TabPos.bDriveReady
X107/BD2	-	X4/DO2	LA_TabPos.bInTarget
		X4/DO3	LA_TabPos.bHomePosAvailable

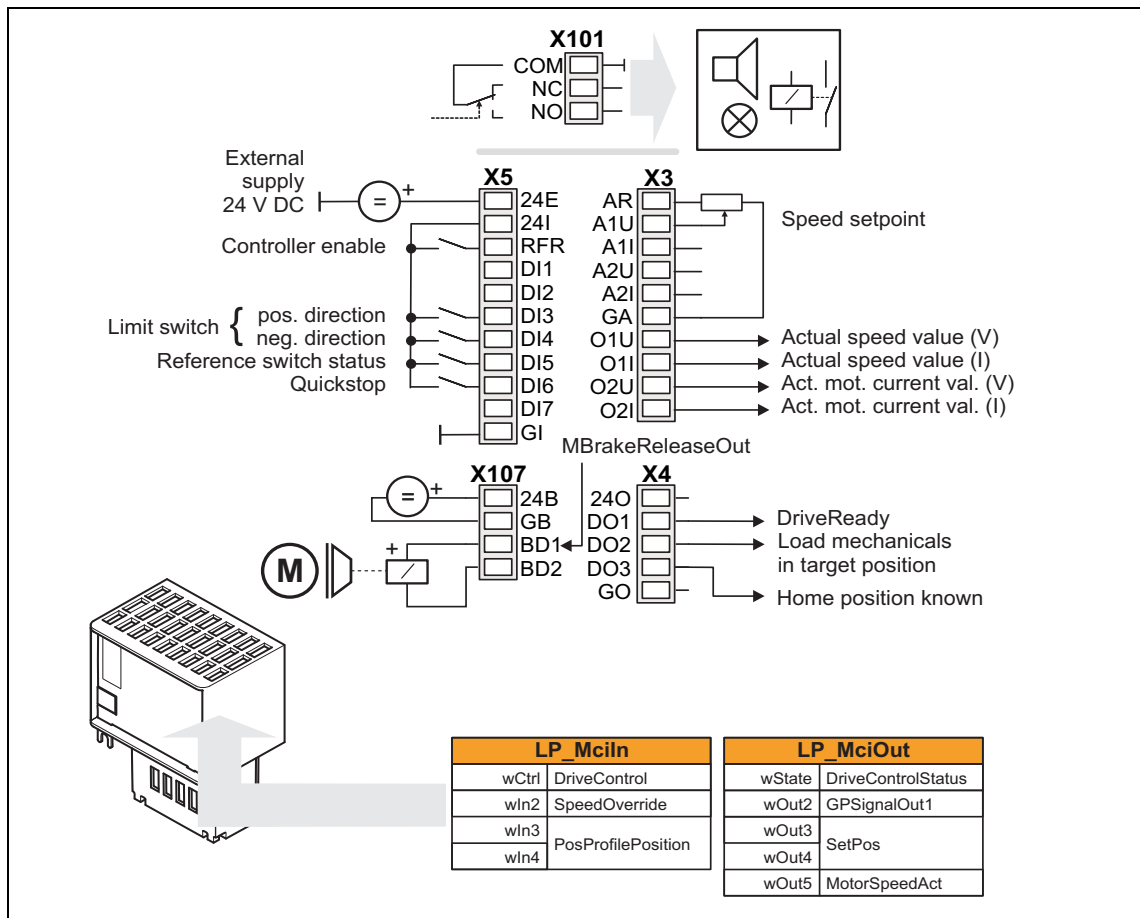
8.4.3.7 CAN



Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_TabPos.bDriveFail		
X5/RFR	LA_TabPos.bFailReset	X3/A1U	LA_TabPos.nMainSetValue_a 10 V = 100 % reference speed (C00011)
X5/DI1	-	X3/A1I	-
X5/DI2	-	X3/A2U	-
X5/DI3	LA_TabPos.bLimitSwitchPos	X3/A2I	-
X5/DI4	LA_TabPos.bLimitSwitchNeg	X3/O1U	LA_TabPos.nMotorSpeedAct_a 10 V = 100 % reference speed (C00011)
X5/DI5	LA_TabPos.bHomeMark	X3/O1I	-
X5/DI6	LA_TabPos.bSetQuickstop	X3/O2U	LA_TabPos.nMotorCurrent_a 10V = 100% of I _{max_mot} (C00022)
X5/DI7	LP_CanOut1: bState_B7	X3/O2I	-
X107/BD1	LA_TabPos.bMBrakeReleaseOut	X4/DO1	LA_TabPos.bDriveReady
X107/BD2	-	X4/DO2	LA_TabPos.bInTarget
		X4/DO3	LA_TabPos.bI _{max} Active

► [Process data assignment for fieldbus communication \(513\)](#)

8.4.3.8 MCI



Connection	Assignment	Connection	Assignment
X101/NC-NO	LA_TabPos.bDriveFail		
X5/RFR	LA_TabPos.bFailReset	X3/A1U	LA_TabPos.nMainSetValue_a 10 V ≙ 100 % reference speed (C00011)
X5/DI1	-	X3/A1I	-
X5/DI2	-	X3/A2U	-
X5/DI3	LA_TabPos.bLimitSwitchPos	X3/A2I	-
X5/DI4	LA_TabPos.bLimitSwitchNeg	X3/O1U	LA_TabPos.nMotorSpeedAct_a 10 V ≙ 100 % reference speed (C00011)
X5/DI5	LA_TabPos.bHomeMark	X3/O1I	-
X5/DI6	LA_TabPos.bSetQuickstop	X3/O2U	LA_TabPos.nMotorCurrent_a 10V ≙ 100% of I _{max_mot} (C00022)
X5/DI7	LP_MciOut: bState_B7	X3/O2I	-
X107/BD1	LA_TabPos.bBrakeReleaseOut	X4/DO1	LA_TabPos.bDriveReady
X107/BD2	-	X4/DO2	LA_TabPos.bInTarget
		X4/DO3	LA_TabPos.bI _{max} Active

► [Process data assignment for fieldbus communication](#) (513)

8.4.4 Process data assignment for fieldbus communication

The fieldbus communication is connected (preconfigured) to the previously selected technology application by selecting the corresponding control mode in [C00007](#):

- "30: [CAN](#)" for the connection to the system bus (CAN)
- "40: [MCI](#)" for the connection to a plugged-on communication module (e.g. PROFIBUS)

The assignment of the process data words depends only on the application, not on the bus system used:

Input words	Name	Assignment
Word 1	DriveControl	Control word <ul style="list-style-type: none"> • For bit assignment see the table below.
Word 2	SpeedOverride	Value for speed override <ul style="list-style-type: none"> • Percentage multiplier for the currently active speed. • 16384 \equiv 100 % of the maximum traversing speed (display in C01211/1). • Values > 16384 are ignored. • If the override value is 0 %, the drive is brought to a standstill. ▶ Speed override (□ 652)
Word 3 and 4	PosProfilePosition	Selection of the target position in [increments] <ul style="list-style-type: none"> • The mode for calculating the position is selected in C01296/1. • 65535 [Increments] \equiv 1 motor revolution • The position resolution, i.e. how many increments form one unit, is displayed in C01205.
Words 5 ... 16	-	Not preconfigured <ul style="list-style-type: none"> • Only available in control mode "40: MCI".

Control word	Name	Function
Bit 0	MckOperationMode_1	Binary-coded selection of the operating mode of the Motion Control Kernel <ul style="list-style-type: none"> • For a detailed description of the individual control bits, see chapter "MCK control word". (□ 560)
Bit 1	MckOperationMode_2	
Bit 2	MckOperationMode_4	
Bit 3	CINH	1 \equiv Inhibit drive controller (controller inhibit): The drive controller changes to the device state " SwitchedOn ". <ul style="list-style-type: none"> ▶ Enable/Inhibit controller (□ 107)
Bit 4	PosProfileNo_1	Selection of the profile number <ul style="list-style-type: none"> ▶ Stipulation of the profile to be executed (□ 644)
Bit 5	PosProfileNo_2	
Bit 6	PosProfileNo_4	
Bit 7	PosProfileNo_8	
Bit 8	PosExecute	1 \equiv Start travel job <ul style="list-style-type: none"> ▶ Positioning (□ 633)
Bit 9	EnableSpeedOverride	1 \equiv Activate speed override <ul style="list-style-type: none"> ▶ Speed override (□ 652)
Bit 10	HomeSetPosition	1 \equiv Set home position <ul style="list-style-type: none"> ▶ Homing (□ 606)
Bit 11	FailReset	1 \equiv Reset error message <ul style="list-style-type: none"> ▶ Reset error message (□ 700)
Bit 12	ManJogNeg	Manual jog in positive/negative direction <ul style="list-style-type: none"> ▶ Manual jog (□ 625)
Bit 13	ManJogPos	
Bit 14	-	Free control bit 14 (not assigned, freely assignable)
Bit 15	-	Free control bit 15 (not assigned, freely assignable)

Output words	Name	Assignment
Word 1	DriveControlStatus	Status word <ul style="list-style-type: none"> For bit assignment see the table below.
Word 2	GPSignalOut1	Analog signal monitor: Output signal 1 <ul style="list-style-type: none"> The selection of the signal source to output is executed in C00410/1. Gain and offset for the output signal can be parameterised in C00413/1 and C00413/2. For a detailed functional description see the L_SignalMonitor_a FB.
Word 3 and 4	SetPos	Absolute position setpoint in [increments] <ul style="list-style-type: none"> 65535 [increments] \equiv 1 motor revolution The position resolution, i.e. how many increments form one unit, is displayed in C01205.
Word 5	MotorSpeedAct	Actual speed value <ul style="list-style-type: none"> Scaling: 16384 \equiv 100 % reference speed (C00011) Only available in control mode "40: MCI".
Word 6 ... 16	-	Not preconfigured <ul style="list-style-type: none"> Only available in control mode "40: MCI".

Status word	Name	Status
Bit 0	DriveFail	1 \equiv Drive controller in error status <ul style="list-style-type: none"> "Fault" device status is active.
Bit 1	GPSignalOut1	Binary signal monitor: Output signals 1 & 2 <ul style="list-style-type: none"> The signal sources to be output are selected in C00411/1...2. A bit coded inversion of the output signals can be parameterised in C00412. For a detailed functional description see FB L_SignalMonitor_b.
Bit 2	GPSignalOut2	
Bit 3	ClnhActive	1 \equiv Controller inhibit is active
Bit 4	DriveReady	1 \equiv Drive controller is ready for operation <ul style="list-style-type: none"> "SwitchedOn" device status is active. The drive is in this device status if the DC bus voltage is applied and the controller is still inhibited by the user (controller inhibit).
Bit 5	DigitalInput5	Signal from the digital input DI5
Bit 6	DigitalInput6	Signal from the digital input DI6
Bit 7	DigitalInput7	Signal from the digital input DI7
Bit 8	InTarget	1 \equiv Target position (actual value) is in the target window
Bit 9	ProfileBusy	1 \equiv Profile positioning is active
Bit 10	HomePosAvailable	1 \equiv Home position is known
Bit 11	SpeedActCompare	Result of the speed comparison (detection of speed=0) <ul style="list-style-type: none"> In case of the "Open loop" operation: <ul style="list-style-type: none"> 1 \equiv Speed setpoint < comparison value (C00024) For "Closed loop" operation: <ul style="list-style-type: none"> 1 \equiv actual speed value < comparison value (C00024)
Bit 12	DigitalInput4	Signal from the digital input DI4
Bit 13	DigitalInput3	Signal from the digital input DI3
Bit 14	QSPisActive	1 \equiv Quick stop is active
Bit 15	-	Free status bit 15 (not assigned, freely assignable)

8.4.5 Setting parameters (short overview)

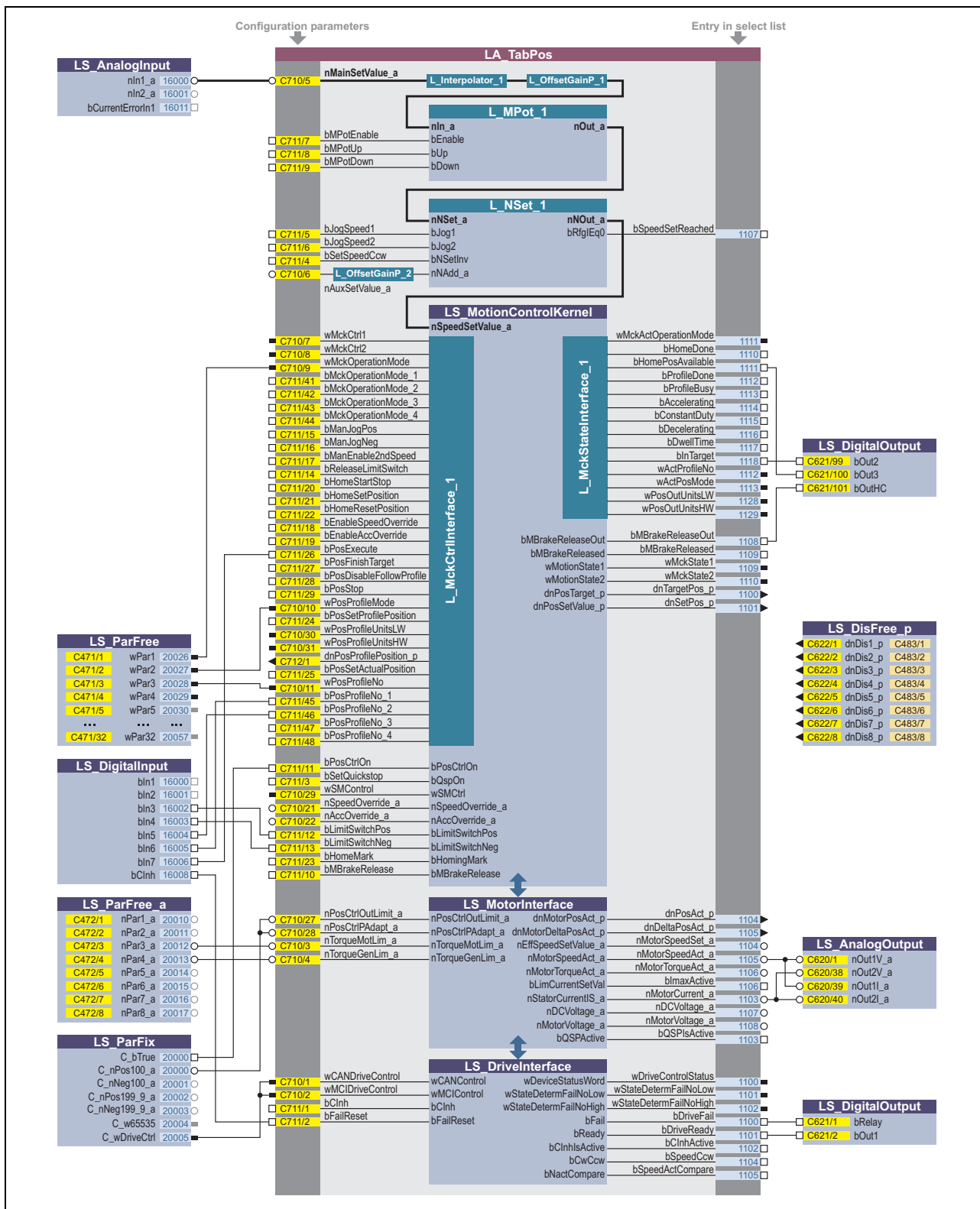
Parameter	Info	Lenze setting	
		Value	Unit
C00012	Accel. time - main setpoint	2.000	s
C00013	Decel. time - main setpoint	2.000	s
C00024	Comparison value N_Act	0.00	%
C00039/1	Fixed setpoint 1	40.00	%
C00039/2	Fixed setpoint 2	60.00	%
C00182	S-ramp time PT1	20.00	s
C00190	Setpoint arithmetic	0: NOut = NSet	
C00220	Accel. time - add. setpoint	0.000	s
C00221	Decel. time - add. setpoint	0.000	s
C00632/1	L_NSet_1: Blocking speed 1 max	0.00	%
C00632/2	L_NSet_1: Blocking speed 2 max	0.00	%
C00632/3	L_NSet_1: Blocking speed 3 max	0.00	%
C00633/1	L_NSet_1: Blocking speed 1 min	0.00	%
C00633/2	L_NSet_1: Blocking speed 2 min	0.00	%
C00633/3	L_NSet_1: Blocking speed 3 min	0.00	%
C00635	L_NSet_1: nMaxLimit	199.99	%
C00636	L_NSet_1: nMinLimit	-199.99	%
C00670	L_OffsetGainP_1: Gain	1.0000	
C00671	L_OffsetGainP_2: Gain	1.0000	
C00696	L_OffsetGainP_1: Offset	0.00	%
C00697	L_OffsetGainP_2: Offset	0.00	%
C00800	L_MPot_1: Upper limit	100.00	%
C00801	L_MPot_1: Lower limit	-100.00	%
C00802	L_MPot_1: Acceleration time	10.0	s
C00803	L_MPot_1: Deceleration time	10.0	s
C00804	L_MPot_1: Inactive fct.	0: Retain value	
C00805	L_MPot_1: Init fct.	0: Load last value	
C00806	L_MPot_1: Use	0: No	
C01297	Alternative function	Bit coded	
C01298/1	MCK operating mode at profile no. 0	1: Follower	
C01298/2	MCK operating mode at profile no. 1	2: Homing	
C01298/3	MCK operating mode at profile no. 2	3: ManualJog	
C01298/4	MCK operating mode at profile no. 3...15	4: Positioning	
C01299	MCKI: Status MCKInterface	-	

Related topics:

► ["GeneralPurpose" functions](#) (546)

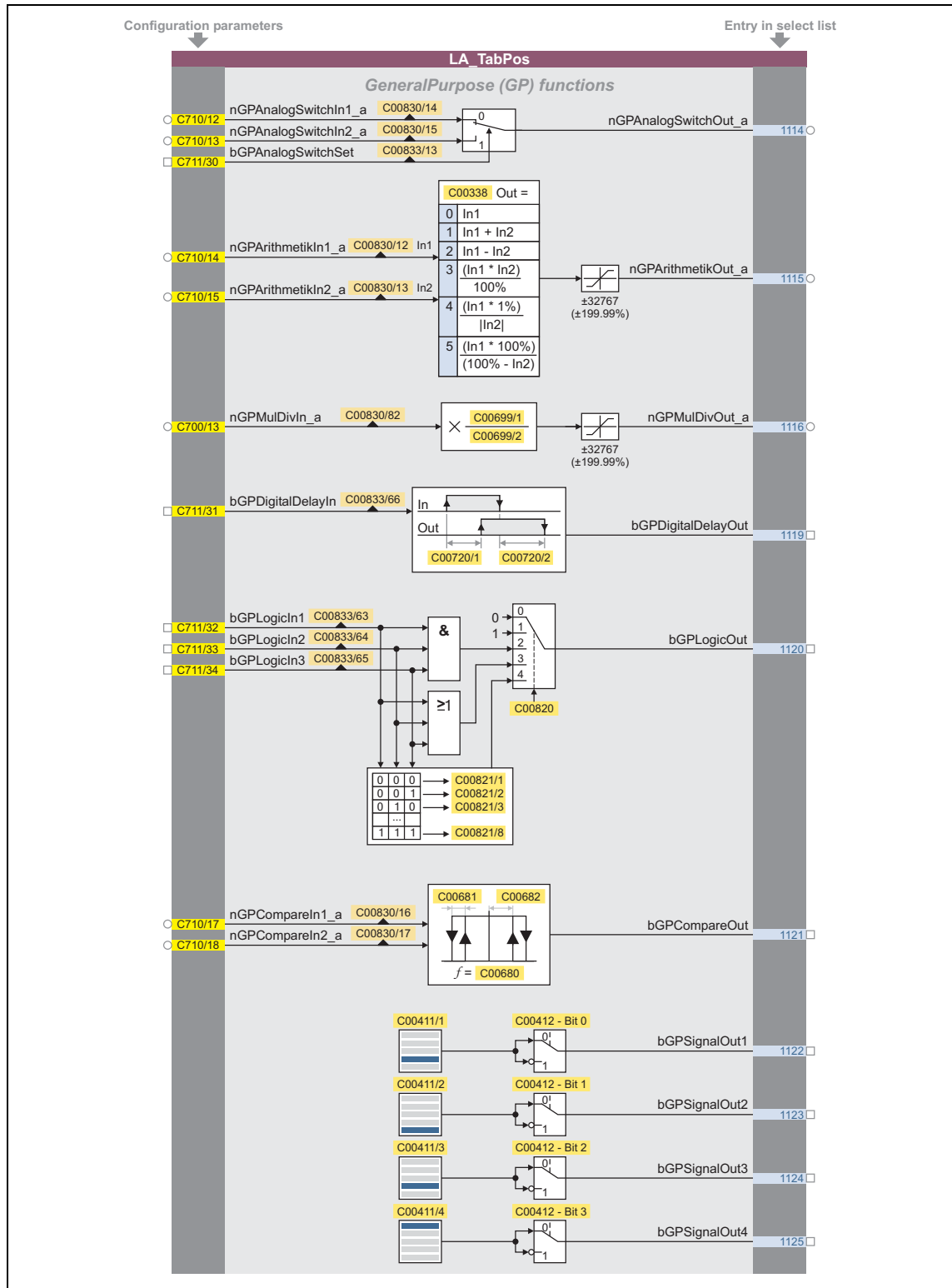
8.4.6 Configuration parameters

If required, the subcodes of [C00710](#), [C00711](#) and [C00712](#) serve to change the pre-configured assignment of the application inputs:

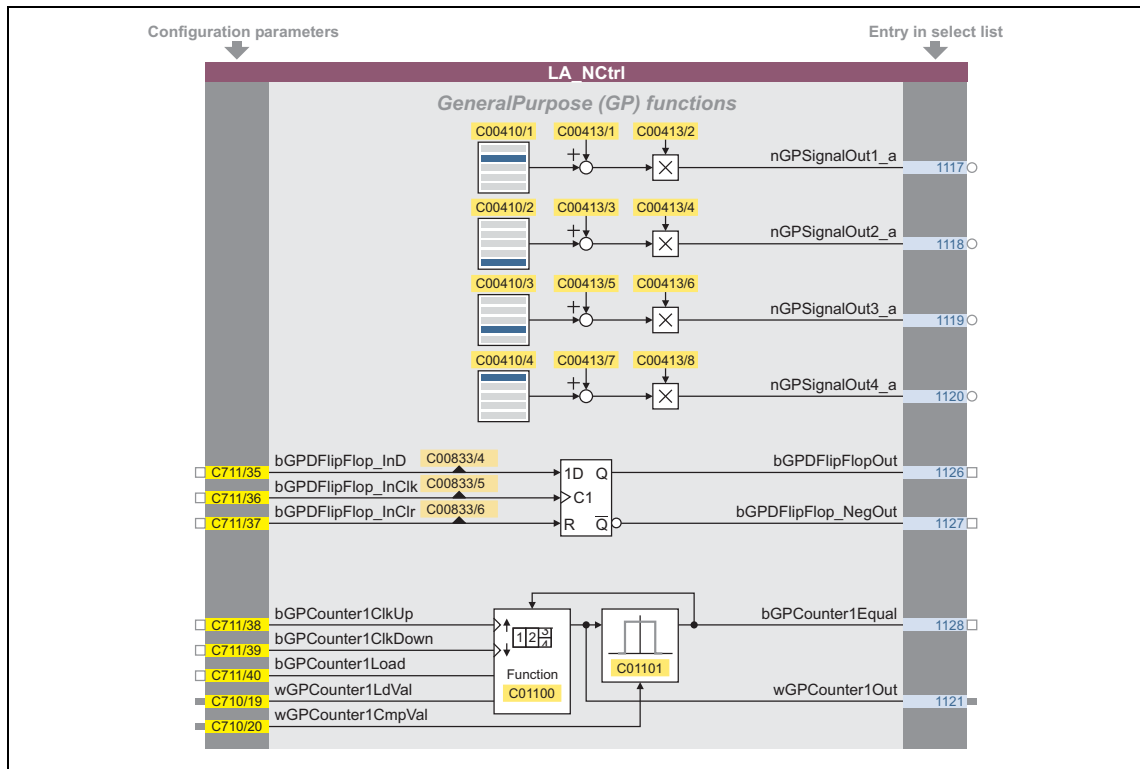


[8-14] Pre-assignment of the "Table positioning" application in the "Terminals 0" control mode

Configuration parameters for "GeneralPurpose" functions



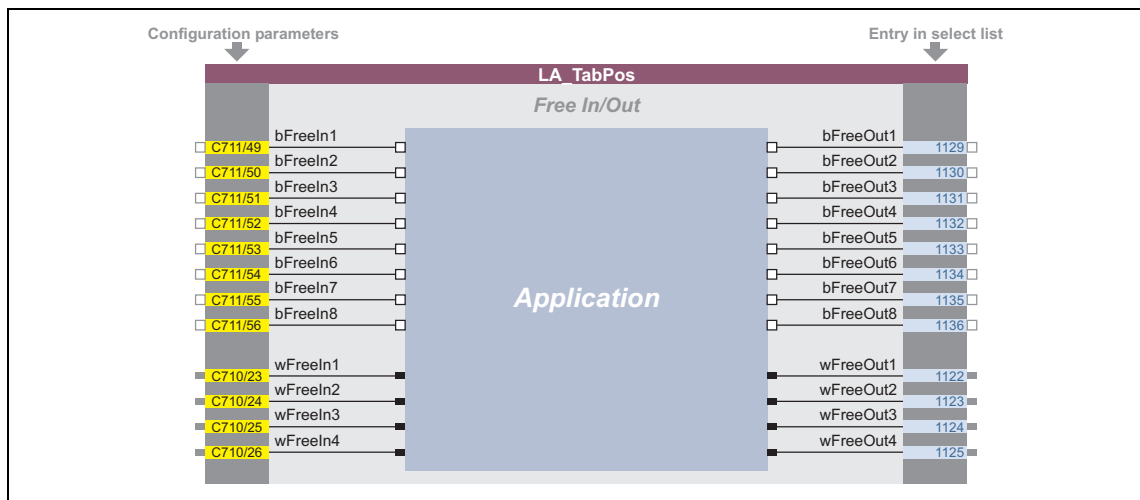
[8-15] "GeneralPurpose" functions



[8-16] "GeneralPurpose" functions (continuation)

Free inputs and outputs

These inputs can be freely interconnected in the application level. They can be used to transfer signals from the I/O level to the application level and vice versa.



[8-17] Free inputs/outputs

Related topics:

- ▶ [User-defined terminal assignment](#) (421)
- ▶ ["GeneralPurpose" functions](#) (546)

8.5 TA "Switch-off positioning"

The basic principle of this technology application is to travel to a switch-off sensor (e.g. a limit switch) in a speed-controlled manner and to stop as close as possible at this position. Unlike other positioning controls, the switch-off positioning neither has a position feedback nor calculates the path in advance. Thus, the accuracy that can be achieved depends on various factors such as the speed at which the switch-off sensor is advanced.

In addition, a pre-switch off can be implemented which requires a sufficient number of unassigned digital inputs on the controller which can be used to connect other sensors for the additional stop positions. These sensors effect a reduction in speed before the last switch-off sensor is reached.

Features

- Pre-configured control modes for terminals and bus control (with predefined process data connection to the fieldbus)
- Free configuration of input and output signals
- Offset, gain, and negation of main setpoint & additional setpoint
- Up to 15 fixed setpoints for speed and ramp time
- Adjustable setpoint ramp times
- Freely selectable, variable ramp shape
- Automatic holding brake control
- Quick stop (QSP) with adjustable ramp time
- Integrated, freely available "GeneralPurpose" functions:
Analog switch, arithmetic, multiplication/division, binary delay element, binary logic, analog comparison, D-flipflop
- Interface to the safety module (optional)
- Integration of encoder feedback
- Switch-off sensor management for the implementation of a pre-switch off

Decision criteria

Criteria	Switch-off positioning with constant load	Switch-off positioning with variable load
Operating mode	V/f characteristic without speed sensor. Alternatively for large breakaway torques: Use of a sensorless vector control (only applicable for horizontal movements).	
Limit switch evaluation	One limit switch is required per direction of movement. When the limit switch is reached, the drive is brought to a standstill led by the deceleration ramp or the QSP ramp.	One limit switch and an initiator are required for fast/slow changeover per direction of movement. When the initiator has been reached, the speed of the drive is reduced to a creeping speed (fixed setpoint 2) in a controlled way. When the limit switch is reached, the drive is brought to a standstill led by the deceleration ramp or the QSP ramp.

Criteria	Switch-off positioning with constant load	Switch-off positioning with variable load
Positioning accuracy at the motor shaft The positioning accuracy of the load depends, among other things, on the clearance and friction of the selected mechanics and has to be determined individually.	The ideal case is 5-10° at the motor shaft. Consider the influence of the motor temperature. In the case of a constant load, you can assume a good repeat accuracy during positioning. In the case of variable loads, you must take significant deviations into account.	5-10° at the motor shaft. As the positioning is executed in a creeping speed, a good repeat accuracy is reached even for variable loads.
Speed setting range	1 : 50, based on 50Hz and M_n	1 : 50, based on 50Hz and M_n
Typical applications	Switch-off positioning with constant load, e.g. travelling drive, roll-up door.	Switch-off positioning with variable load, e.g. travelling drive, conveying belt, hoists approaching a stop position.

System limits and exclusion criteria

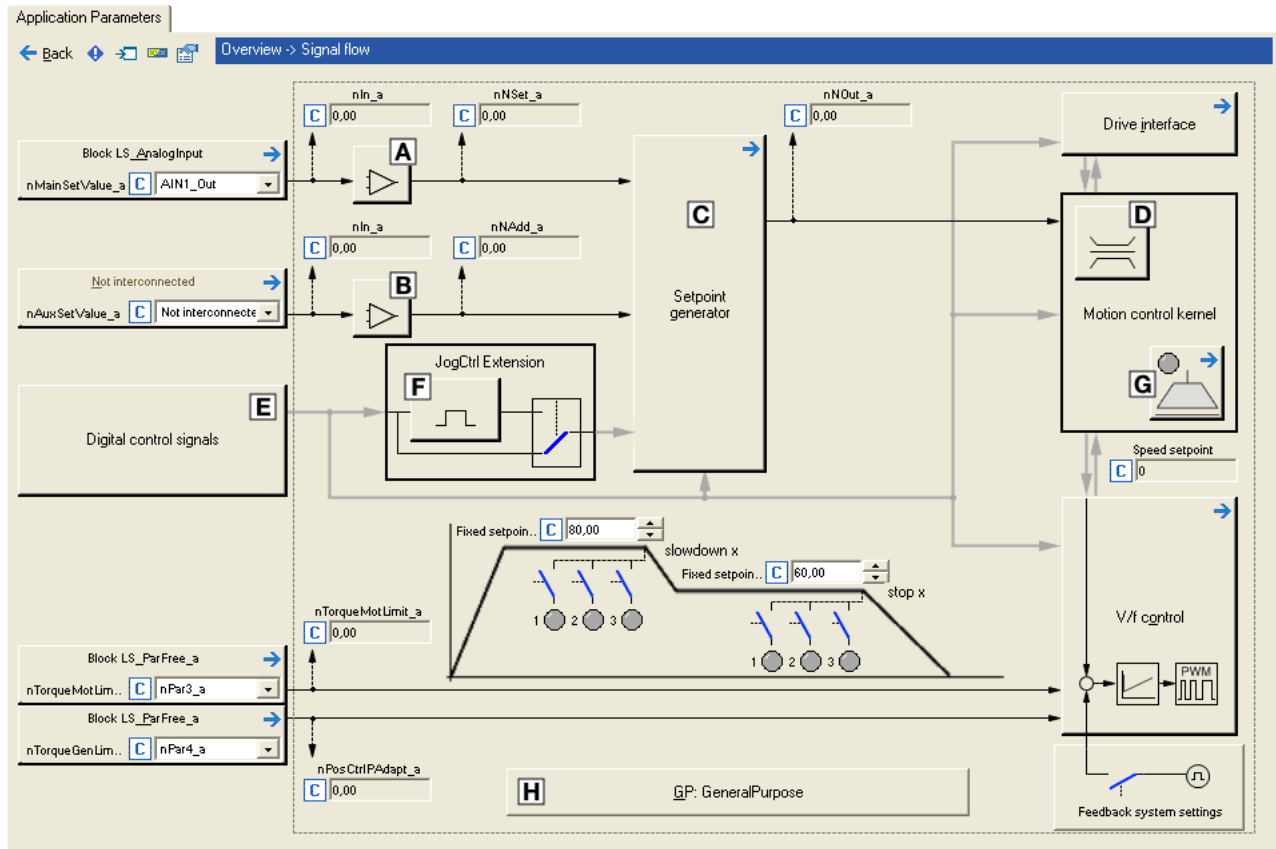
They result from the non-compliance with the decision criteria.

- Compared to systems with speed feedback, the positioning and repeat accuracy is reduced.
- Due to the mechanical hardware limit switches, this concept is only applicable for systems with only a few fixed positions. Changing the target position during the operation or the teaching is not possible.
- If necessary, additional functions like manual jog or homing must be realised externally, e.g. via a control.
- As the 8400 TopLine controller does not meet safety-related functions except STO (Safe Torque Off), you must observe that all safety-related aspects are realised by the plant instructor.
- Especially in the case of an outdoor use or in wet areas, you must consider the corresponding discharge currents when operated with a fault current circuit breaker.
- A table positioning or sequential positioning control is required for highly dynamic applications and jerk-free traversing profiles which is available with the "HighLine" device version.

Related topics:

- ▶ [Commissioning of the "Switch-off positioning" technology application](#) (82)

8.5.1 Basic signal flow



[8-18] Signal flow of the switch-off positioning

- ☐ A Main speed setpoint offset and gain ([L_OffsetGainP_1](#))
- ☐ B Additional speed setpoint offset and gain ([L_OffsetGainP_2](#))
- ☐ C Setpoint generator ([L_NSet_1](#))
- ☐ D Speed setpoint input limitation
- ☐ E Terminal assignment & display of digital control signals
- ☐ F Selection of edge/level for tripping the ramp down and stop functions ([L_LogCtrlExtension_1](#))
- ☐ G [Holding brake control](#)
- ☐ H Integrated disposable "[GeneralPurpose](#)" functions: Analog switch, arithmetic, multiplication/division, binary delay element, binary logic, analog comparison, D-flipflop

8.5.2 Internal interfaces | application block "LA_SwitchPos"




**Note!**

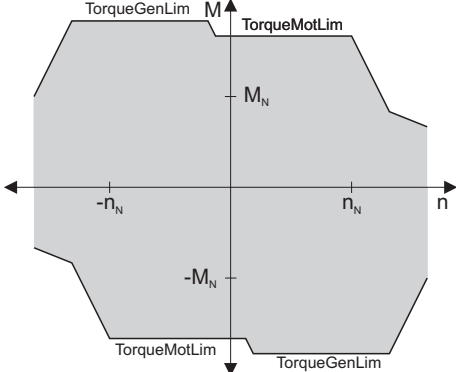
The connectors grayed out in the following table are hidden in the function block editor in the Lenze setting.

- These connections can be shown via the **Connector visibilities** command in the *Context menu* of the application block.

Inputs

Identifier	Data type	Information/possible settings
wCANDriveControl	WORD	Control word via system bus (CAN) for device control <ul style="list-style-type: none"> • See the "wCANControl/wMCIControl control words" subchapter of the chapter on device control for a detailed description of the individual control bits.
wMCIDriveControl	WORD	Control word via communication module (e.g. PROFIBUS) for device control <ul style="list-style-type: none"> • See the "wCANControl/wMCIControl control words" subchapter of the chapter on device control for a detailed description of the individual control bits.
wSMControl	WORD	Interface to the optional safety system. <ul style="list-style-type: none"> • Setting control bit 0 ("SafeStop1") in this control word causes e.g. the automatic deceleration of the drive to standstill within this application (in the Motion Control Kernel). • See the subchapter "Interface to safety system" of the chapter on basic drive functions for a detailed description of the individual control bits.
bCInh	BOOL	Enable/Inhibit controller
		<div>FALSE</div> <div>Enable controller: The controller switches to the "OperationEnabled" device status if no other source for controller inhibit is active. <ul style="list-style-type: none"> • C00158 provides a bit coded representation of all active sources/triggers of a controller inhibit. </div>
bFailReset	BOOL	Reset error message
		<div>In the Lenze setting this input is connected to the digital input controller enable so that a possibly existing error message is reset together with the controller enable (if the cause for the fault is eliminated).</div> <div>TRUE</div> <div>The current fault is reset, if the cause for the fault is eliminated. <ul style="list-style-type: none"> • If the fault still exists, the error status remains unchanged. </div>
bSetQuickstop	BOOL	Enable quick stop (QSP) <ul style="list-style-type: none"> • Also see device command "Activate/deactivate quick stop".
		<div>TRUE</div> <div>Activate quick stop <ul style="list-style-type: none"> • Motor control is decoupled from the setpoint selection and, within the deceleration time parameterised in C00105, the motor is brought to a standstill ($n_{act} = 0$). • The motor is kept at a standstill during closed-loop operation. • A pulse inhibit is set if the auto-DCB function has been activated via C00019. </div>
		<div>FALSE</div> <div>Deactivate quick stop <ul style="list-style-type: none"> • The quick stop is deactivated if no other source for the quick stop is active. • C00159 displays a bit code of active sources/causes for the quick stop. </div>

Identifier	Data type	Information/possible settings
bSetDCBrake	BOOL	Manual DC-injection braking (DCB) <ul style="list-style-type: none"> Detailed information on DC-injection braking is provided in the motor control chapter, subchapter "DC-injection braking".
		 Note! Holding braking is not possible when this braking mode is used! Use the basic " Holding brake control " function for controlling the holding brake with a low rate of wear.
		FALSE Deactivate DC-injection braking.
		TRUE Activate DC-injection braking, i.e. the drive is brought to a standstill by means of DC-injection braking. <ul style="list-style-type: none"> The braking effect stops when the rotor is at standstill. After the hold time (C00107) has expired, the controller sets the pulse inhibit.
bRFG_Stop	BOOL	Ramp function generator: Maintain the current value of the main setpoint integrator <ul style="list-style-type: none"> The speed, for instance, of a running ramp process is immediately kept constant when <i>bRFG_Stop</i> is activated. At the same time, the acceleration/deceleration jumps to the value "0". For a detailed functional description see the L_NSet FB.
		TRUE The current value of the main setpoint integrator is held.
nVoltageAdd_a	INT	Additive voltage impression <ul style="list-style-type: none"> An additional setpoint for the motor voltage can be specified via this process input. If there are, for instance, different loads at the motor output end, it is possible to apply a voltage boost at the starting time. If the value is negative, the voltage is reduced. Scaling: 16384 \equiv 1000 V
		 Stop! Values selected too high may cause the motor to heat up due to the resulting current!
nBoost_a	INT	Additional setpoint for the motor voltage at speed = 0 <ul style="list-style-type: none"> The entire voltage-frequency characteristic is provided with an offset. Scaling: 16384 \equiv 1000 V
		 Stop! Values selected too high may cause the motor to heat up due to the resulting current!
nPWMAngleOffset	INT	Additional offset for the electrical angle of rotation <ul style="list-style-type: none"> If a torque is connected, e.g. dynamic acceleration processes can be generated. Scaling: $\pm 32767 \equiv \pm 180^\circ$ angle of rotation

Identifier	Data type	Information/possible settings				
nTorqueMotLim_a nTorqueGenLim_a	INT	<p>Torque limitation in motor mode and in generator mode</p> <ul style="list-style-type: none">• These input signals are directly transferred to the motor control to limit the controller's maximum torque in motor and generator mode.• The drive cannot output a higher torque in motor/generator mode than set here.• The applied values (any polarity) are internally interpreted as absolute values.• If V/f characteristic control (VFCplus) is selected, limitation is <u>indirectly</u> performed via a so-called I_{\max} controller.• If sensorless vector control (SLVC) or servo control (SC) is selected, limitation has a <u>direct</u> effect on the torque-producing current component.• Scaling: $16384 \equiv 100 \% M_{\max}$ (C00057) <p>Torque limits in motor and generator mode:</p> 				
bSetSpeedCcw	BOOL	<p>Change of direction of rotation</p> <ul style="list-style-type: none">• For instance if a motor or gearbox is fixed laterally reversed to a machine part, but the setpoint selection should still be executed for the positive direction of rotation. <table><tr><td>FALSE</td><td>Clockwise rotation (Cw)</td></tr><tr><td>TRUE</td><td>Direction of rotation to the left (Ccw)</td></tr></table>	FALSE	Clockwise rotation (Cw)	TRUE	Direction of rotation to the left (Ccw)
FALSE	Clockwise rotation (Cw)					
TRUE	Direction of rotation to the left (Ccw)					
bRLQCw	BOOL	<p>Activate clockwise rotation (fail-safe)</p> <ul style="list-style-type: none">• For a detailed functional description see the L_RLO FB. <table><tr><td>FALSE</td><td>Quick stop</td></tr><tr><td>TRUE</td><td>CW rotation</td></tr></table>	FALSE	Quick stop	TRUE	CW rotation
FALSE	Quick stop					
TRUE	CW rotation					
bRLQCcw	BOOL	<p>Activate counter-clockwise rotation (fail-safe)</p> <ul style="list-style-type: none">• For a detailed functional description see the L_RLO FB. <table><tr><td>FALSE</td><td>Quick stop</td></tr><tr><td>TRUE</td><td>Counter-clockwise rotation</td></tr></table>	FALSE	Quick stop	TRUE	Counter-clockwise rotation
FALSE	Quick stop					
TRUE	Counter-clockwise rotation					
nMainSetValue_a	INT	<p>Main speed setpoint</p> <ul style="list-style-type: none">• Offset and gain of this input signal can be set in C00696 and C00670 for a simple signal adjustment of a setpoint encoder.• Scaling: $16384 \equiv 100 \% \text{ reference speed}$ (C00011)• The main setpoint is transformed to a speed setpoint in the setpoint encoder via a ramp function generator with linear or S-shaped ramps.• Upstream to the ramp function generator, a blocking speed masking function and a setpoint MinMax limitation are effective.• For a detailed functional description see the L_NSet FB.				
nAuxSetValue_a	INT	<p>Additional speed setpoint</p> <ul style="list-style-type: none">• Offset and gain of this input signal can be set in C00697 and C00671 for a simple signal adjustment of a setpoint encoder.• Scaling: $16384 \equiv 100 \% \text{ reference speed}$ (C00011)• The additional speed setpoint can be linked arithmetically with the main speed setpoint behind the ramp function generator.• The additional speed setpoint can be shown via ramp times of a second ramp function generator.• For a detailed functional description see the L_NSet FB.				

Identifier	Data type	Information/possible settings
Switch-off positioning		
bJogCtrlInputSel1 bJogCtrlInputSel2	BOOL	Selection inputs for a binary coded selection of the switch-off position 1 ... 3 <ul style="list-style-type: none"> Activation of the signal pairs <i>bJogCtrlSlowDown1/bJogCtrlStop1</i>, <i>bJogCtrlSlowDown2/bJogCtrlStop2</i> or <i>bJogCtrlSlowDown3/bJogCtrlStop3</i> according to the Truth table for activating the pre-switch off.
bJogCtrlRfGIn	BOOL	Ramping down of the setpoint generator in the downstream L_NSet FB according to the Truth table for activating the pre-switch off
bJogCtrlJog1 bJogCtrlJog2	BOOL	Selection inputs for fixed changeover setpoints (JOG setpoints) for the main setpoint <ul style="list-style-type: none"> If the pre-switch off is inactive (<i>bJogCtrlInputSel1</i> and <i>bJogCtrlInputSel2</i> are both set to FALSE), the two control signals are passed through 1:1 to the downstream FB L_NSet. To achieve the desired behaviour (starting at high speed, pre-switch off at low speed), both inputs must be set to TRUE. Fixed setpoint 2 must be less than fixed setpoint 3! Otherwise, the drive will start at a low speed and accelerate after the pre-switch off. If in addition to the inputs <i>bJogCtrlJog1</i> and <i>bJogCtrlJog2</i> the selection inputs <i>bJogSpeed4</i> and <i>bJogSpeed8</i> are assigned, different fixed setpoints can result from this and the drive may travel with different speeds than selected via <i>bJogCtrlJog1</i> and <i>bJogCtrlJog2</i>.
bJogCtrlSlowDown1 bJogCtrlSlowDown2 bJogCtrlSlowDown3	BOOL	Activation of fixed setpoint 2 in the downstream L_NSet FB <ul style="list-style-type: none"> These inputs only have a function if they have been previously activated via <i>bJogCtrlInputSel1</i> and <i>bJogCtrlInputSel2</i> (see Truth table for activating the pre-switch off).
bJogCtrlStop1 bJogCtrlStop2 bJogCtrlStop3	BOOL	Ramping down of the ramp function generator in the downstream L_NSet FB <ul style="list-style-type: none"> These inputs only have a function if they have been previously activated via <i>bJogCtrlInputSel1</i> and <i>bJogCtrlInputSel2</i> (see Truth table for activating the pre-switch off).
bJogSpeed4 bJogSpeed8	BOOL	Selection inputs for fixed changeover setpoints (JOG setpoints) for the main setpoint <ul style="list-style-type: none"> A fixed setpoint for the setpoint generator can be activated instead of the main setpoint via these selection inputs. The selection inputs are binary coded. For a detailed functional description see the L_NSet FB.
bJogRamp1 ... bJogRamp8	BOOL	Selection inputs for alternative acceleration/deceleration times for the main setpoint <ul style="list-style-type: none"> The four selection inputs are binary coded, therefore 15 alternative acceleration/deceleration times can be selected. For main setpoint <i>nMainSetValue_a</i>, the set acceleration time (C00012) and deceleration time (C00013) are active in the case of the binary coded selection "0" (all inputs = FALSE or not assigned). Alternative acceleration times are selected in C00101/1...15. The selection of the alternative deceleration times is carried out in C00103/1...15. For a detailed functional description see the L_NSet FB.
MCK basic functions		
bMBrakeRelease	BOOL	Holding brake control : Release/apply brake <ul style="list-style-type: none"> In conjunction with the operating mode selected in C02580 (Lenze setting: "Brake control off").
	FALSE	Apply brake. <ul style="list-style-type: none"> During automatic operation, the internal brake logic controls the brake.
	TRUE	Release brake manually (forced release). <ul style="list-style-type: none"> Note! The brake can also be released if the controller is inhibited! During automatic operation, the internal brake logic is deactivated and the brake is released (supervisor operation). If a controller inhibit has been set by the brake control, it will be deactivated. In semi-automatic operation, the brake is released including feedforward control.

Identifier	Data type	Information/possible settings				
GP: GeneralPurpose The following inputs are interconnected with logic/arithmetic functions on application level for free usage. ▶ "GeneralPurpose" functions						
nGPAAnalogSwitchIn1_a nGPAAnalogSwitchIn2_a	INT	Analog switch : Input signals <ul style="list-style-type: none">The input signal selected via the selection input <i>bGPAAnalogSwitchSet</i> is output at output <i>nGPAAnalogSwitchOut_a</i>.				
bGPAAnalogSwitchSet	BOOL	Analog switch : Selection input <table><tr><td>FALSE</td><td><i>nGPAAnalogSwitchOut_a</i> = <i>nGPAAnalogSwitchIn1_a</i></td></tr><tr><td>TRUE</td><td><i>nGPAAnalogSwitchOut_a</i> = <i>nGPAAnalogSwitchIn2_a</i></td></tr></table>	FALSE	<i>nGPAAnalogSwitchOut_a</i> = <i>nGPAAnalogSwitchIn1_a</i>	TRUE	<i>nGPAAnalogSwitchOut_a</i> = <i>nGPAAnalogSwitchIn2_a</i>
FALSE	<i>nGPAAnalogSwitchOut_a</i> = <i>nGPAAnalogSwitchIn1_a</i>					
TRUE	<i>nGPAAnalogSwitchOut_a</i> = <i>nGPAAnalogSwitchIn2_a</i>					
nGPArithmetikIn1_a nGPArithmetikIn2_a	INT	Arithmetic : Input signals <ul style="list-style-type: none">The arithmetic function is selected in C00338.The result is output at output <i>nGPArithmetikOut_a</i>.				
nGPMulDivIn_a	INT	Multiplication/Division : Input signal <ul style="list-style-type: none">The factor for the multiplication can be set in C00699/1 (numerator) and C00699/2 (denominator).The result is output at output <i>nGPMulDivOut_a</i>.				
bGPDigitalDelayIn	BOOL	Binary delay element : Input signal <ul style="list-style-type: none">The on-delay can be set in C00720/1.The off-delay can be set in C00720/2.The time-delayed input signal is output at output <i>bGPDigitalDelayOut</i>.				
bGPLogicIn1 bGPLogicIn2 bGPLogicIn3	BOOL	Binary logic : Input signals <ul style="list-style-type: none">The logic operation is selected in C00820.The result is output at output <i>bGPLogicOut</i>.				
nGPCompareIn1_a nGPCompareIn2_a	INT	Analog comparison : Input signals <ul style="list-style-type: none">The comparison operation is selected in C00680.Hysteresis and window size can be set in C00680 and C00682.If the comparison statement is true, the output <i>bGPCompareOut</i> will be set to TRUE.				
bGPDFlipFlop_InD bGPDFlipFlop_InClk bGPDFlipFlop_InClr	BOOL	D-FlipFlop : Input signals <ul style="list-style-type: none">Data, clock and reset input				
Free inputs The following inputs can freely be interconnected on the application level. The signals can be transferred from the I/O level to the application level via these inputs.						
bFreeIn1 ... bFreeIn8	BOOL	Free inputs for digital signals				
wFreeIn1 ... wFreeIn4	WORD	Free inputs for 16-bit signals				
dnFreeIn1_p ... dnFreeIn2_p	DINT	Free inputs for 32-bit signals				

Outputs

Identifier	Data type	Value/meaning
wDriveControlStatus	WORD	Status word of the controller <ul style="list-style-type: none"> The status word contains information on the current status of the drive controller. See the "wDeviceStatusWord status word" subchapter of the chapter on device control for a detailed description of the bit assignment.
wStateDetermFailNoLow	WORD	Display of the status determining error (LOW word)

Identifier	Data type	Value/meaning
wStateDetermFailNoHigh	WORD	Display of the status determining error (HIGH word)
bDriveFail	BOOL	TRUE Drive controller in error status. • " Fault " device state is active.
bWarningActive	BOOL	TRUE A monitoring in the drive controller, for which the error response "Warning" or "WarningLocked" has been parameterised, responded.
bSafeTorqueOff	BOOL	TRUE Safe torque off. • " SafeTorqueOff " device status is active.
bDriveReady	BOOL	TRUE Controller is ready for operation. • " SwitchedOn " device status is active. • The drive is in this device status if the DC bus voltage is applied and the controller is still inhibited by the user (controller inhibit).
bCInhActive	BOOL	TRUE Controller inhibit is active.
bImpIsActive	BOOL	TRUE Pulse inhibit is active.
bQSPlsActive	BOOL	TRUE Quick stop is active.
bSpeedCcw	BOOL	Current direction of rotation FALSE Clockwise rotation (Cw) TRUE Direction of rotation to the left (Ccw)
bSpeedActCompare	BOOL	Result of the speed comparison (detection of speed=0) TRUE During open-loop operation: Speed setpoint < Comparison value (C00024) During closed-loop operation: Actual speed value < Comparison value (C00024)
blmaxActive	BOOL	"Current setpoint inside the limitation" status signal TRUE The current setpoint is internally limited (the drive controller operates at the maximum current limit).
bSpeedSetReached	BOOL	Status signal "setpoint = 0" TRUE Speed setpoint from the ramp function generator = 0
bSpeedActEqSet	BOOL	TRUE Actual speed value = speed setpoint
nMotorCurrent_a	INT	Current stator current/effective motor current • Scaling: 16384 \equiv 100 % I_{\max_mot} (C00022)
nMotorSpeedSet_a	INT	Speed setpoint • Scaling: 16384 \equiv 100 % reference speed (C00011)
nMotorSpeedAct_a	INT	Actual speed value • Scaling: 16384 \equiv 100 % reference speed (C00011)
nMotorTorqueAct_a	INT	Actual torque • In the "VFC (+encoder)" operating mode of the motor control, this value is determined from the current motor current and corresponds to the actual torque only by approximation. • Scaling: 16384 \equiv 100 % M_{\max} (C00057)
nDCVoltage_a	INT	Actual DC-bus voltage • Scaling: 16384 \equiv 1000 V
nMotorVoltage_a	INT	Current motor voltage/inverter output voltage • Scaling: 16384 \equiv 1000 V

Identifier	Data type	Value/meaning	
MCK basic functions			
bMBrakeReleaseOut	BOOL	Holding brake control : Trigger signal for the holding brake control switching element via a digital output <ul style="list-style-type: none">Use bit 0 in C02582 to activate inverted switching element triggering.	
		FALSE	Apply brake.
		TRUE	Release brake.
bMBrakeReleased	BOOL	Holding brake control : "Brake released" considering the brake release time <ul style="list-style-type: none">When the holding brake is triggered to close, <i>bMBrakeReleased</i> is immediately set to FALSE even if the brake closing time has not yet elapsed!	
		TRUE	Brake released (after the brake release time has expired).
GP: GeneralPurpose The following outputs are interconnected with logic/arithmetic functions on application level for free usage. ▶ "GeneralPurpose" functions			
nGPAalogSwitchInOut_a	INT	Analog switch : Output signal	
nGPArithmetikOut_a	INT	Arithmetic : Output signal	
nGPMulDivOut_a	INT	Multiplication/Division : Output signal	
bGPDigitalDelayOut	BOOL	Binary delay element : Output signal	
bGPLogicOut	BOOL	Binary logic : Output signal	
bGPCompareOut	BOOL	Analog comparison : Output signal	
bGPSignalOut1 ... bGPSignalOut4	BOOL	Binary signal monitor : Output signals <ul style="list-style-type: none">The signal sources to be output are selected in C00411/1...4.A bit coded inversion of the output signals can be parameterised in C00412.	
nGPSignalOut1_a ... nGPSignalOut4_a	BOOL	Analog signal monitor : Output signals <ul style="list-style-type: none">The signal sources to be output are selected in C00410/1...4.Gain and offset for each output signal can be parameterised in C00413/1...8.	
bGPDFlipFlop_Out	BOOL	D-FlipFlop : Output signal	
bGPDFlipFlop_NegOut	BOOL	D-FlipFlop : Negated output signal	
Free outputs The following outputs can freely be interconnected on the application level. The signals from the application level can be transferred to the I/O level via these outputs.			
bFreeOut1 ... bFreeOut8	BOOL	Free outputs for digital signals	
wFreeOut1 ... wFreeOut4	WORD	Free outputs for 16-bit signals	
dnFreeOut1_p dnFreeOut2_p	WORD	Free outputs for 32-bit signals	

8.5.2.1 Truth table for activating the pre-switch off

Input		Function	Response in the setpoint generator (FB L_NSet)
bJogCtrl InputSel1	bJogCtrl InputSel2		
FALSE	FALSE	Pre-switch off inactive	No response <ul style="list-style-type: none"> The input signal <i>bJogCtrlRfgIn</i> is output directly at output <i>bRfgOut</i>. The input signals <i>bJogCtrlJog1</i> and <i>bJogCtrlJog2</i> are passed through 1:1 to the downstream FB L_NSet for the selection of fixed setpoints.
TRUE	FALSE	The <i>bJogCtrlSlowDown1</i> and <i>bJogCtrlStop1</i> inputs are evaluated.	Pre-switch off can be activated <ul style="list-style-type: none"> If the slowdown function is activated via the selected <i>bJogCtrlSlowDown</i> input, fixed setpoint 2 is activated in the setpoint generator. If the stop function is activated via the selected <i>bJogCtrlStop</i> input, the setpoint generator is deactivated.
FALSE	TRUE	The <i>bJogCtrlSlowDown2</i> and <i>bJogCtrlStop2</i> inputs are evaluated.	
TRUE	TRUE	The inputs <i>bsJogCtrlSlowDown3</i> and <i>bJogCtrlStop3</i> are evaluated.	

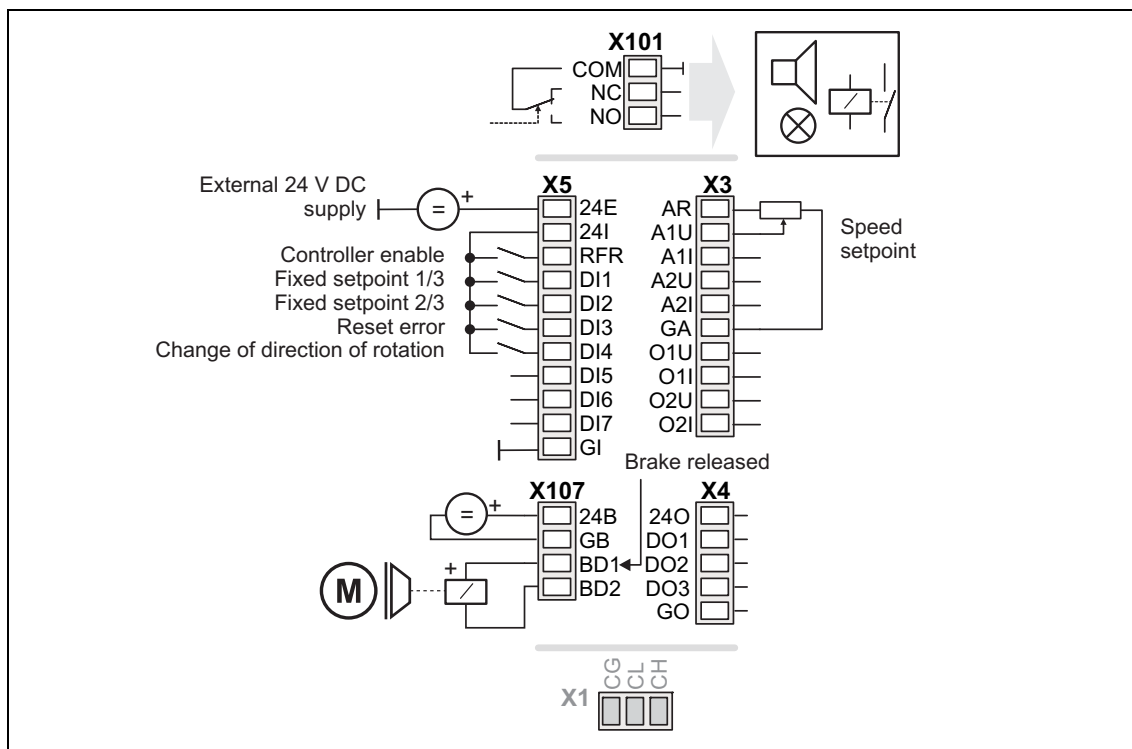
[8-1] Truth table for activating the pre-switch off

8.5.3 Terminal assignment of the control modes

The following comparison provides information about which inputs/outputs of the application block **LA_SwitchPos** are interconnected to the digital and analog input/output terminals of the drive controller in the different control modes.

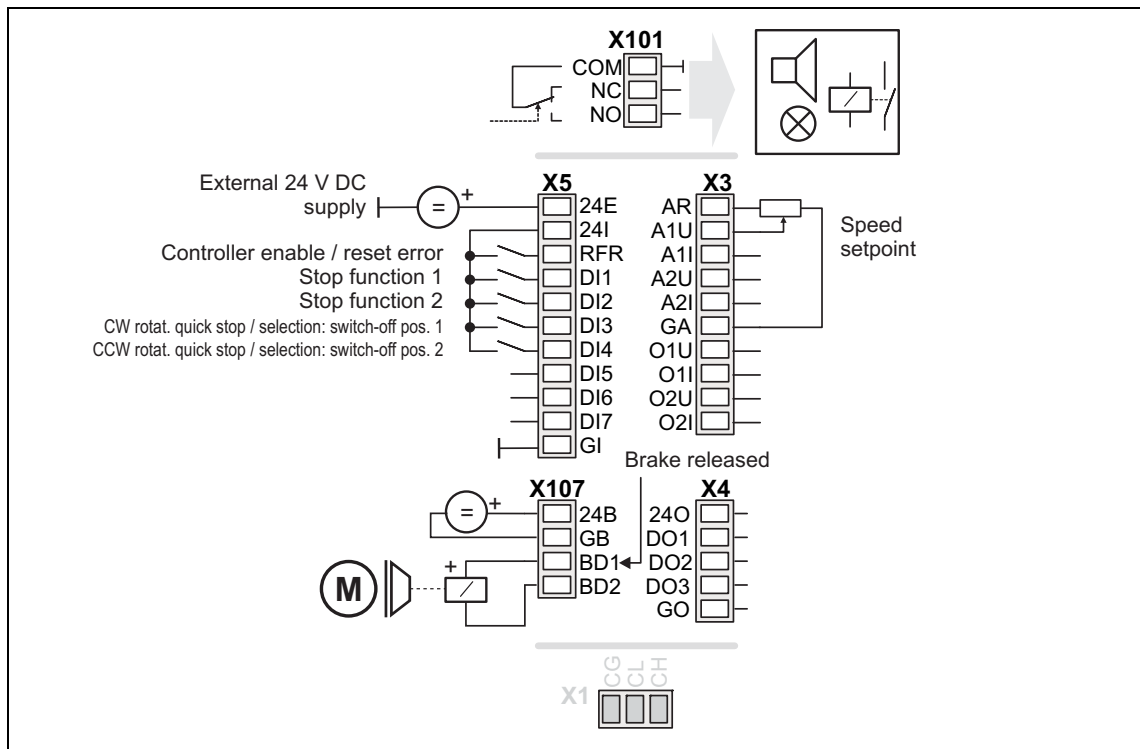
Control mode (C00007)								
	10: Terminals 0	12: Terminals 2	14: Terminals 11	16: Terminal 16	20: Keypad	21: PC	30: CAN	40: MCI
Digital input terminals								
X5/RFR	Controller enable	Controller enable / Reset of error message bFailReset						
X5/DI1	Fixed setpoint 1/3 bJogCtrlJog1	Stop function 1 bJogCtrlStop1		Fixed setpoint 1/3 bJogCtrlJog1	-	-	Stop function 1 bJogCtrlStop1	
X5/DI2	Fixed setpoint 2/3 bJogCtrlJog2	Stop function 2 bJogCtrlStop2	Selection: Pre-switch off 1 bJogCtrlSlowDown 1	Fixed setpoint 2/3 bJogCtrlJog2	-	-	Selection: Pre-switch off 1 bJogCtrlSlowDown 1	
X5/DI3	Reset error message bFailReset	CW rotation quick stop bRLQCw Selection: Switch-off position 1 bJogCtrlInputSel1		CW rotation quick stop bRLQCw	-	-	Stop function 2 bJogCtrlStop2	
X5/DI4	Change of direction of rotation bSetSpeedCcw	CCW rotation quick stop bRLQCcw Selection: Switch-off position 2 bJogCtrlInputSel2		CCW rotation quick stop bRLQCcw	-	-	Selection: Pre-switch off 2 bJogCtrlSlowDown 2	
X5/DI5	-	-	Stop function 2 bJogCtrlStop2	-	-	-	Stop function 3 bJogCtrlStop3	
X5/DI6	-	-	Selection: Pre-switch off 2 bJogCtrlSlowDown 2	-	-	-	Selection: Pre-switch off 3 bJogCtrlSlowDown 3	
X5/DI7	-	-	-	-	-	-	-	-
Analog input terminals								
X3/A1U, A1I	Main speed setpoint nMainSetValue_a 10 V ≙ 100 % reference speed (C00011)				-	-	Additional speed setpoint nAuxSetValue_a 10 V ≙ 100 % reference speed (C00011)	
X3/A2U, A2I	-	-	-	-	-	-	-	-
Digital output terminals								
X4/DO1 ... DO3	-	-	-	-	-	-	-	-
X107/BD1, BD2	Control of the holding brake bMBrakeReleaseOut							
X101/COM, NO	-	-	-	-	-	-	-	-
Analog output terminals								
X3/O1U, O1I	-	-	-	-	-	-	-	-
X3/O2U, O2I	-	-	-	-	-	-	-	-

8.5.3.1 Terminals 0



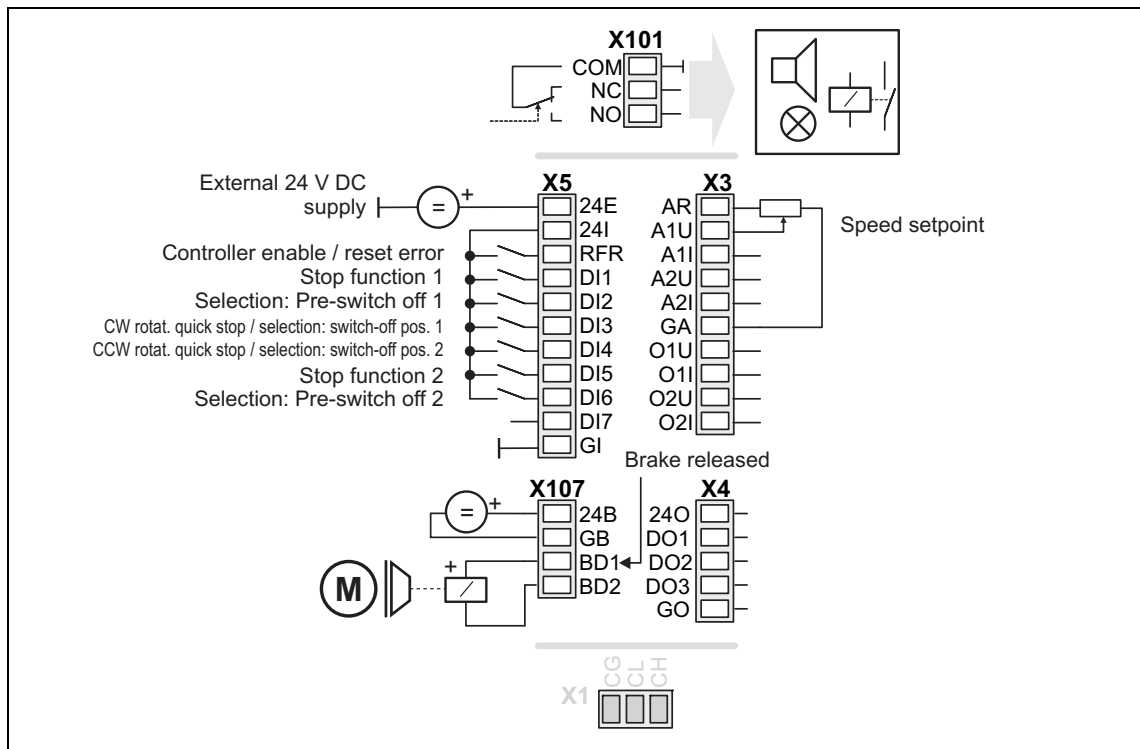
Connection	Assignment	Connection	Assignment
X101/NC-NO	-		
X5/RFR	-	X3/A1U	LA_SwitchPos.nMainSetValue_a
X5/DI1	LA_SwitchPos.bJogCtrlJog1	X3/A1I	10 V ≙ 100 % reference speed (C00011)
X5/DI2	LA_SwitchPos.bJogCtrlJog2	X3/A2U	-
X5/DI3	LA_SwitchPos.bFailReset	X3/A2I	-
X5/DI4	LA_SwitchPos.bSetSpeedCcw	X3/O1U	-
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
X107/BD1	LA_SwitchPos.bMBrakeReleaseOut	X4/DO1	-
X107/BD2	-	X4/DO2	-
		X4/DO3	-

8.5.3.2 Terminals 2



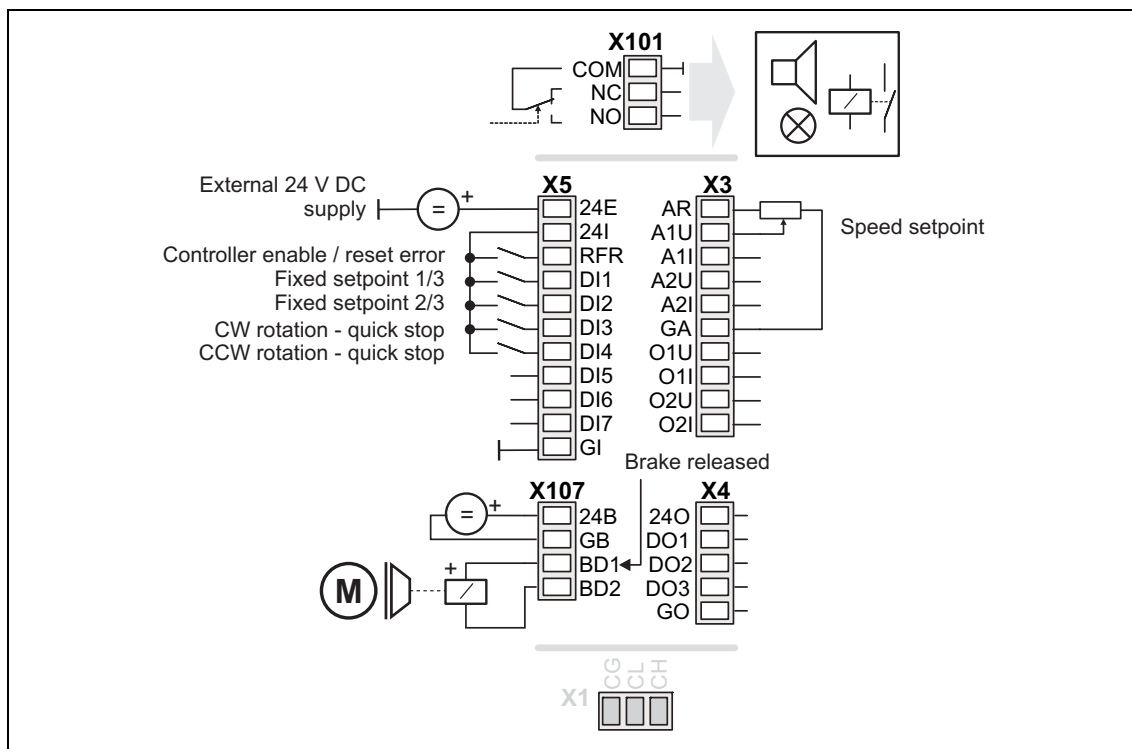
Connection	Assignment	Connection	Assignment
X101/NC-NO	-		
X5/RFR	LA_SwitchPos: bFailReset	X3/A1U	LA_SwitchPos.nMainSetValue_a
X5/DI1	LA_SwitchPos: bLogCtrlStop1	X3/A1I	10 V ≙ 100 % reference speed (C00011)
X5/DI2	LA_SwitchPos: bLogCtrlStop2	X3/A2U	-
X5/DI3	LA_SwitchPos: bRLQCw	X3/A2I	-
	LA_SwitchPos: bLogCtrlInputSel1	X3/O1U	-
X5/DI4	LA_SwitchPos: bRLQCcw	X3/O1I	-
	LA_SwitchPos: bLogCtrlInputSel2	X3/O2U	-
X5/DI5	-		
X5/DI6	-	X4/DO1	-
X5/DI7	-	X4/DO2	-
		X4/DO3	-
X107/BD1	LA_SwitchPos.bMBrakeReleaseOut		
X107/BD2	-		

8.5.3.3 Terminals 11



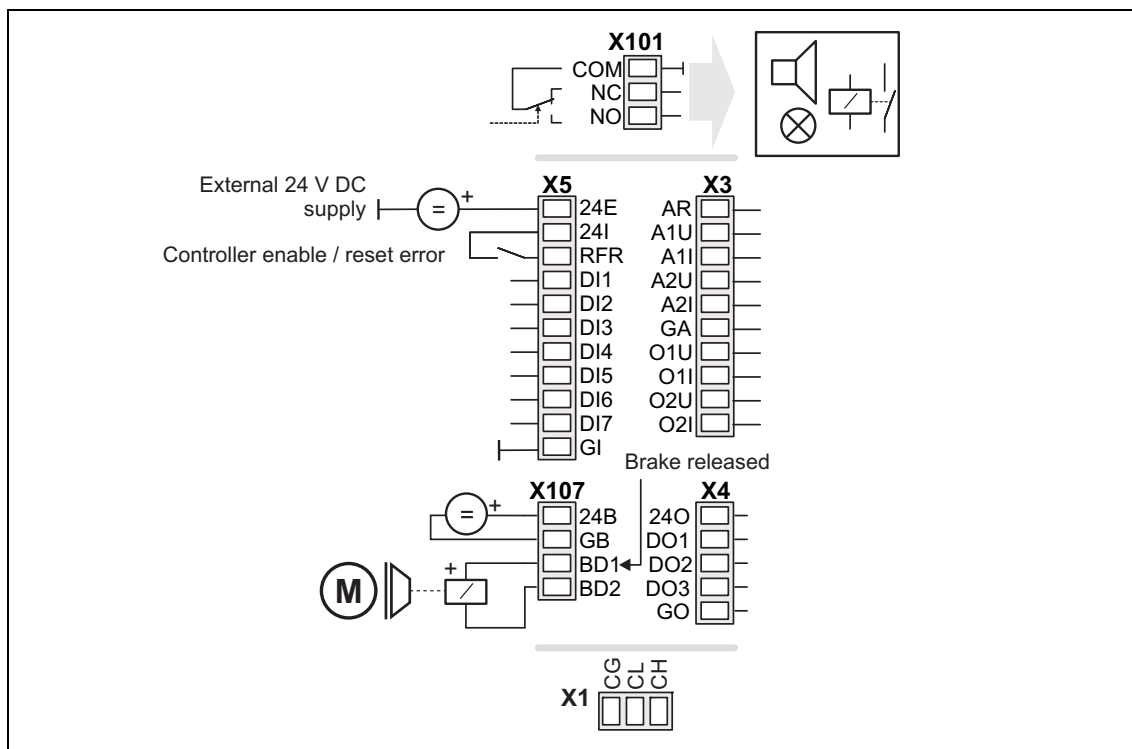
Connection	Assignment	Connection	Assignment
X101/NC-NO	-		
X5/RFR	LA_SwitchPos: bFailReset	X3/A1U	LA_SwitchPos.nMainSetValue_a
X5/DI1	LA_SwitchPos: bLogCtrlStop1	X3/A1I	10 V ≙ 100 % reference speed (C00011)
X5/DI2	LA_SwitchPos: bLogCtrlSlowDown1	X3/A2U	-
X5/DI3	LA_SwitchPos: bRLQCw	X3/A2I	-
	LA_SwitchPos: bLogCtrlInputSel1	X3/O1U	-
X5/DI4	LA_SwitchPos: bRLQCcw	X3/O1I	-
	LA_SwitchPos: bLogCtrlInputSel2	X3/O2U	-
X5/DI5	LA_SwitchPos: bLogCtrlStop2		
X5/DI6	LA_SwitchPos: bLogCtrlSlowDown2	X4/DO1	-
X5/DI7	-	X4/DO2	-
		X4/DO3	-
X107/BD1	LA_SwitchPos.bMBrakeReleaseOut		
X107/BD2	-		

8.5.3.4 Terminal 16



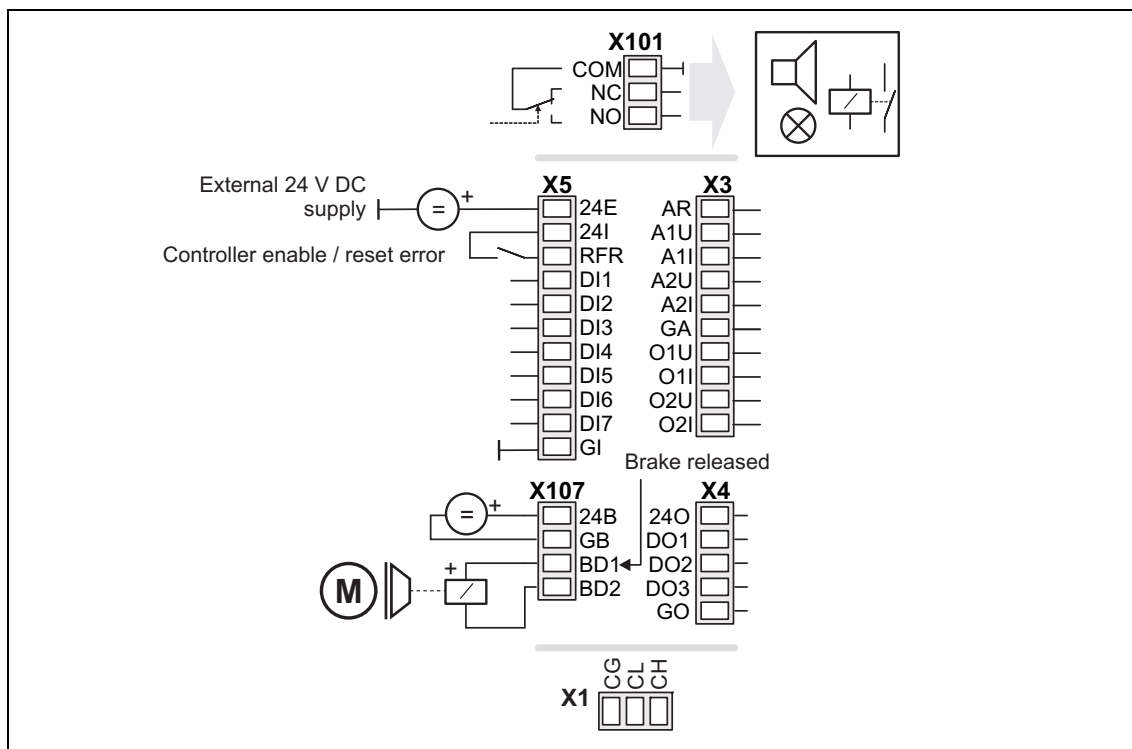
Connection	Assignment	Connection	Assignment
X101/NC-NO	-		
X5/RFR	LA_SwitchPos: bFailReset	X3/A1U	LA_SwitchPos.nMainSetValue_a
X5/DI1	LA_SwitchPos: bLogCtrlJog1	X3/A1I	10 V ≙ 100 % reference speed (C00011)
X5/DI2	LA_SwitchPos: bLogCtrlJog2	X3/A2U	-
X5/DI3	LA_SwitchPos: bRLQCw	X3/A2I	-
X5/DI4	LA_SwitchPos: bRLQCcw	X3/O1U	-
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
X107/BD1	LA_SwitchPos.bMBrakeReleaseOut	X4/DO1	-
X107/BD2	-	X4/DO2	-
		X4/DO3	-

8.5.3.5 Keypad



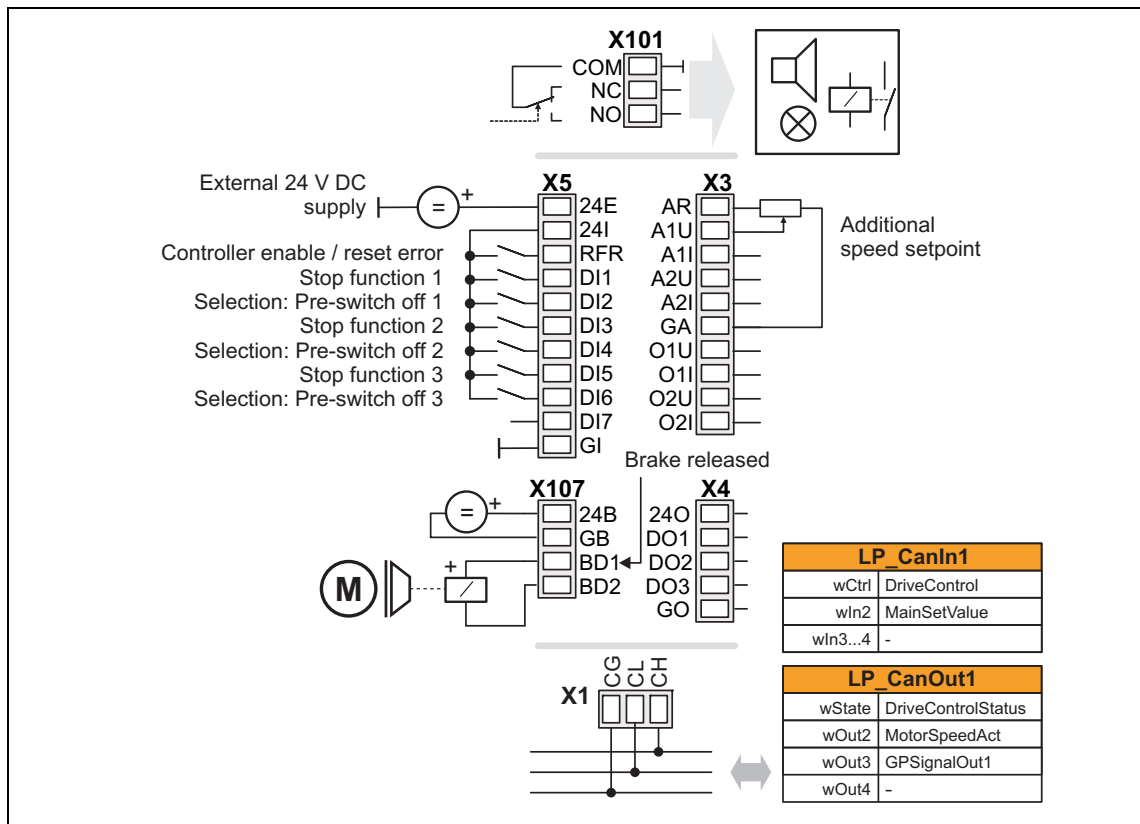
Connection	Assignment	Connection	Assignment
X101/NC-NO	-		
X5/RFR	-	X3/A1U	-
X5/DI1	-	X3/A1I	-
X5/DI2	-	X3/A2U	-
X5/DI3	-	X3/A2I	-
X5/DI4	-	X3/O1U	-
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
X107/BD1	LA_SwitchPos.bMBrakeReleaseOut	X4/DO1	-
X107/BD2	-	X4/DO2	-
		X4/DO3	-

8.5.3.6 PC



Connection	Assignment	Connection	Assignment
X101/NC-NO	-		
X5/RFR	-	X3/A1U	-
X5/DI1	-	X3/A1I	-
X5/DI2	-	X3/A2U	-
X5/DI3	-	X3/A2I	-
X5/DI4	-	X3/O1U	-
X5/DI5	-	X3/O1I	-
X5/DI6	-	X3/O2U	-
X5/DI7	-	X3/O2I	-
X107/BD1	LA_SwitchPos.bMBrakeReleaseOut	X4/DO1	-
X107/BD2	-	X4/DO2	-
		X4/DO3	-

8.5.3.7 CAN



Connection	Assignment	Connection	Assignment
X101/NC-NO	-		
X5/RFR	LA_SwitchPos: bFailReset	X3/A1U	LA_SwitchPos.nAuxSetValue_a 10 V = 100 % reference speed (C00011)
X5/DI1	LA_SwitchPos: bLogCtrlStop1	X3/A1I	-
X5/DI2	LA_SwitchPos: bLogCtrlSlowDown1	X3/A2U	-
X5/DI3	LA_SwitchPos: bLogCtrlStop2	X3/A2I	-
X5/DI4	LA_SwitchPos: bLogCtrlSlowDown2	X3/O1U	-
X5/DI5	LA_SwitchPos: bLogCtrlStop3	X3/O1I	-
X5/DI6	LA_SwitchPos: bLogCtrlSlowDown3	X3/O2U	-
X5/DI7	-	X3/O2I	-
X107/BD1	LA_SwitchPos.bMBrakeReleaseOut	X4/DO1	-
X107/BD2	-	X4/DO2	-
		X4/DO3	-

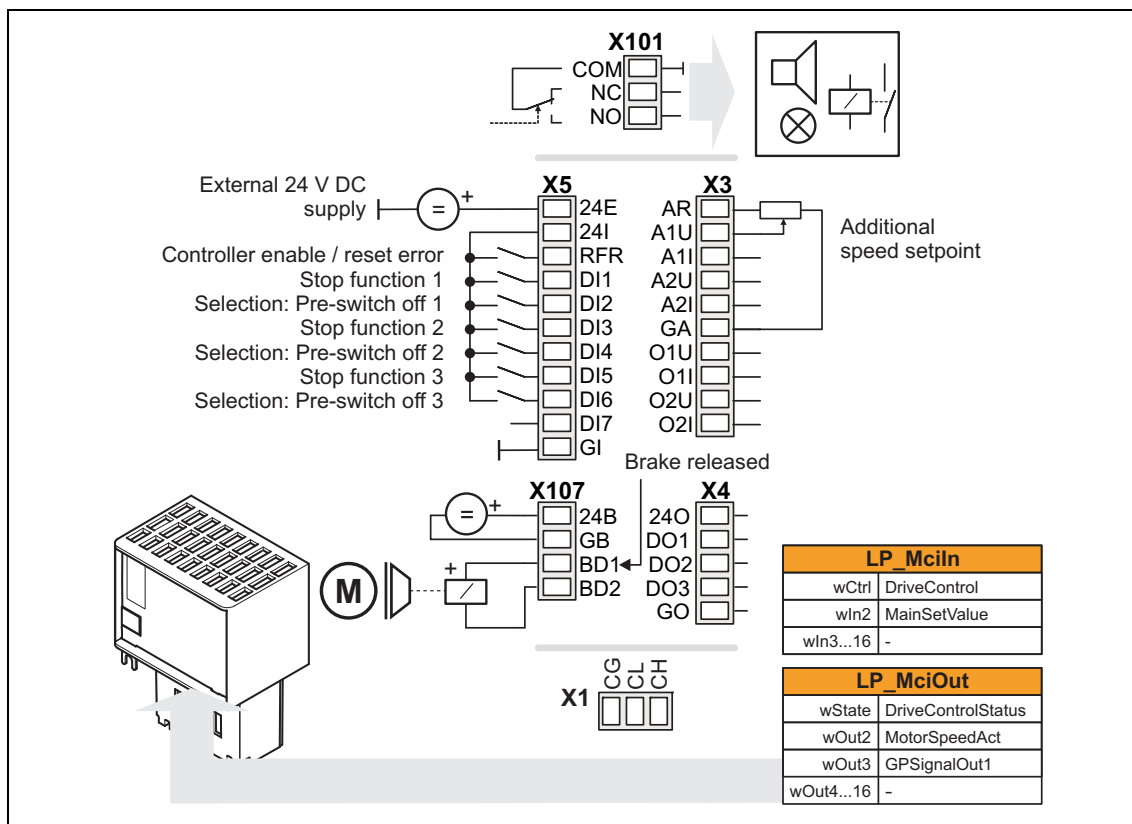
► [Process data assignment for fieldbus communication](#) (539)



Note!

You must set the setpoint arithmetic in [C00190](#) to "1: NOut = NSet + NAdd" so that the additional speed setpoint selected via the analog input A1U has an additive effect.

8.5.3.8 MCI



Connection	Assignment	Connection	Assignment
X101/NC-NO	-		
X5/RFR	LA_SwitchPos: bFailReset	X3/A1U	LA_SwitchPos.nAuxSetValue_a 10 V = 100 % reference speed (C00011)
X5/DI1	LA_SwitchPos: bLogCtrlStop1	X3/A1I	-
X5/DI2	LA_SwitchPos: bLogCtrlSlowDown1	X3/A2U	-
X5/DI3	LA_SwitchPos: bLogCtrlStop2	X3/A2I	-
X5/DI4	LA_SwitchPos: bLogCtrlSlowDown2	X3/O1U	-
X5/DI5	LA_SwitchPos: bLogCtrlStop3	X3/O1I	-
X5/DI6	LA_SwitchPos: bLogCtrlSlowDown3	X3/O2U	-
X5/DI7	-	X3/O2I	-
X107/BD1	LA_SwitchPos.bMBrakeReleaseOut	X4/DO1	-
X107/BD2	-	X4/DO2	-
		X4/DO3	-

► [Process data assignment for fieldbus communication](#) (539)



Note!

You must set the setpoint arithmetic in [C00190](#) to "1: NOut = NSet + NAdd" so that the additional speed setpoint selected via the analog input A1U has an additive effect.

8.5.4 Process data assignment for fieldbus communication

The fieldbus communication is connected (preconfigured) to the previously selected technology application by selecting the corresponding control mode in [C00007](#):

- "30: [CAN](#)" for the connection to the system bus (CAN)
- "40: [MCI](#)" for the connection to a plugged-on communication module (e.g. PROFIBUS)

The assignment of the process data words depends only on the application, not on the bus system used:

Input words	Name	Assignment
Word 1	DriveControl	Control word • For bit assignment see the table below.
Word 2	MainSetValue	Speed setpoint • Scaling: 16384 \equiv 100 % reference speed (C00011)
Word 3	-	Not preconfigured
Word 4	-	Not preconfigured
Words 5 ... 16	-	Not preconfigured • Only available in control mode "40: MCI".

Control word	Name	Function
Bit 0	SwitchOn	1 \equiv Change to the " SwitchedOn " device status • This bit must be set in the CAN/MCI control word to ensure that the device changes to the " SwitchedOn " device status after mains connection without the need for a master control specifying this bit via fieldbus. • If control via a bus system is not wanted (e.g. in the case of control via terminals), the <i>wDriveCtrl</i> output signal of the LS_ParFix system block can be connected to the control word inputs.
Bit 1	DisableVoltage	1 \equiv Inhibit inverter control (pulse inhibit)
Bit 2	SetQuickStop	1 \equiv Activate quick stop (QSP). ▶ Activate/deactivate quick stop (📘 108)
Bit 3	EnableOperation	1 \equiv Enable controller (RFR) • If control via terminals is performed, this bit must be set both in the CAN control word and in the MCI control word. Otherwise, the controller is inhibited. ▶ Enable/Inhibit controller (📘 107)
Bit 4	ModeSpecific_1	Reserved (currently not assigned)
Bit 5	JogCtrlInputSel1	Binary coded selection of the switch-off position 1 ... 3 • Activation of the signal pairs <i>bJogCtrlSlowDown1/bJogCtrlStop1</i> , <i>bJogCtrlSlowDown2/bJogCtrlStop2</i> or <i>bJogCtrlSlowDown3/bJogCtrlStop3</i> according to the Truth table for activating the pre-switch off .
Bit 6	JogCtrlInputSel2	
Bit 7	ResetFault	1 \equiv Reset fault (trip reset) • Acknowledge error message (if the error cause has been eliminated). ▶ Reset error (📘 111)
Bit 8	bJogCtrlRfglN	Ramping down of the setpoint generator in the downstream L_NSet FB according to the Truth table for activating the pre-switch off
Bit 9	reserved_1	Reserved (currently not assigned)
Bit 10	reserved_2	

Control word	Name	Function
Bit 11	MBrkRelease	Holding brake control : 0 ≡ Apply brake 1 ≡ Release brake • In conjunction with the operating mode selected in C02580 (Lenze setting: "Brake control off").
Bit 12	JogCtrlJog1	Binary coded selection of the fixed setpoints (JOG setpoints)
Bit 13	JogCtrlJog2	
Bit 14	SetFail	1 ≡ Set error (trip set)
Bit 15	SetSpeedCcw	0 ≡ Direction of rotation to the right (Cw) 1 ≡ Direction of rotation to the left (Ccw)

Output words	Name	Assignment
Word 1	DriveControlStatus	Status word • For bit assignment see the table below.
Word 2	MotorSpeedAct	Actual speed value • Scaling: 16384 ≡ 100 % reference speed (C00011)
Word 3	GPSignalOut1	Analog signal monitor: Output signal 1 • The selection of the signal source to output is executed in C00410/1 . • Gain and offset for the output signal can be parameterised in C00413/1 and C00413/2 . • For a detailed functional description see the L_SignalMonitor a FB.
Word 4	-	Not preconfigured
Words 5 ... 16	-	Not preconfigured • Only available in control mode "40: MCI".

Status word	Name	Status
Bit 0	DriveFail	1 ≡ Drive controller in error status • " Fault " device status is active.
Bit 1	PowerDisabled	1 ≡ Inverter control inhibited (pulse inhibit is active)
Bit 2	DriveReady	1 ≡ Drive controller is ready for operation • " SwitchedOn " device status is active. • The drive is in this device status if the DC bus voltage is applied and the controller is still inhibited by the user (controller inhibit).
Bit 3	SpeedCcw	0 ≡ Direction of rotation to the right (Cw) 1 ≡ Direction of rotation to the left (Ccw)
Bit 4	QSPIsActive	1 ≡ Quick stop is active
Bit 5	BrakeReleased	1 ≡ Brake released (after the brake opening time has elapsed)
Bit 6	ActSpeedIsZero	During open-loop operation: 1 ≡ Speed setpoint < Comparison value (C00024)
		During closed-loop operation: 1 ≡ Actual speed value < Comparison value (C00024)
Bit 7	ControllerInhibit	1 ≡ Controller inhibited (controller inhibit is active)
Bit 8	StatusCodeBit0	Bit coded display of the active device status ► Device state machine and device states (see table [4-1])
Bit 9	StatusCodeBit1	
Bit 10	StatusCodeBit2	
Bit 11	StatusCodeBit3	
Bit 12	Warning	
		1 ≡ A warning is indicated

Status word	Name	Status
Bit 13	Trouble	1 ≡ Controller is in the "Trouble" device status • E.g. if an overvoltage has occurred.
Bit 14	JogCtrlInputSel1	Binary coded selection of the switch-off position 1 ... 3 • Bit 5 and bit 6 of the control word.
Bit 15	JogCtrlInputSel2	

8.5.5 Setting parameters (short overview)

Parameter	Info	Lenze setting	
		Value	Unit
C00011	Appl.: Reference speed	1500	rpm
C00012	Accel. time - main setpoint	2.000	s
C00013	Decel. time - main setpoint	2.000	s
C00105	Decel. time - quick stop	2.000	s
C00039/1	Fixed setpoint 1	40.00	%
C00039/2	Fixed setpoint 2	60.00	%
C00039/3	Fixed setpoint 3	80.00	%
C00039/4...15	Fixed setpoint 4 ... 15	0.00	%
C00101/1...15	Add. accel. time 1 ... 15	0.000	s
C00103/1...15	Add. decel. time 1 ... 15	0.000	s
C00105	Decel. time - quick stop	2.000	s
C00106	Auto-DCB: Hold time	0.500	s
C00107	DCB braking: Hold time	999.000	s
C00134	L_NSet_1: Ramp smoothing	0: Off	
C00182	L_NSet_1: S-ramp time PT1	20.00	s
C00190	L_NSet_1: Setpoint arithmetic	0: Out = Set	
C00220	L_NSet_1: Acceleration time - add. setpoint	0.000	s
C00221	L_NSet_1: Deceleration time - add. setpoint	0.000	s
C00241	L_NSet_1: Hyst. NSet reached	0.50	%
C00488/1	InputSens.SlowDown1	0: Level	
C00488/2	InputSens.Stop1	0: Level	
C00488/3	InputSens.SlowDown2	0: Level	
C00488/4	InputSens.Stop2	0: Level	
C00488/5	InputSens.SlowDown3	0: Level	
C00488/6	InputSens.Stop3	0: Level	
C00632/1	L_NSet_1: Blocking speed 1 max	0.00	%
C00632/2	L_NSet_1: Blocking speed 2 max	0.00	%
C00632/3	L_NSet_1: Blocking speed 3 max	0.00	%
C00633/1	L_NSet_1: Blocking speed 1 min	0.00	%
C00633/2	L_NSet_1: Blocking speed 2 min	0.00	%
C00633/3	L_NSet_1: Blocking speed 3 min	0.00	%
C00635	L_NSet_1: nMaxLimit	199.99	%
C00636	L_NSet_1: nMinLimit	-199.99	%
C00670	L_OffsetGainP_1: Gain	1.0000	
C00671	L_OffsetGainP_2: Gain	1.0000	

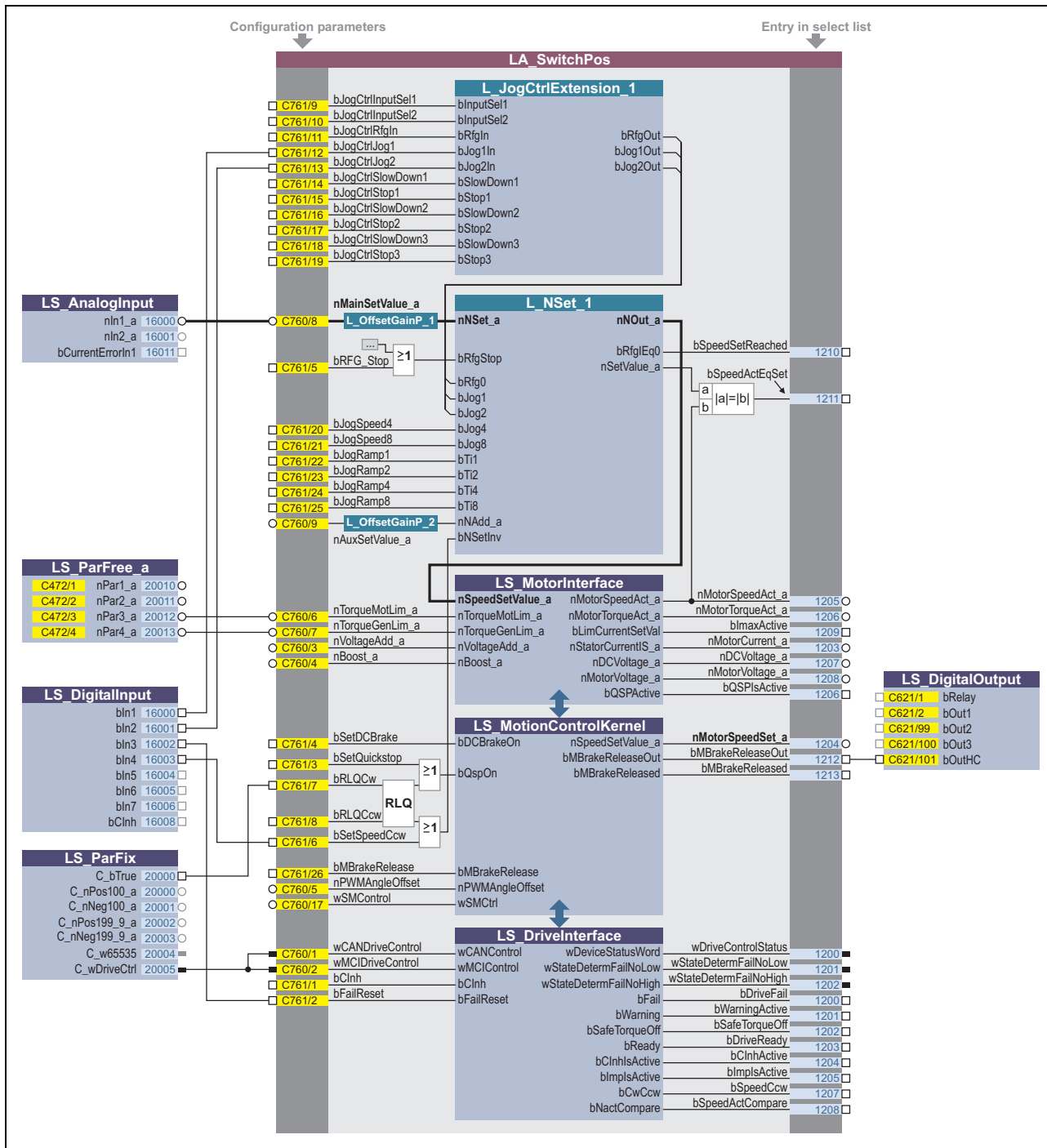
Parameter	Info	Lenze setting	
		Value	Unit
C00672	L_OffsetGainP_3: Gain	1.0000	
C00696	L_OffsetGainP_1: Offset	0.00	%
C00697	L_OffsetGainP_2: Offset	0.00	%
C00698	L_OffsetGainP_3: Offset	0.00	%
C00800	L_MPot_1: Upper limit	100.00	%
C00801	L_MPot_1: Lower limit	-100.00	%
C00802	L_MPot_1: Acceleration time	10.0	s
C00803	L_MPot_1: Deceleration time	10.0	s
C00804	L_MPot_1: Inactive fct.	0: Retain value	
C00805	L_MPot_1: Init fct.	0: Load last value	
C00806	Use of motor potentiometer	0: No	
C02610/2	MCK: Ramp time synchr. setpoint	2.000	s
C02611/1	MCK: Pos. max. speed	199.99	%
C02611/2	MCK: Pos. min. speed	0.00	%
C02611/3	MCK: Neg. min. speed	0.00	%
C02611/4	MCK: Neg. max. speed	199.99	%

Related topics:

► ["GeneralPurpose" functions](#) (📖 546)

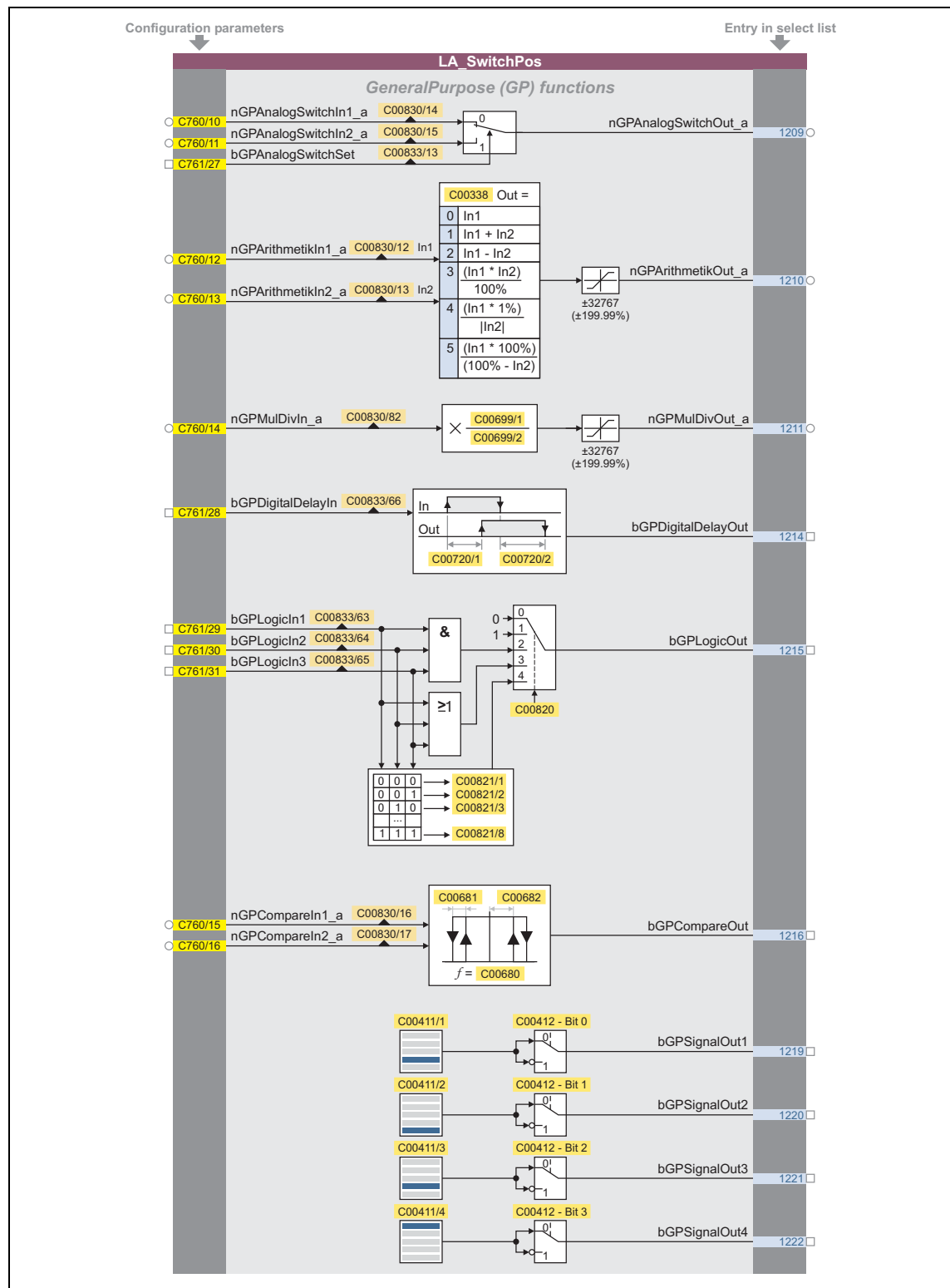
8.5.6 Configuration parameters

If required, the subcodes of [C00760](#) and [C00761](#) serve to change the pre-configured assignment of the application inputs:

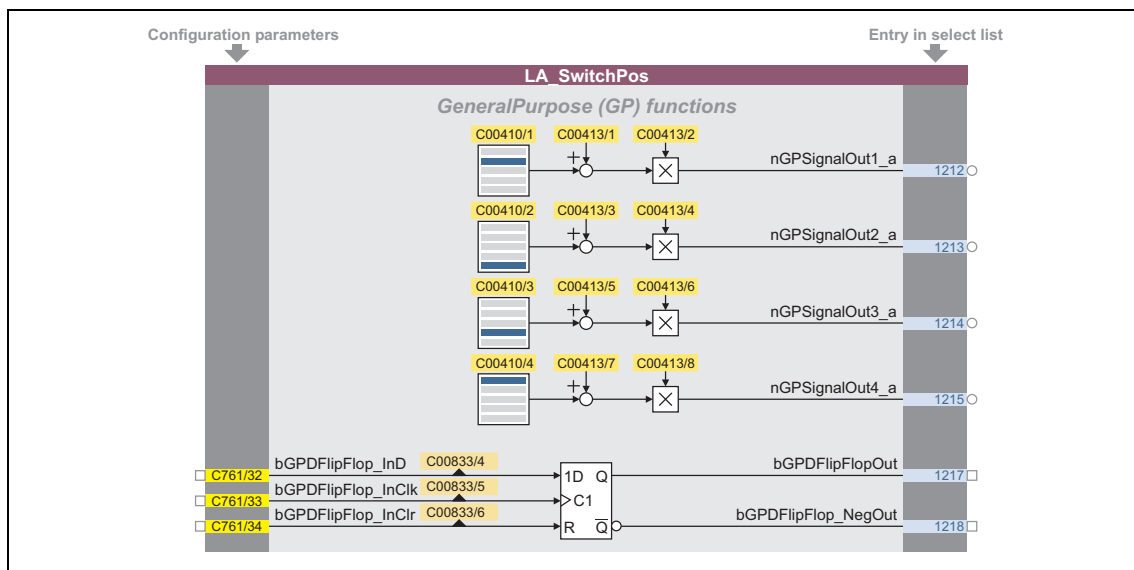


[8-19] Pre-assignment of the "Switch-off positioning" application in the "Terminals 0" control mode

Configuration parameters for "GeneralPurpose" functions



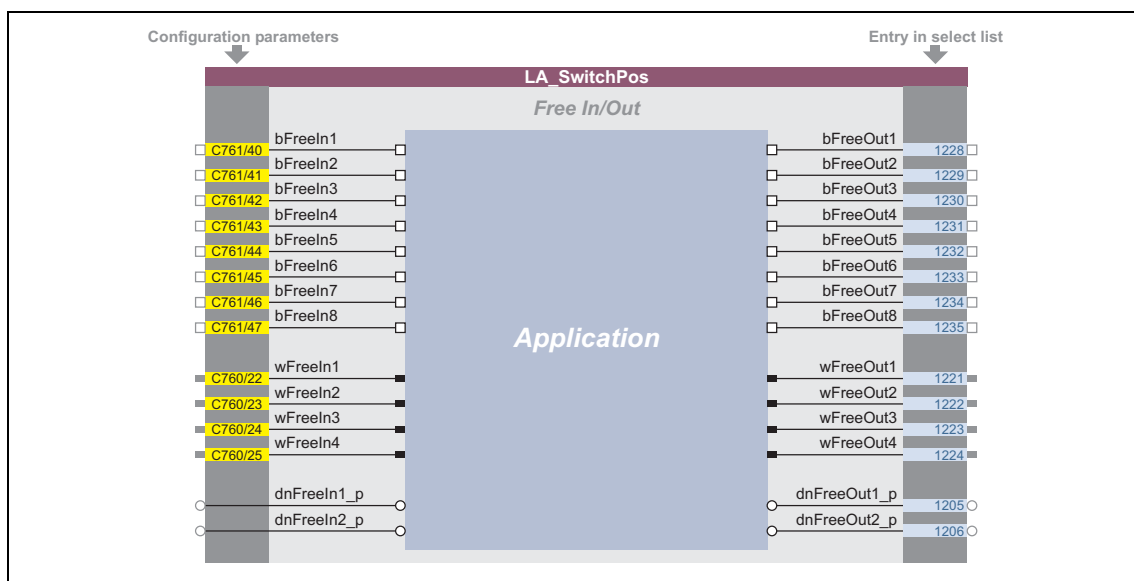
[8-20] "GeneralPurpose" functions



[8-21] "GeneralPurpose" functions (continuation)

Free inputs and outputs

These inputs can be freely interconnected in the application level. They can be used to transfer signals from the I/O level to the application level and vice versa.



[8-22] Free inputs/outputs

Related topics:

- ▶ [User-defined terminal assignment](#) (421)
- ▶ ["GeneralPurpose" functions](#) (546)

8.6 "GeneralPurpose" functions

Each technology application provides different free logic and arithmetic functions, so-called "GeneralPurpose" functions.

For the interconnection of these functions, the application block features inputs and outputs on the I/O level, which are linked to the logic/arithmetic function.



Note!

In the Lenze setting, the connectors for the "GeneralPurpose" functions are hidden in the function block editor.

- These connections can be shown via the **Connector visibilities** command in the *Context menu* of the application block.



Tip!

The inputs of the "GeneralPurpose" functions can also be linked to other output signals via the configuration parameters of the technology application.

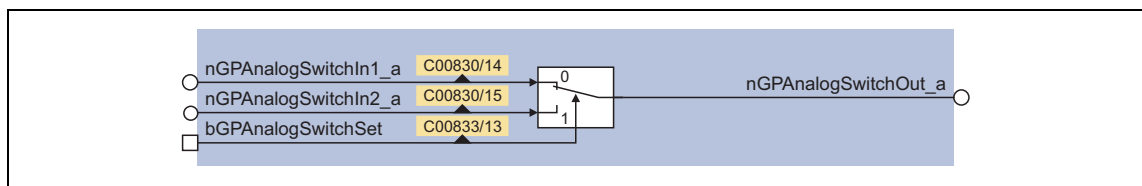
On the other hand, the outputs of the "GeneralPurpose" functions can be selected in the configuration parameters of other inputs.

Related topics:

- ▶ [User-defined terminal assignment](#) (421)
- ▶ [TA "Actuating drive speed": Configuration parameters](#) (454)
- ▶ [TA "Table positioning": Configuration parameters](#) (516)
- ▶ [TA "Switch-off positioning": Configuration parameters](#) (543)

8.6.1 Analog switch

This function switches between two analog input signals. The switch-over is controlled by a boolean input signal.

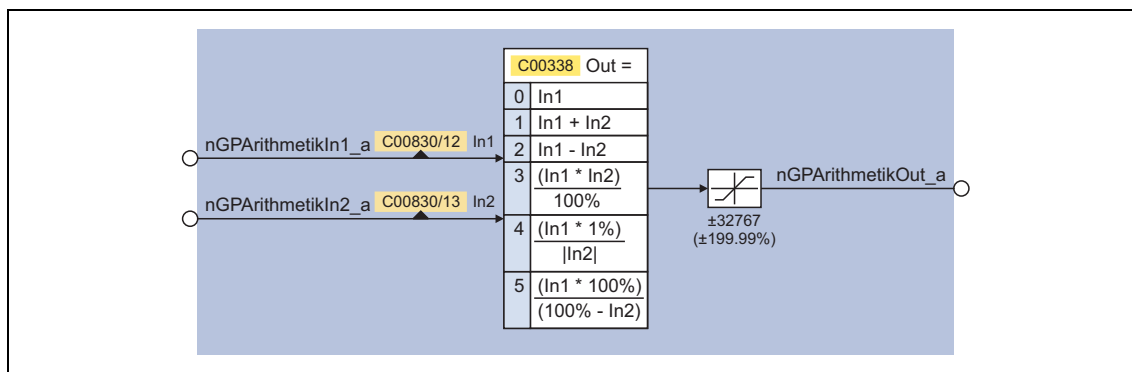


[8-23] GeneralPurpose function "Analog switch"

- For a detailed functional description see FB [L_AnalogSwitch](#).

8.6.2 Arithmetic

This function links two analog signals arithmetically. The arithmetic function can be parameterised.



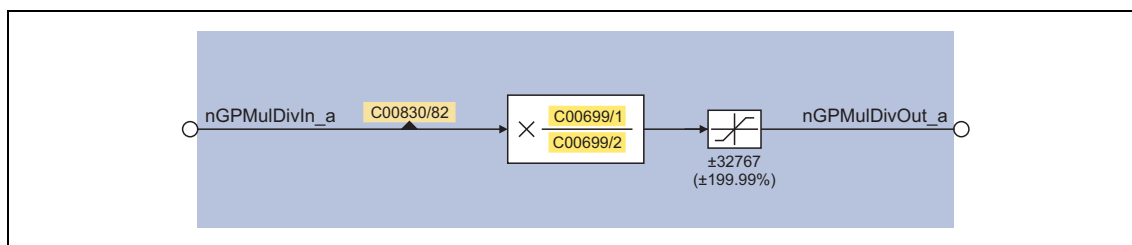
[8-24] GeneralPurpose function "Arithmetic"

Parameter	Info	Lenze setting	
		Value	Unit
C00338	L_Arithmetik_1: Function	0: nOut_a = nIn1_a	

- For a detailed functional description see the [L_Arithmetik](#) FB.

8.6.3 Multiplication/Division

This function multiplies an analog input signal with a parameterisable factor. The factor must be selected in the form of a quotient (numerator and denominator).



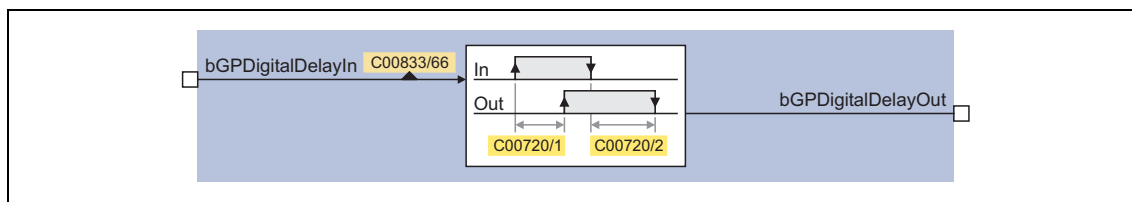
[8-25] GeneralPurpose function "Multiplication/division"

Parameter	Info	Lenze setting	
		Value	Unit
C00699/1	L_MulDiv_1: Numerator	0	
C00699/2	L_MulDiv_1: Denominator	10000	

- For a detailed functional description see FB [L_MulDiv](#).

8.6.4 Binary delay element

This function timely delays binary signals. On-delay and off-delay can be parameterised separately.



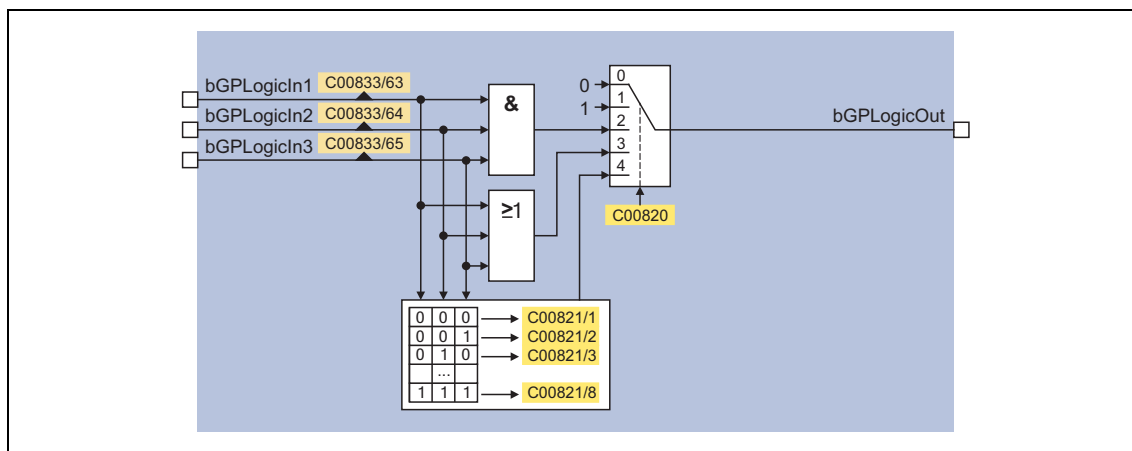
[8-26] GeneralPurpose function "Binary delay element"

Parameter	Info	Lenze setting	
		Value	Unit
C00720/1	L_DigitalDelay_1: On delay	0.000	s
C00720/2	L_DigitalDelay_1: Off delay	0.000	s

- For a detailed functional description see FB [L_DigitalDelay](#).

8.6.5 Binary logic

This function provides a binary output signal which is formed by a logic operation of the input signals. Alternatively, you can also select a fixed binary value which is independent of the input signals.



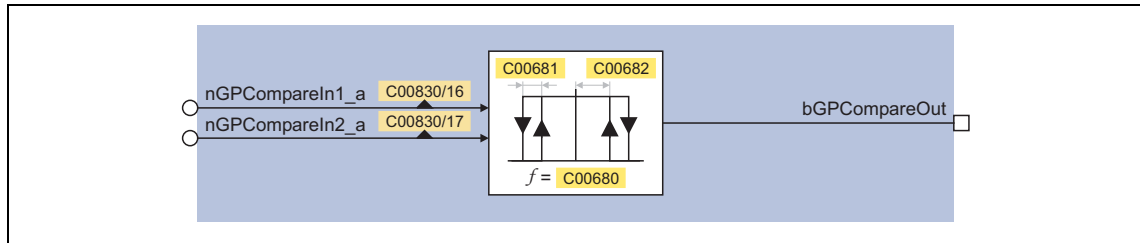
[8-27] GeneralPurpose function "Binary logic"

Parameter	Info	Lenze setting	
		Value	Unit
C00820	L_DigitalLogic_1: Function	0: bOut = 0	
C00821/1	bIn1=0/bIn2=0/bIn3=0	0: FALSE	
C00821/...	
C00821/8	bIn1=1/bIn2=1/bIn3=1	0: FALSE	

- For a detailed functional description see FB [L_DigitalLogic](#).

8.6.6 Analog comparison

This function compares two analog signals and can be used e.g. to realise a trigger. The comparison operation, hysteresis and window size can be parameterised.



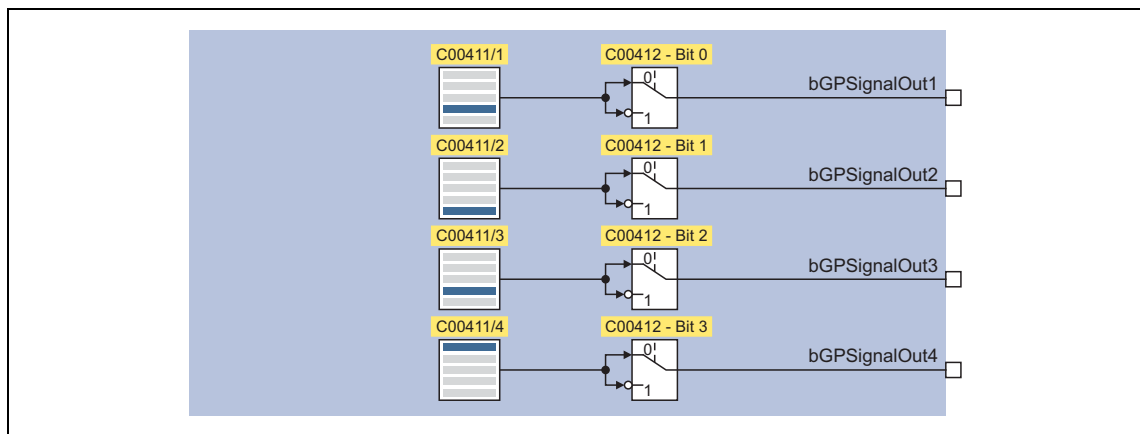
[8-28] GeneralPurpose function "Analog comparison"

Parameter	Info	Lenze setting	
		Value	Unit
C00680	L_Compare_1: Fct.	6: $ In1 < In2 $	
C00681	L_Compare_1: Hysteresis	0.50	%
C00682	L_Compare_1: Window	2.00	%

- For a detailed functional description see FB [L_Compare](#).

8.6.7 Binary signal monitor

This function serves to output four binary signals selected from a list of all binary output signals available in the drive controller. You can set an inversion of the output signals.



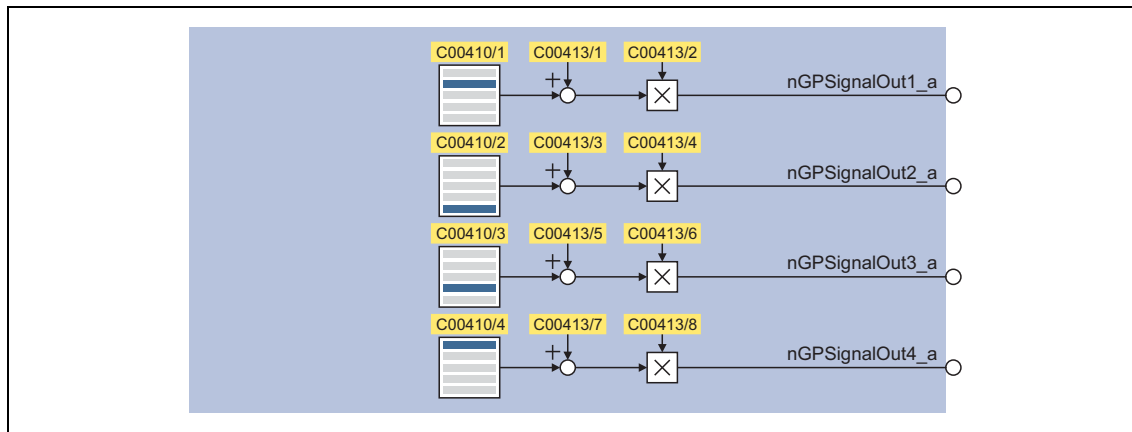
[8-29] GeneralPurpose function "Binary signal monitor"

Parameter	Info	Lenze setting	
		Value	Unit
C00411/1...4	L_SignalMonitor_b: Signal 1 ... 4	0: Not connected	
C00412	L_SignalMonitor_b: Inversion	Bit coded	

- For a detailed functional description see FB [L_SignalMonitor_b](#).

8.6.8 Analog signal monitor

This function serves to output four analog signals selected from a list of all analog output signals available in the drive controller. Offset and gain of the source signals can be adjusted.



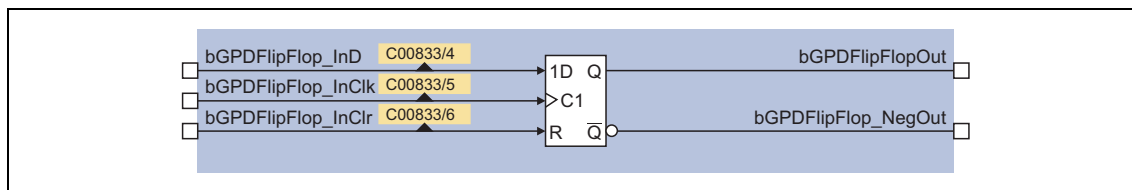
[8-30] GeneralPurpose function "Analog signal monitor"

Parameter	Info	Lenze setting	
		Value	Unit
C00410/1...4	L_SignalMonitor_a: Signal 1 ... 4	0: Not connected	
C00413/1	L_SignalMonitor_a: Signal 1 offset	0.00	%
C00413/2	L_SignalMonitor_a: Signal 1 gain	100.00	%
C00413/3	L_SignalMonitor_a: Signal 2 offset	0.00	%
C00413/4	L_SignalMonitor_a: Signal 2 gain	100.00	%
C00413/5	L_SignalMonitor_a: Signal 3 offset	0.00	%
C00413/6	L_SignalMonitor_a: Signal 3 gain	100.00	%
C00413/7	L_SignalMonitor_a: Signal 4 offset	0.00	%
C00413/8	L_SignalMonitor_a: Signal 4 gain	100.00	%

- For a detailed functional description see the [L_SignalMonitor_a](#) FB.

8.6.9 D-FlipFlop

This function saves the logic status of the data input (1D) in case of an active clock edge at the clock input (C1) and puts out its value in sequence at the output Q. If there is no active clock edge, the input value is not accepted.

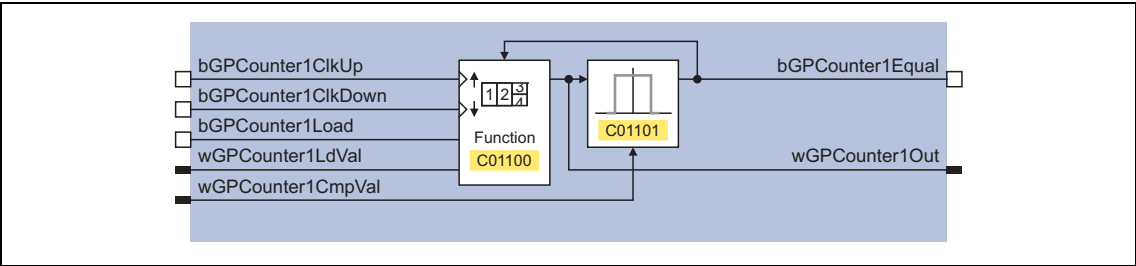


[8-31] GeneralPurpose function "D-FlipFlop" (clock-edge controlled)

- For a detailed functional description see FB [L_DFlipFlop](#).

8.6.10 Counter

This function is a digital upcounter and downcounter with a comparison operation.



[8-32] GeneralPurpose function "Counter"

Parameter	Info	Lenze setting	
		Value	Unit
C01100/1	L_Counter_1: Function	0: Normal counting	
C01101/1	L_Counter_1: Comparison	0: Greater than or equal to	

- Only available with [TA "Table positioning"](#).
- For a detailed functional description see FB [L_Counter](#).

9 Basic drive functions (MCK)

In this chapter, the standard and basic drive functions integrated in the **Motion Control Kernel (MCK)** of the 8400 TopLine are described to which the active technology application can gain access via defined internal interfaces. As a result, the time-consuming creation of individual FB interconnections is avoided and the amount of work and complexity involved in the implementation of standard functions is minimised.

In the **Motion Control Kernel**, for example, an automatic holding brake control function is integrated which controls the holding brake in relation to the speed setpoint and various other internal control signals. Due to integrated automatic brake operation, the user is relieved of the task of managing these control signals.

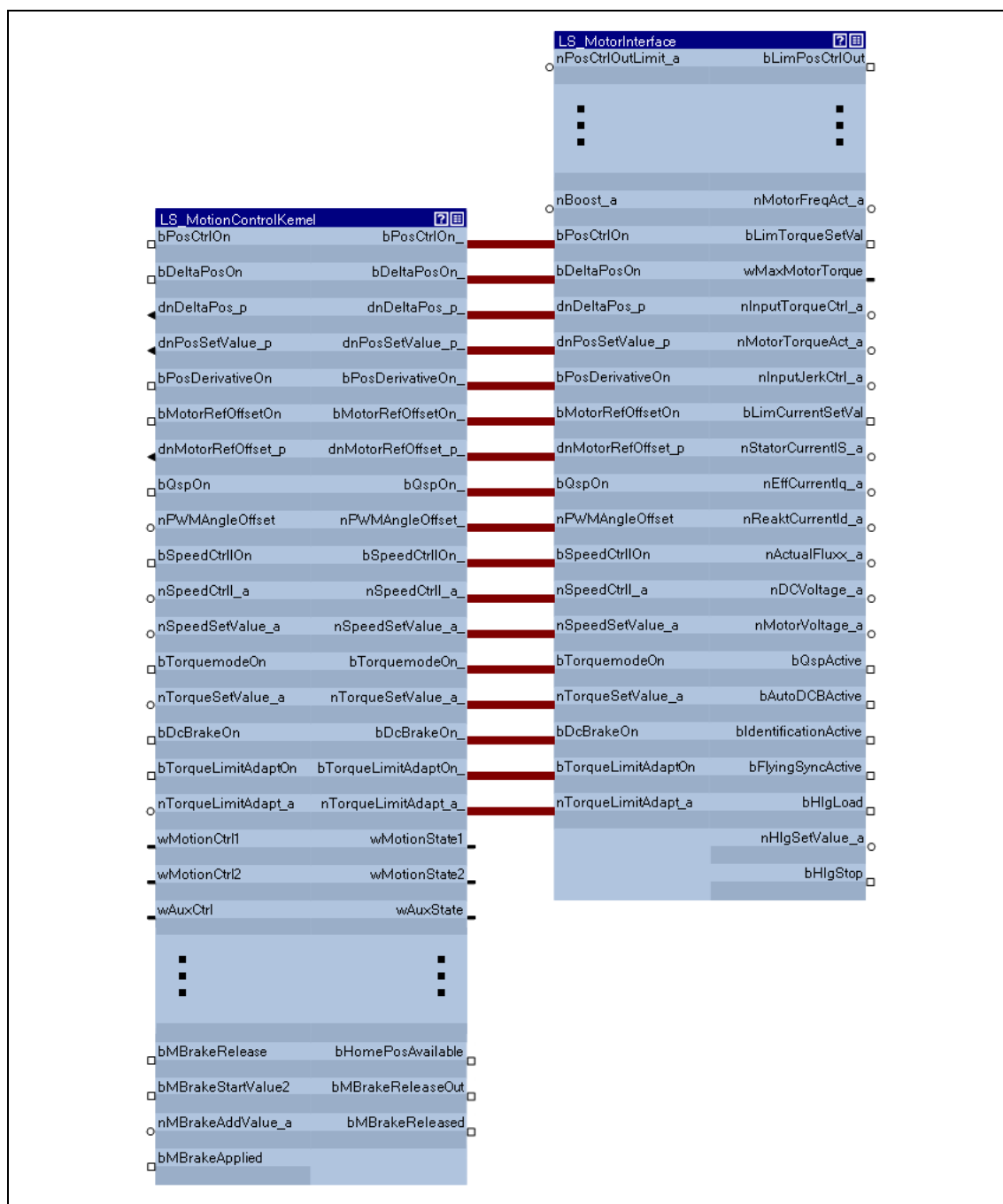
Other standard functions integrated in the **Motion Control Kernel** in the case of the 8400 TopLine controller are, for example:

- Manual jog, e.g. for manual setting-up operation
- Homing for positioning functions of the drive
- Position profile generator for positioning functions of the drive

9.1

Basic signal flow

The **Motion Control Kernel** is connected between setpoint generator (e.g. ramp generator, PID process controller, etc.) and the motor control function in the case of the available technology applications. For problem-free interaction of the **Motion Control Kernel** and motor control function, the two associated system blocks [LS_MotionControlKernel](#) and [LS_MotorInterface](#) have interfaces with corresponding inputs/outputs. These are visible in the FB Editor for monitoring purposes and must be connected to each other:



[9-1] Interconnection of Motion Control Kernel and motor control function


In the interconnection previously shown, the **Motion Control Kernel** monitors every interface. Some of the signals such as a quick stop request or a DC-injection braking request are directly passed through to the motor control. However, other signals are passed through or modified depending on the operating mode (e.g. synchronising a setpoint selection via ramp function).


9.2 Internal interfaces | System block "LS_MotionControlKernel"

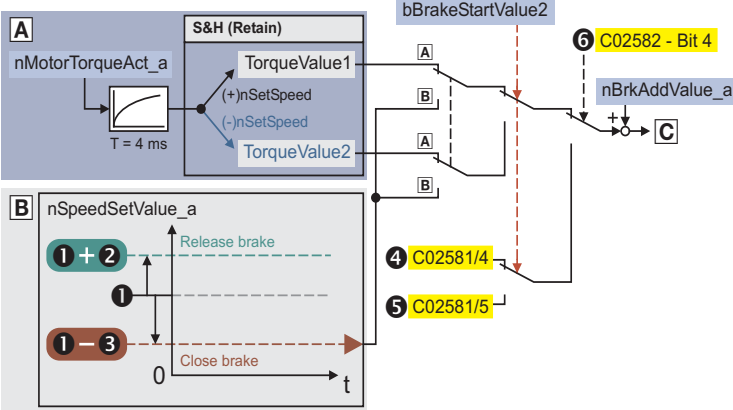
In the Function Block editor, the system block **LS_MotionControlKernel** provides the interfaces to the **Motion Control Kernel**.

Inputs

Identifier	Data type	Information/possible settings
Control and setpoint signals for motor control The purpose of the following inputs is to transfer control signals and setpoints to the internal motor control function (LS_MotorInterface).		
bPosCtrlOn	BOOL	Activation of position/angle control
		FALSE Position/angle control deactivated.
		TRUE Position/angle control activated.
bDeltaPosOn	BOOL	Activate position difference as setpoint selection <ul style="list-style-type: none"> In order to position the motor shaft, the position control function can work within the motor control function with the absolute position setpoint <i>dnPosSetValue_p</i> or alternatively with the speed setpoint <i>nSpeedSetValue_a</i> and the position difference <i>dnDeltaPos_p</i>.
		FALSE Positioning with position setpoint <i>dnPosSetValue_p</i> .
		TRUE Positioning with speed setpoint <i>nSpeedSetValue_a</i> and position difference <i>dnDeltaPos_p</i> . Note: In this case, <u>no</u> position encoder should be set to ensure a correct function (C00490 = "No encoder: <i>nSpeedSetValue_a</i> ").
dnDeltaPos_p	DINT	Position difference (following error input) <ul style="list-style-type: none"> Difference between setpoint position and actual position in [increments] Is used for position control if <i>bDeltaPosOn</i> = TRUE. Scaling: A revolution is displayed with 65536 increments or steps.
dnPosSetValue_p	DINT	Absolute position setpoint in [increments] <ul style="list-style-type: none"> Is used for position control if <i>bDeltaPosOn</i> = FALSE. Scaling: A revolution is displayed with 65536 increments or steps.
bPosDerivativeOn	BOOL	Create a setpoint for the speed controller from the position setpoint <ul style="list-style-type: none"> For highly dynamic control systems, the setpoint for the speed controller can be created from the absolute position setpoint <i>dnPosSetValue_p</i> instead of the speed setpoint <i>nSpeedSetValue_a</i>. ▶ Position control/additive speed specification
		TRUE Create a speed setpoint from the position setpoint. <ul style="list-style-type: none"> The absolute position setpoint <i>dnPosSetValue_p</i> is differentiated and a speed value is created which is the setpoint for the speed controller. Internal limitation of 65536 increments/ms.
bMotorRefOffsetOn	BOOL	In preparation - Input has no function at present time! Adopt home position ("Homing on the fly")
		FALSE → TRUE Adopt home position <i>dnMotorRefOffset_p</i> .

Identifier	Data type	Information/possible settings
dnMotorRefOffset_p	DINT	<p>Home position in [increments]</p> <ul style="list-style-type: none"> Value is adopted when control bit 9 ("HomeSetPos") is set from "0" to "1" in the MCK control word and is sent to the motor control function via the <i>dnMotorRefOffset_p_</i> output. Transfer is possible in any operating mode ("Homing on the fly"). For this function, the two outputs <i>bMotorRefOffsetOn_</i> and <i>dnMotorRefOffset_p_</i> must be connected to the inputs of the same name of the LS_MotorInterface system block.
bQspOn	BOOL	<p>Trigger quick stop (QSP) via the MCK</p> <ul style="list-style-type: none"> Also see device command "Activate/deactivate quick stop".
		<p>TRUE</p> <p>Activate quick stop</p> <ul style="list-style-type: none"> Motor control is decoupled from the setpoint selection and, within the deceleration time parameterised in C00105, the motor is brought to a standstill ($n_{act} = 0$). A pulse inhibit is set if the auto-DCB function has been activated via C00019. The motor is kept at a standstill during closed-loop operation (function in preparation).
		<p>FALSE</p> <p>Deactivate quick stop</p> <ul style="list-style-type: none"> The quick stop is deactivated if no other source for the quick stop is active. C00159 displays a bit code of active sources/causes for the quick stop.
nPWMAngleOffset	INT	<p>Angular offset input</p> <ul style="list-style-type: none"> Scaling: $16384 \equiv 100\%$ Setting range: 0 ... 199.99 %
bSpeedCtrlIOn	BOOL	<p>Directly set the I-component of speed controller</p> <ul style="list-style-type: none"> In order to statically specify a minimum torque, e.g. when a load is being lifted.
		<p>TRUE</p> <p>Set the I-component of the speed controller to the value <i>nSpeedCtrlI_a</i>.</p>
nSpeedCtrlI_a	INT	<p>I-component of the speed controller</p> <ul style="list-style-type: none"> Value is adopted in the case of a FALSE-TRUE edge at the input <i>bSpeedCtrlIOn</i>.
nSpeedSetValue_a	INT	Rotation speed/velocity setpoint
bTorquemodeOn	BOOL	<p>TRUE</p> <p>Switch on torque-controlled operation</p>
nTorqueSetValue_a	INT	Torque setpoint
bDcBrakeOn	BOOL	<p>Manual DC-injection braking (DCB)</p> <ul style="list-style-type: none"> For this function, the <i>bDcBrakeOn_</i> output signal must be connected to the <i>bDcBrakeOn</i> input of the same name of the LS_MotorInterface system block. Detailed information on DC-injection braking is provided in the motor control chapter, subchapter "DC-injection braking".
		<p> Note!</p> <p>Holding braking is not possible when this braking mode is used! Use the basic "Holding brake control" function for controlling the holding brake with a low rate of wear.</p>
		<p>FALSE</p> <p>Deactivate DC-injection braking.</p>
		<p>TRUE</p> <p>Activate DC-injection braking, i.e. the drive is brought to a standstill by means of DC-injection braking.</p> <ul style="list-style-type: none"> The braking effect stops when the rotor is at standstill. After the hold time (C00107) has expired, the controller sets the pulse inhibit.

Identifier	Data type	Information/possible settings
bTorqueLimitAdaptOn	BOOL	Adaptation of torque limitation
		TRUE Activate adaptation of torque limitation.
nTorqueLimitAdapt_a	INT	Value for adaptation of torque limitation <ul style="list-style-type: none"> Scaling: $16384 \equiv 100\%$ of the torque limit specified at the LS_MotorInterface system block via the <i>nTorqueMotLimit_a</i> and <i>nTorqueGenLimit_a</i> inputs.
Control words		
MCK: wMotionCtrl1 wMotionCtrl2	WORD	MCK control word 1 & 2 <ul style="list-style-type: none"> The two control words together form a 32-bit double control word with which the entire Motion Control Kernel is controlled. All motion profiles in the different operating modes can be operated via this interface. See the "MCK control word" subchapter for a detailed description of the individual control bits. Display parameter: C01240
wAuxCtrl	WORD	For future extensions - Input has no function at present time! Additional control word
wSMCtrl	WORD	Interface to the optional safety system. <ul style="list-style-type: none"> Setting control bit 0 ("SafeStop1") in this control word causes e.g. the automatic deceleration of the drive to standstill within this application (in the Motion Control Kernel). See the "Interface to safety system" subchapter for a detailed description of the individual control bits.
Control and setpoint signals for Motion Control Kernel function		
dnProfilePosition_p	DINT	Profile position in [increments] <ul style="list-style-type: none"> Position which is to be entered into a profile data set selected via the MCK control word. In the "absolute" mode, this position is a target position. However, in the "relative" mode it is a relative traverse path. ► Consideration of residual value in case of external profile calculation
nSpeedAddValue_v	INT	Additive speed setpoint in [inc/ms]
nSpeedOverride_a	INT	Value for Speed override <ul style="list-style-type: none"> Percentage multiplier (0 ... 199.99 %) for the currently active speed. $16384 \equiv 100\%$ of the maximum traversing speed (display in C01211/1). If the override value is 0 %, the drive is brought to a standstill.
nAccOverride_a	INT	Value for Acceleration override <ul style="list-style-type: none"> Percentage multiplier (0 ... 199.99 %) for the currently active acceleration. $16384 \equiv 100\%$ of the parameterised acceleration of the corresponding operating mode. If the override value is 0 %, acceleration ceases.
nSRampOverride_a	INT	Value for S-ramp smoothing override <ul style="list-style-type: none"> Percentage multiplier (0 ... 100 %) for the currently active acceleration. $16384 \equiv 100\%$ of the parameterised S-ramp time (C01306/1...15). Values > 16384 are ignored. <div>  Note! </div> <p>If the <i>nSRampOverride_a</i> input remains unconnected or if an override value of "0 %" is selected, activation of the S-ramp override causes deactivation of the S-ramp time.</p> <ul style="list-style-type: none"> Deactivation of the S-ramp time before the start of a profile with S-ramp time causes linear ramp generation. Deactivation of the S-ramp time during a traversing process, however, is not accepted immediately in the profile generator, but the profile generator checks automatically when an online change of the ramp form can be carried out and then initiates it automatically.

Identifier	Data type	Information/possible settings
bLimitSwitchPos	BOOL	Input for Hardware limit switch (positive)
bLimitSwitchNeg	BOOL	Input for Hardware limit switch (negative)
bHomingMark	BOOL	Input for pre-stop mark/pre-stop signal for homing <ul style="list-style-type: none"> Relevant for homing modes "4" ... "7".
bMBrakeRelease	BOOL	Holding brake control : Releasing/applying the brake in connection with the selected operating mode <div> <div>FALSE</div> <div>Apply brake. <ul style="list-style-type: none"> During automatic operation, the internal brake logic controls the brake. </div> </div> <div> <div>TRUE</div> <div>Release brake manually (forced release). <ul style="list-style-type: none"> Note! The brake can also be released if the controller is inhibited! During automatic operation, the internal brake logic is deactivated and the brake is released (supervisor operation). If a controller inhibit has been set by the brake control, it will be deactivated. In semi-automatic operation, the brake is released including feedforward control. </div> </div>
bMBrakeStartValue2	BOOL	Holding brake control : Selection of the torque feedforward control value ▶ Feedforward control of the motor before release <div> <div>FALSE</div> <div>Starting value 1 is active (see the following figure).</div> </div> <div> <div>TRUE</div> <div>Starting value 2 is active (see the following figure).</div> </div> <p>Creation of the feedforward control value for the release process of the brake:</p> <p> A Signal path for motor control <u>with</u> feedback B Signal path for motor control <u>without</u> feedback C Feedforward control value </p>  <p> 1 C02581/1: Switching threshold 2 C02581/2: Hysteresis for release 3 C02581/3: Hysteresis for application 4 C02581/4: Starting value 1 for manual feedforward control 5 C02581/5: Starting value 2 for manual feedforward control 6 C02582/Bit 4: Selection of the feedforward control value (automatic/manual selection) </p>
nMBrakeAddValue_a	INT	Holding brake control : Additive feedforward control value (speed or torque) in [%] for torque feedforward control when the respective control mode is started <ul style="list-style-type: none"> For speed control: 100 % ≡ reference speed (C00011) For torque control: 100 % ≡ maximum torque (C00057) ▶ Feedforward control of the motor before release

Identifier	Data type	Information/possible settings
bMBrakeApplied	BOOL	Holding brake control : Input for status detection via switching contacts at the brake <ul style="list-style-type: none"> Only effective if bit 5 in C02582 is set to "1".
		FALSE Brake is released.
		TRUE Brake is applied.

Outputs

Identifier	Data type	Value/meaning
Control and setpoint signals for motor control The following outputs are used to transfer control signals and setpoints to the internal motor control function (LS_MotorInterface).		
bPosCtrlOn_	BOOL	TRUE Activate position control.
bDeltaPosOn_	BOOL	TRUE Control to adjust for following errors.
dnDeltaPos_p_	DINT	Following error input
dnPosSetValue_p_	DINT	Absolute position setpoint
bPosDerivativeOn_	BOOL	TRUE Activate precontrol function of speed controller.
bMotorRefOffsetOn_	BOOL	FALSE → TRUE Accept home position.
dnMotorRefOffset_p_	DINT	Home position
bQspOn_	BOOL	TRUE Activate quick stop
nPWMAngleOffset_a_	INT	Angular offset input
bSpeedCtrlIOn_	BOOL	TRUE Set I-component of speed controller.
nSpeedCtrlI_a_	INT	I-component of the speed controller
nSpeedSetValue_a_	INT	Main setpoint of speed
bTorqueModeOn_	BOOL	TRUE Switch on torque-guided operation.
nTorqueSetValue_a_	INT	Torque setpoint
bDcBrakeOn_	BOOL	TRUE Activate DC-injection braking.
bTorqueLimitAdaptOn_	BOOL	TRUE Activate adaptation of torque limitation.
nTorqueLimitAdapt_a_	INT	Value for adaptation of torque limitation
Status words		
wMotionState1 wMotionState2	WORD	MCK status word 1 & 2 <ul style="list-style-type: none"> For a detailed description of the individual status bits, see subchapter entitled "MCK status word." Display parameter: C01241
wAuxState	WORD	For future extensions - Output has no function at present time! Additional status word

Identifier	Data type	Value/meaning
Status signal and actual-value signals from Motion Control Kernel functions		
nSpeedSet_v	INT	Speed setpoint selection in [increments/ms] • 16384 \equiv 15000 rpm
dnPosTarget_p	DINT	Target position in [increments] • 65535 \equiv 1 revolution of the motor shaft
dnPosSet_p	DINT	Modulo position in [increments] • 65535 \equiv 1 revolution of the motor shaft ► Activation of the modulo measuring system
dnPosSetRelative_p (from version 02.00.00)	DINT	Relative feed in positioning processes in [increments] • 65535 \equiv 1 revolution of the motor shaft
wActProfileNo	WORD	Number of current profile
wFollowProfileNo	WORD	Number of sequence profile
bBusy	BOOL	TRUE Setpoint profile generation is active.
bDone	BOOL	TRUE Setpoint profile generation is completed (set position = target position).
bHomingDone	BOOL	TRUE Homing has been carried out. • The <i>bHomingDone</i> output, in contrast to the <i>bHomePosAvailable</i> output, remains set to TRUE even if a travel command that resulted in a reset of the home position has been carried out.
bHomePosAvailable	BOOL	TRUE Home position is known. ► Status bit "HomPosAvailable"
bMBrakeReleaseOut	BOOL	Trigger signal for switching element holding brake control via a digital output • Use bit 0 in C02582 to activate inverted switching element triggering. ► Holding brake control
		FALSE Apply brake.
		TRUE Release brake.
bMBrakeReleased	BOOL	"Brake released" status signal considering the brake release time • When the holding brake is triggered to close, <i>bMBrakeReleased</i> is immediately set to FALSE even if the brake closing time has not yet elapsed! ► Holding brake control
		TRUE Brake released (after the brake release time has expired).
bFollowErrLim1 (from version 12.00.00)	BOOL	TRUE The current following error has exceeded the limit 1 for the following error set in C01215/1 via the time set in C01244/2 . ► Following error monitoring system
bFollowErrLim2 (from version 12.00.00)	BOOL	TRUE The current following error has exceeded the limit 2 for the following error set in C01244/3 via the time set in C01215/2 . ► Following error monitoring system
wGearNum wGearDenom (from version 02.00.00)	WORD	Output of the gearbox factor set in C01202/1 and C01202/2 • These outputs can be connected to the <i>GearNum</i> -/ <i>GearDenom</i> inputs of the FBs which process a gearbox factor (FB L_PhiIntegrator 1 , FB L_DFSET 1 , FB L_CalcDiameter 1). • C01067/1...3 can be used to inform these FBs that the gearbox direction of rotation is inverted is mostly done by selecting "motor mounting position inverted").

9.2.1 MCK control word

The motion control function implemented in the [LS_MotionControlKernel](#) system block can be controlled via the *wMotionCtrl1* and *wMotionCtrl2* control words. Together, both control words form a 32-bit control double word which serves to control the entire MotionControlKernel. All motion profiles in the various operating modes can be operated via this interface.

For direct control via a fieldbus system, the two control words can be triggered by the field bus via a port block. In addition to a few other signals (e.g. limit switch, speed override) that are connected to the digital inputs of the drive controller, all control signals can therefore be activated/deactivated via the fieldbus used (CAN, PROFIBUS, etc.).

As an alternative to this, changes to the individual control bits or bit fields (e.g. for specifying the profile number) can also be carried out via separate process inputs provided by the [L_MckCtrlInterface](#) function block. The control words *wOutMckPosCtrl_1* and *wOutMckPosCtrl_2* output by this function block constitute the input information for the [LS_MotionControlKernel](#) system block in this case.

MCK control word 1 (wMotionCtrl1)

Bit	Designation	Description	Bit 3	Bit 2	Bit 1	Bit 0
0	OpMode_Bit0	Operating mode				
...	...	Speed follower	0	0	0	0
...	...	Homing	0	0	0	1
...	...	Manual jog	0	0	1	0
...	...	Positioning	0	0	1	1
...	...	Stop	0	1	0	0
...	...	Position follower	0	1	0	1
All other possible settings are reserved for future extensions!						
4	ManJogPos	Manual jog			Bit 5	Bit 4
5	ManJogNeg	Stop manual jogging			0	0
		Manual jog, right			0	1
		Manual jog, left			1	0
		No change from previous status			1	1
6	ManExecute 2ndSpeed	"1" ≡ Change over to manual speed 2				
7	ReleaseLimitSwitch	"1" ≡ Retract operated hardware limit switch				
8	HomStartStop	"1" ≡ Start/stop homing process				
9	HomSetPos	"1" ≡ Set homing position				
10	HomResetPos	"1" ≡ Reset the "Reference known" status • <i>bHomePosDone</i> and <i>bHomePosAvailable</i> are reset to FALSE. • The positions remain unaffected.				
11	EnableSpeedOverride	"1" ≡ Activate speed override				
12	EnableAccOverride	"1" ≡ Activate acceleration override				
13	Enable SRampOverride	"1" ≡ Activate S-ramp override				
14	PosTeachSetPos	"1" ≡ Teach MCK set position into the selected profile				
15	PosTeachActPos	"1" ≡ Teach current position into the selected profile				

MCK control word 2 (wMotionCtrl2)

Bit	Designation	Description								
16	PosExecute	"0→1" ≡ Start travelling								
17	PosFinishTarget	"0→1" ≡ Complete cancelled profile								
18	PosDisable FollowProfile	"1" ≡ Do not travel sequence profile								
19	PosStop	"1" ≡ Cancel travelling From version 02.00.00, more travel requests will be inhibited ("PosExecute" will be blocked).								
20 ... 23	PosModeBit0 ... PosModeBit3	Positioning mode				Bit 3	Bit 2	Bit 1	Bit 0	
		Positioning mode = setting in C01300/1...15				0	0	0	0	
		Absolute (shortest path)				0	0	0	1	
		Continuous				0	0	1	0	
		Relative				0	0	1	1	
		absolute (Cw)				0	1	0	0	
		absolute (Ccw)				0	1	0	1	
		Absolute (shortest path) to TP				1	0	0	0	
		Continuous to TP				1	0	0	1	
		Relative to TP				1	0	1	0	
		Absolute (Cw) on TP				1	0	1	1	
		Absolute (Ccw) on TP				1	1	0	0	
		All other possible settings are reserved for future extensions!								
24 ... 31	ProfileNo_Bit0 ... ProfileNo_Bit7	Profile	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
		Profile 0	0	0	0	0	0	0	0	0
		Profile 1	0	0	0	0	0	0	0	1
		Profile 2	0	0	0	0	0	0	1	0
								
		Profile 15	0	0	0	0	1	1	1	1
		All other possible settings are reserved for future extensions!								

**Note!**

The profile 0 is no valid profile for the "[Positioning](#)" operating mode.

If a driving request with an invalid profile number is started, the response set in [C00595/12](#) occurs (Lenze setting: "WarningLocked").

**Tip!**

Travel requests/profiles can also be started while the drive is running. The drive does not need to be at standstill.

9.2.2

MCK status word

MCK status word 1 (wMotionState1)

Bit	Designation	Description	Bit 3	Bit 2	Bit 1	Bit 0
0	ActOpModeBit00	Active operating mode				
...	...	Speed follower	0	0	0	0
3	ActOpModeBit03	Homing	0	0	0	1
		Manual jog	0	0	1	0
		Positioning	0	0	1	1
		Stop or Safe stop 1 (SS1)	0	1	0	0
		Position follower	0	1	0	1
		StandBy (internal operating mode in the event of quick stop, pulse inhibit and DC-injection braking)	1	1	1	1
4	Busy	"1" = Internal profile generation is active. A speed profile is being generated.				
5	Done	"1" = Generation of a speed profile with the selected position has been completed.				
6	AcceleratingActive	"1" = Profile generation phase is in the acceleration process.				
7	ConstSpeedDuty	"1" = Profile generation phase at constant speed active.				
8	DeceleratingActive	"1" = Profile generation phase is in the deceleration process.				
9	S_ShapingActive	From version 12.00.00: "1" = Rounding during acceleration/deceleration active. ▶ Status bit "S_ShapingActive"				
10	Pos. HW-Limit Detected	"1" = Positive limit switch has triggered. • Reset only possible via "Manual jog" mode! ▶ Hardware limit switch				
11	Neg. HW-Limit Detected	"1" = Negative limit switch has triggered. • Reset only possible via "Manual jog" mode! ▶ Hardware limit switch				
12	HomPosDone	"1" = Homing has been completed.				
13	HomPosAvailable	"1" = The home position has been detected and is known in the drive. ▶ Status bit "HomPosAvailable"				
14	Pos. SW limit detected	"1" = Positive software limit position overtravelled. ▶ Software limit positions				
15	Neg. SW limit detected	"1" = Negative software limit position overtravelled. ▶ Software limit positions				

**Note!**

The internal "[StandBy](#)" operating mode is assumed if controller inhibit, pulse inhibit, quick stop and/or DC-injection braking are activated.

- No setpoint generation via the **Motion Control Kernel** in this operating mode.
- If the holding brake control sets a controller inhibit when the holding brake is closed, the internal "StandBy" operating mode is not assumed.

MCK status word 2 (wMotionState2)

Bit	Designation	Description																																																							
16	DwellTime	"1" ≡ Dwell time after reaching the setpoint position is active. ▶ Target position monitoring (status "drive in target")																																																							
17	InTarget	"1" ≡ Dwell time has expired and current actual position is in the set target window. ▶ Target position monitoring (status "drive in target")																																																							
18	PosDone	"1" ≡ Positioning profile has been completed in the "Positioning" or "Homing" mode. Setpoint position of a profile data set is in target.																																																							
19	Reserved	-																																																							
20 ... 23	ActPosMode_Bit00 ... ActPosMode_Bit03	<table><tr><th>Active positioning mode</th><th>Bit 3</th><th>Bit 2</th><th>Bit 1</th><th>Bit 0</th></tr><tr><td>Absolute (shortest path)</td><td>0</td><td>0</td><td>0</td><td>1</td></tr><tr><td>Continuous</td><td>0</td><td>0</td><td>1</td><td>0</td></tr><tr><td>Relative</td><td>0</td><td>0</td><td>1</td><td>1</td></tr><tr><td>absolute (Cw)</td><td>0</td><td>1</td><td>0</td><td>0</td></tr><tr><td>absolute (Ccw)</td><td>0</td><td>1</td><td>0</td><td>1</td></tr><tr><td>Absolute (shortest path) to TP</td><td>1</td><td>0</td><td>0</td><td>0</td></tr><tr><td>Continuous to TP</td><td>1</td><td>0</td><td>0</td><td>1</td></tr><tr><td>Relative to TP</td><td>1</td><td>0</td><td>1</td><td>0</td></tr><tr><td>Absolute (Cw) on TP</td><td>1</td><td>0</td><td>1</td><td>1</td></tr><tr><td>Absolute (Ccw) on TP</td><td>1</td><td>1</td><td>0</td><td>0</td></tr></table> <p>Note: The display of the active positioning mode depends on further factors. See subchapter "Override of the parameterised positioning mode".</p>	Active positioning mode	Bit 3	Bit 2	Bit 1	Bit 0	Absolute (shortest path)	0	0	0	1	Continuous	0	0	1	0	Relative	0	0	1	1	absolute (Cw)	0	1	0	0	absolute (Ccw)	0	1	0	1	Absolute (shortest path) to TP	1	0	0	0	Continuous to TP	1	0	0	1	Relative to TP	1	0	1	0	Absolute (Cw) on TP	1	0	1	1	Absolute (Ccw) on TP	1	1	0	0
Active positioning mode	Bit 3	Bit 2	Bit 1	Bit 0																																																					
Absolute (shortest path)	0	0	0	1																																																					
Continuous	0	0	1	0																																																					
Relative	0	0	1	1																																																					
absolute (Cw)	0	1	0	0																																																					
absolute (Ccw)	0	1	0	1																																																					
Absolute (shortest path) to TP	1	0	0	0																																																					
Continuous to TP	1	0	0	1																																																					
Relative to TP	1	0	1	0																																																					
Absolute (Cw) on TP	1	0	1	1																																																					
Absolute (Ccw) on TP	1	1	0	0																																																					
24 ... 31	ActProfileNo_Bit00 ... ActProfileNo_Bit07	<table><tr><th>Active profile</th><th>Bit 7</th><th>Bit 6</th><th>Bit 5</th><th>Bit 4</th><th>Bit 3</th><th>Bit 2</th><th>Bit 1</th><th>Bit 0</th></tr><tr><td>Profile 0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td></tr><tr><td>Profile 1</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>1</td></tr><tr><td>Profile 2</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>1</td><td>0</td></tr><tr><td>...</td><td colspan="8">...</td></tr><tr><td>Profile 15</td><td>0</td><td>0</td><td>0</td><td>0</td><td>1</td><td>1</td><td>1</td><td>1</td></tr></table>	Active profile	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0	Profile 0	0	0	0	0	0	0	0	0	Profile 1	0	0	0	0	0	0	0	1	Profile 2	0	0	0	0	0	0	1	0								Profile 15	0	0	0	0	1	1	1	1	
Active profile	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0																																																	
Profile 0	0	0	0	0	0	0	0	0																																																	
Profile 1	0	0	0	0	0	0	0	1																																																	
Profile 2	0	0	0	0	0	0	1	0																																																	
...	...																																																								
Profile 15	0	0	0	0	1	1	1	1																																																	

**Note!**

The effective positioning mode is generated via the MCK control word (bit 20 ... 23) and/or the parameters [C01300/1...15](#) for defining the positioning mode in the profile data. Here, the setting in the MCK control word superimposes the mode selection via the corresponding parameter. This means that the mode selection and the touch probe enable are possible via process data.

For generating the effective positioning mode, the following applies:

- Valid PosMode in the MCK control word:
→ Use positioning mode of the MCK control word
- PosMode in the MCK control word = 0:
→ Use positioning mode set in [C01300/x](#)
- Invalid PosMode in the MCK control word:
→ Error message "Ck09: Positioning mode invalid"

9.2.2.1 Status bit "HomPosAvailable"

Bit 13 ("HomPosAvailable") in the MCK status word 1 shows that the reference position has been detected and is known in the drive.

An available reference information (bit 13 = "1") and thus a valid measuring system is required for the following functions:

- Positioning in the "[Positioning](#)" operating mode in the following ([C01300/1...15](#)) positioning modes:
 - 1: absolute (beeline)
 - 4: absolute (Cw)
 - 5: absolute (Ccw)
 - 8: absolute (shortest path) to TP
 - 11: absolute (Cw) to TP
 - 12: absolute (Ccw) to TP
- Response to set software limit positions
- Stopping on breakpoints in the "[Manual jog](#)" operating mode
- Traversing of a sequence profile with absolute measuring reference in the "[Homing](#)" mode after homing is completed

Resetting the reference information

The following events reset bit 13 ("HomPosAvailable") in the MCK status word 1:

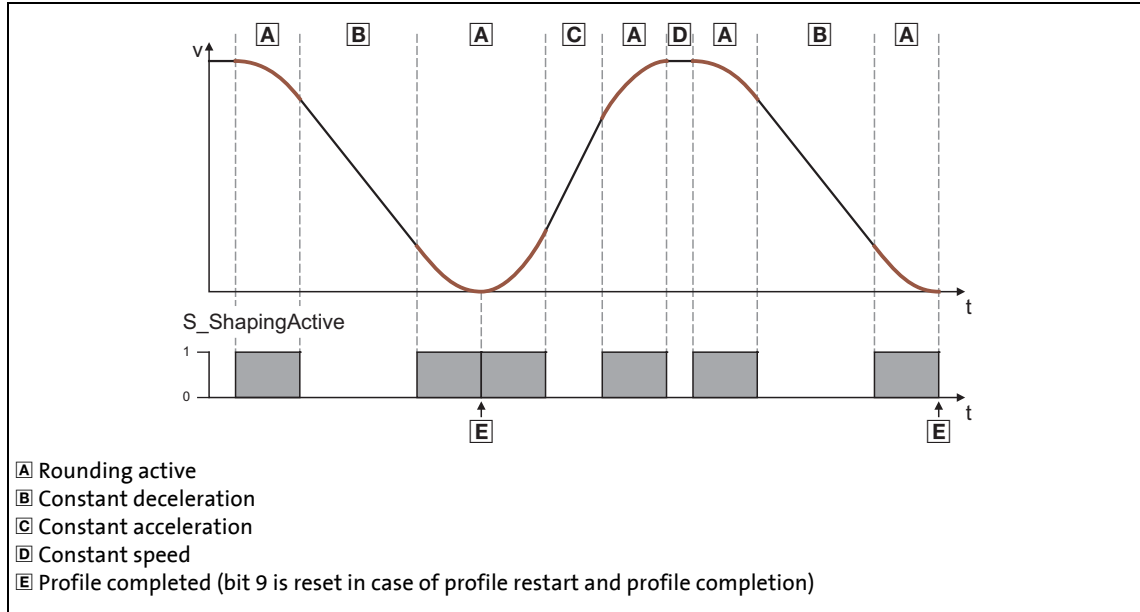
- Setting bit 10 ("HomResetPos") in the MCK control word 1
- Overtravelling the 32-bit position display area at the limit ± 2147483647 increments when the cycle ([C1201/1](#)) = "0 units".
- Change of the position encoder selection in [C00490](#)
- Change of the cycle in [C1201/1](#)
- Writing on the machine parameters if bit 1 ("delete reference when machine data is changed") is set in [C2652](#).
 - Machine parameters are cycle ([C1201/1](#)), gearbox factors ([C1202/1...2](#), [C1203/1...2](#)) and feed constant ([C1204](#)).
 - The mere writing of these parameters (even when the previous value is used) causes the reference to be deleted!
- Encoder error when a position encoder is used at the multi-encoder interface
- Resolver error when a resolver is used as position encoder
- Mains recovery at a cycle set unlike "0 units" in [C1201/1](#) and if the position difference at reference recovery is higher than 1000 cycles.

9.2.2.2 Status bit "S_ShapingActive"

This function extension is available from version 12.00.00!

Bit 9 ("S_ShapingActive") in the MCK status word 1 indicates in the operating modes "[Homing](#)", "[Manual jog](#)", "[Positioning](#)", "[Stop](#)" and "[Position follower](#)" when rounding is effective while S-shaped profiles are being carried out.

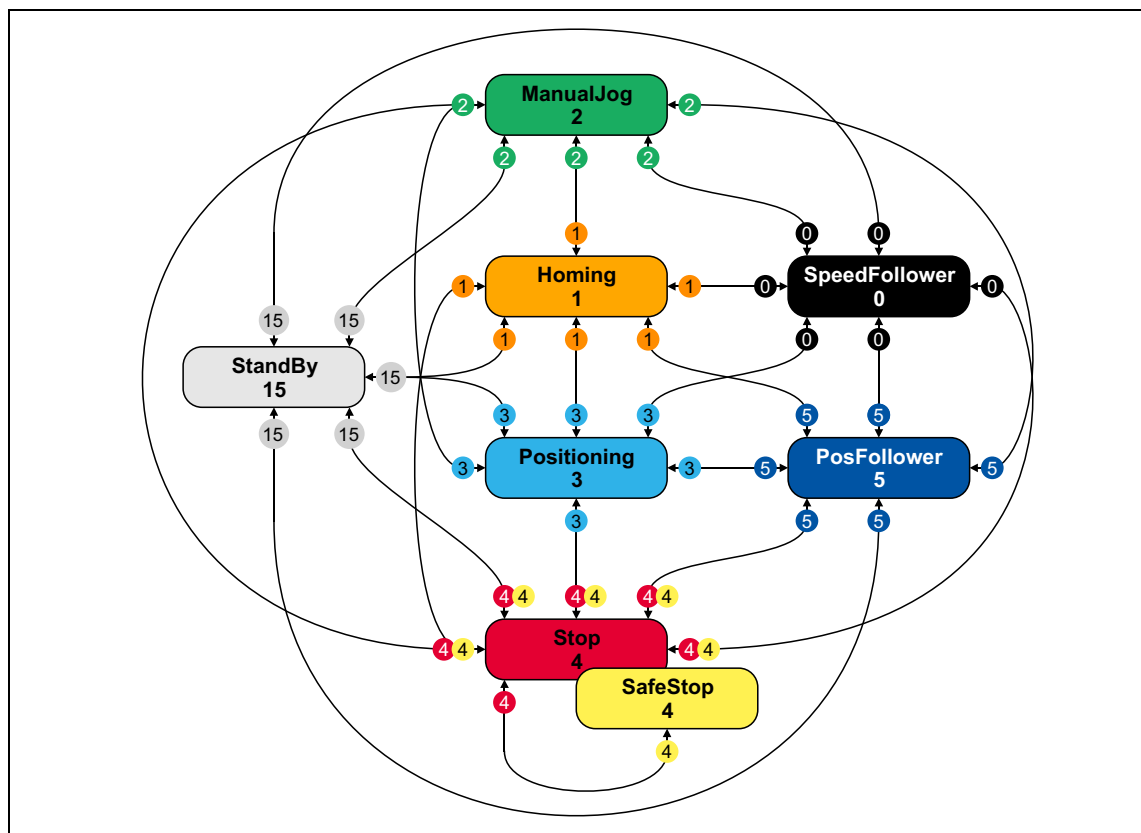
- Bit 9 is usually reset in case of profile restarts and after profiles have been completed.
- The following illustration shows this by means of a real temporal characteristic:



[9-2] Example: Display of the rounding generated via the "S_ShapingActive" status bit

9.2.3 MCK state machine

Prio	Condition	
Global conditions:		
1	<div>15</div> Setpoint generation through Motor control (MCTRL) : <ul style="list-style-type: none">• DCB = DC-injection braking• QSP = quick stop• CINH = controller inhibit	<div><div>DCB →</div><div>QSP →</div><div>CINH →</div><div>≥1</div><div>→ 15</div></div>
2	<div>4</div> "Safe stop 1" (SS1) requested ▶ Interface to safety system	<div><div>DCB →</div><div>QSP →</div><div>CINH →</div><div>SafeStop1 →</div><div>&</div><div>→ 4</div></div>
Conditions requested by MCK control word :		<div>Bit 3</div> <div>Bit 2</div> <div>Bit 1</div> <div>Bit 0</div>
3	<div>2</div> Manual jog requested	<div>0</div> <div>0</div> <div>1</div> <div>0</div>
4	<div>1</div> Homing requested	<div>0</div> <div>0</div> <div>0</div> <div>1</div>
5	<div>3</div> Positioning requested	<div>0</div> <div>0</div> <div>1</div> <div>1</div>
6	<div>0</div> Speed follower requested	<div>0</div> <div>0</div> <div>0</div> <div>0</div>
7	<div>5</div> Position follower requested	<div>0</div> <div>1</div> <div>0</div> <div>1</div>
8	<div>4</div> Stop requested	<div>0</div> <div>1</div> <div>0</div> <div>0</div>



[9-3] MCK state machine

9.2.3.1 "StandBy" operating mode

The internal "StandBy" operating mode is implicitly assumed if controller inhibit, pulse inhibit, quick stop and/or DC-injection braking are activated. Thus, there is no setpoint generation by the **Motion Control Kernel** in the "StandBy" operating mode.

- If the holding brake control sets a controller inhibit when the holding brake is closed, the internal "StandBy" operating mode is not assumed.
- The "StandBy" operating mode cannot be activated via the MCK control word.
- When the "StandBy" operating mode is active, bits 0 ... 3 are set in the MCK status word.

Speed acceptance when the "StandBy" operating mode is quit

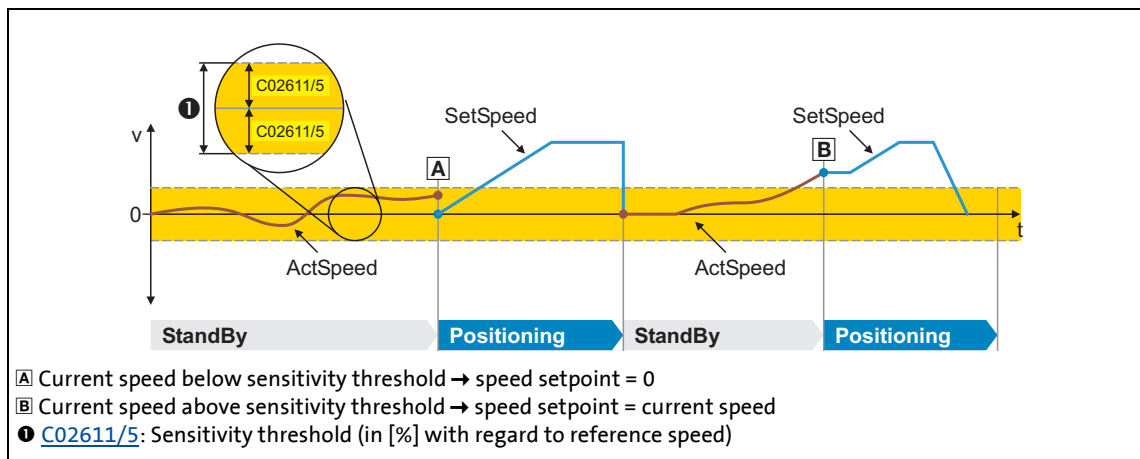
In addition to cancelling the controller inhibit, pulse inhibit, quick stop and/or DC injection braking, a change to another operating mode from "StandBy" also requires a termination of the magnetisation of the motor (not in case of synchronous motors). If there is a change to a setpoint-controlled operating mode of the **Motion Control Kernel** the current speed is transferred to the speed setpoint.



Note!

Due to a motor magnetisation of a motor normally standing still, the current speed can also be non-zero rpm when "StandBy" is quit. If the operating mode now changes to "Positioning", the transfer of this speed to the speed setpoint may cause a permanent drifting of the motor shaft, depending on the activated option in [C01216](#).

From version [V12.00.00 onwards](#), a sensitivity threshold can be set for preventing a drifting of the motor shaft in [C2611/5](#). If the absolute value of the current speed is below the sensitivity threshold, the value "0" is transferred to the speed setpoint instead of the current speed. The following illustration shows the issue:



[9-4] Example: Sensitivity threshold for speed transfer from the "StandBy" operating mode

In the Lenze setting "0.5 %", the sensitivity threshold corresponds to approx. 7.5 rpm at a reference speed of 1500 rpm set in [C00011](#).

9.2.4 Interface to safety system

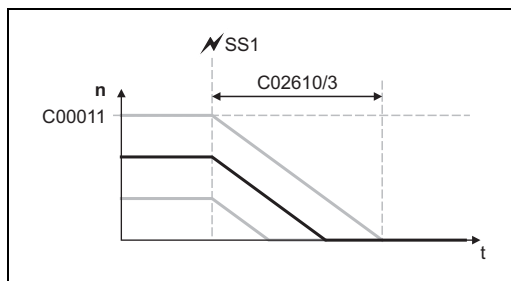
For operation with optional safety system, the [LS_MotionControlKernel](#) system block has the *wSMCtrl* input. This interface is used to transfer a control word by means of which the **Motion Control Kernel** can be supplied with information on requested or active safety functions. The **Motion Control Kernel** then initiates the necessary motion sequence (e.g. braking).

At the moment, only bit 0 in the *wSMCtrl* control word has a function. Additional functions are in preparation:

Bit	Designation	Description
0	SafeStop1	"1" = Request for "Safe Stop 1" (SS1).
1	Reserved	In preparation - Still without function!
...		
15		

Behaviour in case of request for "Safe Stop 1" (SS1)

The drive is brought to a standstill with the stopping ramp set in [C02610/3](#).



- The time set in [C02610/3](#) refers to the down-ramping of the reference speed set in [C00011](#).
- If the current speed is lower, the time to standstill is accordingly lower as well.

[9-5] Ramping down to standstill

If the request is reset during the down-ramping process (bit 0 = "1→0"), the behaviour depends on the active operating mode:

- In the "[Speed follower](#)" operating mode, direct synchronisation with the target speed takes place with the ramp time set in [C02610/2](#).
- In the "[Homing](#)" operating mode, the ramp-down is continued with the deceleration for stop set in [C01251](#) if the bit 8 ("HomStartStop") in the MCK control word = "0". If bit 8 is set, the homing process starts immediately in the selected homing mode.
- In the "[Manual jog](#)" operating mode, the behaviour depends on whether the manual jog initiator (*bManJogPos* or *bManJogNeg*) is still set:

Bit 0 (SafeStop1)	bManJogPos bManJogNeg	Behaviour
1	TRUE	Ramping down to standstill
0	TRUE	Accelerating to manual speed
0	FALSE	Ramping down to standstill

- In the "[Positioning](#)" operating mode, the behaviour depends on the setting in [C01216](#).
- In the "[Position follower](#)" operating mode, (forward) positioning to the signalled absolute position always takes place if this position differs from the internal position.

9.2.5 Consideration of residual value in case of external profile calculation

The *dnProfilePosition_p* input serves to transfer a profile position in [increments] to the SB [LS_MotionControlKernel](#). This will then be entered into the active profile data set selected in the [MCK control word](#) via the bits 24 ... 31.

For (external) calculations to be carried out before, the following blocks can be used in the FB Editor.

- From version 12.00.00 onwards, these blocks automatically consider residual values and modulo positions in case of a cycle length definition and correctly forward these internally:

Block	Function
L_ConvUnitsToIncr_1 L_ConvUnitsToIncr_2 L_ConvUnitsToIncr_3	... converts a position value provided in the real unit of the machine into an internal 32-bit position value. • These FBs are available from version 12.00.00.
L_MckCtrlInterface_1	... provides the application with process inputs for controlling various basic functions of the Motion Control Kernel.
LS_ParFreeUnit LS_ParFreeUnit_2	Output of 16 parameterisable position signals with internal conversion of [unit] in [increments] • These SBs are available from version 02.00.00.

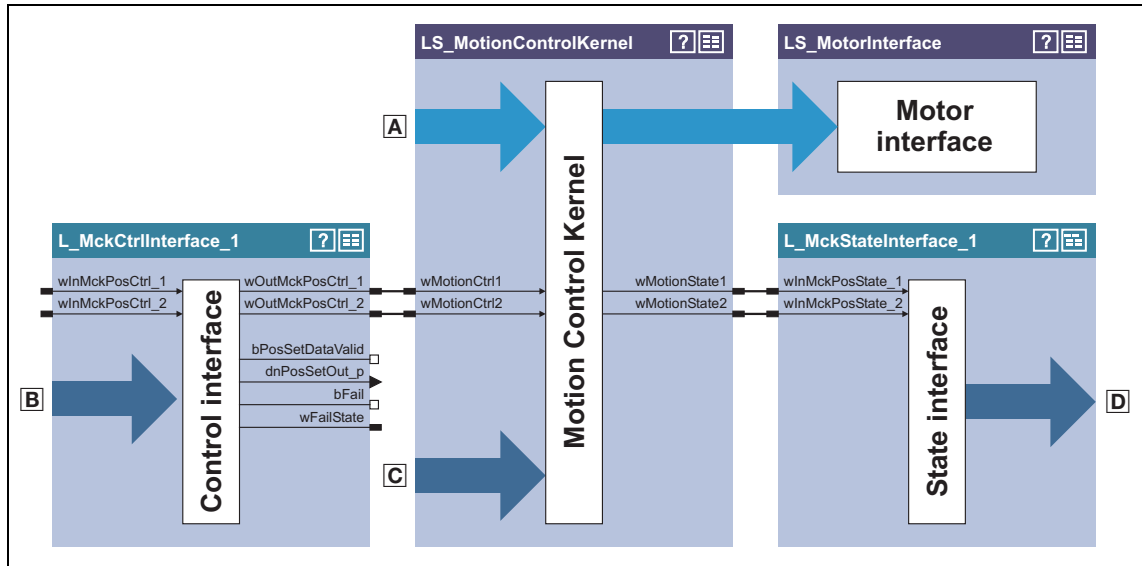
The following blocks also automatically consider residual values and module positions and can be used for forwarding the increment results of the previously mentioned blocks:

Block	Function
L_Mux_1	... switches one of eight selectable input signals to the output.
L_SignalSwitch32_1 L_SignalSwitch32_2 L_SignalSwitch32_3	... switches between two input signals of "DINT" data type. • These FBs are available from version 02.00.00.
LA_SwitchPos / LA_TabPos : • dnFreeIn1_p • dnFreeIn2_p	These two inputs serve to transfer 32-bit signals from the I/O level to the application level. The signals are available at the correspondent outputs of the application block LA_SwitchPosIn or LA_TabPosIn .
LA_TabPos : • dnPosProfilePosition	Selection of the target position in [increments] for the "table positioning" application. The signal is available in the application level at the correspondent output of the LA_TabPosIn application block.

9.3

MCKInterface

The so-called "MCK interface" described in this chapter consists of the two function blocks [L_MckCtrlInterface](#) and [L_MckStateInterface](#), which are connected upstream respectively downstream of the [LS_MotionControlKernel](#) system block:



[9-6] Detail of the interconnection architecture for the "table positioning" technology application

A Control and setpoint signals for motor control

B Additional process inputs for controlling the **Motion Control Kernel**, e.g.:

- Selection of the operating mode
- Selection of the profile number
- Override of the positioning mode
- Control inputs for manual jogging, homing, positioning
- Control inputs for speed/acceleration/S-ramp override

C Control and setpoint signals for the **Motion Control Kernel** such as

- Selection of speed setpoint for speed follower
- Selection of positioning setpoint for position follower
- Selection of override values
- Connection for limit switch & pre-stop mark for homing
- Holding brake control

D Output of status signals of the **Motion Control Kernel**

Control of the Motion Control Kernel

Control of the basic drive functions implemented in the Motion Control Kernel is carried out by means of

- direct specification of the control words, for example via a master control unit also connected to the fieldbus.
 - For this purpose, the control word inputs can be directly connected to the field bus interface **LP_McIn** respectively **LP_CanIn**.
 - See the "[MCK control word](#)" chapter for a detailed description of the individual control bits.
- the specification of individual process signals at the [L_MckCtrlInterface](#) FB which are then ORed with the control word.

Plausibility check

The process signals applied to the [L_MckCtrlInterface](#) FB are logically linked by means of an OR logic operation to the specified control word via the two control word inputs *wInMckPosCtrl_1* and *wInMckPosCtrl_2* and, after a plausibility check, are output via the two control word outputs *wOutMckPosCtrl_1* and *wOutMckPosCtrl_2*.

- The profile number, the operating mode, and the positioning mode are checked for plausibility.
- If implausibility is detected, only control bit information is output and the *bFail* output is set to TRUE.
- The result of the plausibility check is provided as the *wFailState* output word and displayed in [C01299](#).

The control words that are output, namely *wOutMckPosCtrl_1* and *wOutMckPosCtrl_2*, constitute the input information for the [LS_MotionControlKernel](#) system block.

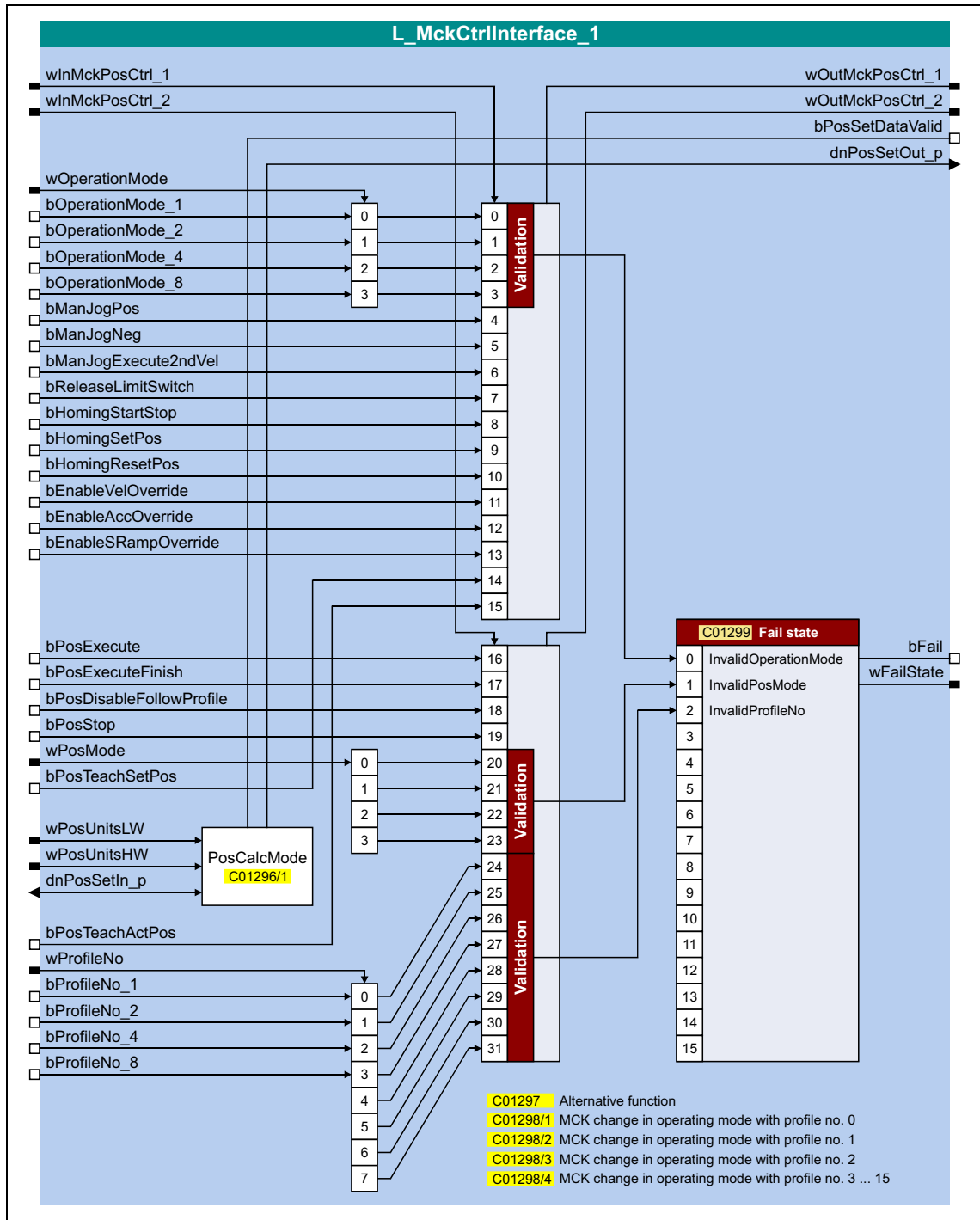
Status information of the Motion Control Kernel

Output by the [LS_MotionControlKernel](#), the status words *wMotionState1* and *wMotionState2* also constitute input information for the downstream [L_MckStateInterface](#) FB, which provides this information to the application in the form of process signals.

9.3.1 Control inputs | "L_MckCtrlInterface" function block


This FB provides process inputs for controlling different basic functions of the **Motion Control Kernel**.

In addition to the ORing of discrete input signals with the control word inputs, the FB has further functions that are described in the following subchapters.



Inputs

Identifier	Data type	Information/possible settings														
wInMckPosCtrl_1 wInMckPosCtrl_2	WORD	<p><u>Direct</u> specification of the MCK control word 1 & 2</p> <ul style="list-style-type: none">For example, via a master control unit that is also connected to the fieldbus. For this purpose, the control word inputs can be directly connected to the LP_McIn respectively LP_CanIn1 fieldbus interface.The two control words together form a 32-bit double control word with which the entire Motion Control Kernel is controlled.All motion profiles in the different operating modes can be operated via this interface.See the "MCK control word" chapter for a detailed description of the individual control bits.														
wOperationMode	WORD	<p>Selection of the operating mode of the Motion Control Kernel</p> <ul style="list-style-type: none">Only bit 0 ... bit 3 of <i>wOperationMode</i> are evaluated.If an invalid operating mode is selected, the response set in C00595/11 is activated (Lenze setting: "Warning").The current operating mode is displayed in C01243. <table><tr><td>0</td><td>Speed follower</td></tr><tr><td>1</td><td>Homing</td></tr><tr><td>2</td><td>Manual jog</td></tr><tr><td>3</td><td>Positioning</td></tr><tr><td>4</td><td>Stop</td></tr><tr><td>5</td><td>Position follower</td></tr><tr><td>6 ... 15</td><td>Reserved for future extensions</td></tr></table>	0	Speed follower	1	Homing	2	Manual jog	3	Positioning	4	Stop	5	Position follower	6 ... 15	Reserved for future extensions
0	Speed follower															
1	Homing															
2	Manual jog															
3	Positioning															
4	Stop															
5	Position follower															
6 ... 15	Reserved for future extensions															
bOperationMode_1 ... bOperationMode_8	BOOL	<p>Binary-coded selection of the operating mode of the Motion Control Kernel</p> <ul style="list-style-type: none">See the "MCK control word" chapter for a detailed description of the individual control bits.If an invalid operating mode is selected, the response set in C00595/11 is activated (Lenze setting: "Warning").The current operating mode is displayed in C01243.														
bManJogPos bManJogNeg	BOOL	<p>Manual jog:</p> <p><i>bManJogPos</i> = TRUE: Manual jog right</p> <p><i>bManJogNeg</i> = TRUE: Manual jog left</p> <p>Both inputs = TRUE: No change compared to previous state</p> <p>Both inputs = FALSE: Stop manual jog</p>														
bManJogExecute2ndVel	BOOL	<p>Manual jog: Changeover to speed 2</p> <table><tr><td>FALSE</td><td>Speed 1 (C01231/1) active</td></tr><tr><td>TRUE</td><td>Speed 2 (C01231/2) active</td></tr></table>	FALSE	Speed 1 (C01231/1) active	TRUE	Speed 2 (C01231/2) active										
FALSE	Speed 1 (C01231/1) active															
TRUE	Speed 2 (C01231/2) active															
bReleaseLimitSwitch	BOOL	<p>Manual jog: Retract operated limit switch</p> <table><tr><td>TRUE</td><td>Retract operated limit switch (in opposite direction)</td></tr></table>	TRUE	Retract operated limit switch (in opposite direction)												
TRUE	Retract operated limit switch (in opposite direction)															

Identifier	Data type	Information/possible settings
bHomingStartStop	BOOL	Homing: Start/stop homing • Only possible in the "referencing" operating mode.
		TRUE If one of homing modes "4" ... "15" in C01221 is selected: Start reference search • The current status of the reference search is indicated via the status outputs <i>bHomingDone</i> and <i>bHomePosAvailable</i> . • If the 100_Set_Ref_directly" referencing mode has been selected in C01221 , the home position can be set manually via the <i>bHomeStartStop</i> input with the drive at a standstill. The current actual position is set as the home position (C01227/2)
		If homing mode "100: SetRef" is selected: Setting the home position manually • The home position is set manually with the drive at a standstill. The current actual position now corresponds to the reference position set in C01227/2 in the machine measuring system.
bHomingSetPos	BOOL	TRUE↔FALSE Stop homing. • If the <i>bHomingStartStop</i> input is reset to FALSE during active referencing, homing is cancelled and the drive is brought to a standstill.
		Homing: Set home position ("on the fly" homing) • With referencing "on the fly", the home position of a machine can be set during ongoing movement. Jerking and compensating movements do not occur.
bHomingResetPos	BOOL	FALSE↔TRUE The position at the <i>dnMotorRefOffset_p</i> input of the LS MotionControlKernel SB at the instant of activation is the set home position.
		Homing: Delete home position Note: With this function, positions are not deleted but only the status signals <i>bHomePosAvailable</i> and <i>bHomePosDone</i> are reset. Setpoints and actual positions remain untouched until a renewed reference setting or homing.
bEnableVelOverride	BOOL	TRUE↔FALSE The internal status "reference known" is reset. • The controller is no longer referenced. • The process outputs <i>bHomePosAvailable</i> and <i>bHomingDone</i> are reset to FALSE.
		Speed override
bEnableAccOverride	BOOL	TRUE Activate speed override
		Acceleration override
bEnableSRampOverride	BOOL	TRUE Activate acceleration override
		S-ramp smoothing override
bPosExecute	BOOL	 Note! If the <i>nSRampOverride_a</i> input on the LS MotionControlKernel remains unconnected or if "0 %" is specified as the override value, activation of the S-ramp override results in deactivation of the S-ramp time. • Deactivation of the S-ramp time before the start of a profile with S-ramp time causes linear ramp generation. • Deactivation of the S-ramp time during a traversing process, however, is not accepted immediately in the profile generator, but the profile generator checks automatically when an online change of the ramp form can be carried out and then initiates it automatically.
		TRUE Activate S-ramp smoothing override
bPosExecuteFinish	BOOL	Positioning: Start travelling
		FALSE↔TRUE Execute selected profile
bPosExecuteFinish	BOOL	Positioning: Complete cancelled profile
		FALSE↔TRUE A positioning process previously cancelled, e.g. by <i>bPosStop</i> or due to a device error, is resumed by travelling to the original target.

Identifier	Data type	Information/possible settings																						
bPosDisableFollowProfile	BOOL	Positioning : Do not execute sequence profile (switch-off profile linkage) <table><tr><td>TRUE</td><td>Evaluation of the sequence profile number parameterised in C01307/1...15 for the selected profile is suppressed.</td></tr></table>	TRUE	Evaluation of the sequence profile number parameterised in C01307/1...15 for the selected profile is suppressed.																				
TRUE	Evaluation of the sequence profile number parameterised in C01307/1...15 for the selected profile is suppressed.																							
bPosStop	BOOL	Positioning : Cancel travelling <table><tr><td>TRUE</td><td>Stop positioning From version 02.00.00, more travel requests will be inhibited ("PosExecute" will be blocked).</td></tr></table>	TRUE	Stop positioning From version 02.00.00, more travel requests will be inhibited ("PosExecute" will be blocked).																				
TRUE	Stop positioning From version 02.00.00, more travel requests will be inhibited ("PosExecute" will be blocked).																							
wPosMode	WORD	Override of the positioning mode set in the profile data <ul style="list-style-type: none">Via this input, an override of the positioning mode parameterised in C01300/1...15 for the selected profile is possible.The value set in C01300/1...15 is not overwritten in this case.Only bit 0 ... bit 3 of <i>wPosMode</i> are evaluated.If <i>wPosMode</i> = 0 is selected, the positioning mode set in C01300/1...15 is used. <table><tr><td>0</td><td>Positioning mode = setting in C01300/1...15</td></tr><tr><td>1</td><td>Absolute (shortest path)</td></tr><tr><td>2</td><td>Continuous</td></tr><tr><td>3</td><td>Relative</td></tr><tr><td>4</td><td>absolute (Cw)</td></tr><tr><td>5</td><td>absolute (Ccw)</td></tr><tr><td>8</td><td>Absolute (shortest path) to TP</td></tr><tr><td>9</td><td>Continuous to TP</td></tr><tr><td>10</td><td>Relative to TP</td></tr><tr><td>11</td><td>Absolute (Cw) on TP</td></tr><tr><td>12</td><td>Absolute (Ccw) on TP</td></tr></table> <p>All other possible settings are reserved for future extensions!</p>	0	Positioning mode = setting in C01300/1...15	1	Absolute (shortest path)	2	Continuous	3	Relative	4	absolute (Cw)	5	absolute (Ccw)	8	Absolute (shortest path) to TP	9	Continuous to TP	10	Relative to TP	11	Absolute (Cw) on TP	12	Absolute (Ccw) on TP
0	Positioning mode = setting in C01300/1...15																							
1	Absolute (shortest path)																							
2	Continuous																							
3	Relative																							
4	absolute (Cw)																							
5	absolute (Ccw)																							
8	Absolute (shortest path) to TP																							
9	Continuous to TP																							
10	Relative to TP																							
11	Absolute (Cw) on TP																							
12	Absolute (Ccw) on TP																							
bPosTeachSetPos	BOOL	Position teaching : MCK setpoint position <table><tr><td>FALSE↗TRUE</td><td>Teach MCK setpoint position into the selected profile.</td></tr></table>	FALSE↗TRUE	Teach MCK setpoint position into the selected profile.																				
FALSE↗TRUE	Teach MCK setpoint position into the selected profile.																							
wPosUnitsLW wPosUnitsHW	WORD	Selection of the target position in [units] <ul style="list-style-type: none"><i>wPosUnitsLW</i> = LOW word, <i>wPosUnitsHW</i> = HIGH wordThe mode for calculating the position is selected in C01296/1.																						
dnPosSetIn_p	DINT	Selection of the target position in [increments] <ul style="list-style-type: none">The mode for calculating the position is selected in C01296/1.																						
bPosTeachActPos	BOOL	Position teaching : Current position <table><tr><td>FALSE↗TRUE</td><td>Teach current position into the selected profile.</td></tr></table>	FALSE↗TRUE	Teach current position into the selected profile.																				
FALSE↗TRUE	Teach current position into the selected profile.																							
wProfileNo	WORD	Stipulation of the profile to be executed <ul style="list-style-type: none">Optionally as a data word or binary coded.																						
bProfileNo_1 ... bProfileNo_8	BOOL	<ul style="list-style-type: none">When the profile is stipulated, this FB carries out a mode change in the Lenze setting at the same time:<ul style="list-style-type: none">If profile 0 is selected: Activation of "Speed follower" operating modeIf profile 1 is selected: Activation of "Homing" operating modeIf profile 2 is selected: Activation of "Manual jog" operating modeIf profile 3 ... 15 is selected: Activation of "Positioning" operating mode																						

Outputs

Identifier	Data type	Value/meaning	
wOutMckPosCtrl_1 wOutMckPosCtrl_2	WORD	Output of the MCK control word 1 & 2 <ul style="list-style-type: none">For transfer to the LS_MotionControlKernel system block.For a detailed description of the individual control bits, see chapter "MCK control word". (□ 560)	
bPosSetDataValid	BOOL		Status signal "Position conversion completed, data consistent" <ul style="list-style-type: none">This output is permanently set to TRUE if the g"0: dnPosOut_p=dnPosIn_p" mode has been set for the position calculation in C01296/1 and no modulo measuring system exists.If a cycle length has been set in C01201/1, a calculation is made under the following conditions without an immediate setting of <i>bPosSetDataValid</i>:<ul style="list-style-type: none">Position specification is higher than or equal to the cycle length.Position specification is negative. For a correct positioning process, the <i>bPosSetDataValid</i> = TRUE status is required.
		TRUE	Conversion of the target position from [units] into [increments] has been completed. <ul style="list-style-type: none">The travel profile data are valid and the profile is ready to start.
dnPosSetOut_p	DINT	Output of the target position in [increments] <ul style="list-style-type: none">Observe the <i>bPosSetDataValid</i> status output!	
wFailState	WORD	Result of the plausibility check <ul style="list-style-type: none">Display parameter: C01299Result is bit coded:	
		Bit 0	Invalid operating mode selection <ul style="list-style-type: none">"1" ≡ The selected operating mode is not defined/invalid.
		Bit 1	Invalid positioning mode selection <ul style="list-style-type: none">"1" ≡ The selected positioning mode is not defined/invalid.
		Bit 2	Invalid profile number selection <ul style="list-style-type: none">"1" ≡ The selected profile number refers to a profile data set that does not exist.
		Bit 3	Reserved
		...	
bFail	BOOL	FALSE	Okay, no error
		TRUE	<ul style="list-style-type: none">Plausibility check error orcontrol information error (in this case after ORing the individual signals with the control words)

9.3.1.1 Alternative functions for control bit "PosExecute"

In [C01297](#), alternative functions for bit 16 (PosExecute) in the MCK control word can be selected with bit-coding.

PosStop with PosExecute = FALSE

If bit 0 has been set in [C01297](#), positioning can only be started/cancelled with the "PosExecute" control bit.

- If the "Positioning" operating mode has been set on the MCK, the "Pos-Execute" control bit has the following effects when being activated:

Signals at the input	Signals in the control word to the MCK
bPosExecute = TRUE	bPosExecute = TRUE bPosStop = FALSE bHomingStartStop remains unchanged
bPosExecute = FALSE	bPosExecute = FALSE bPosStop = TRUE bHomingStartStop remains unchanged

HomingStartStop with PosExecute

If bit 1 has been set in [C01297](#), homing can only be started/stopped with the "PosExecute" control bit.

- If the "Homing" operating mode has been set on the MCK, the "PosExecute" control bit has the following effect when activated:

Signals at the input	Signals in the control word to the MCK
bPosExecute = TRUE	bPosExecute = TRUE bPosStop = FALSE bHomingStartStop = TRUE
bPosExecute = FALSE	bPosExecute = FALSE bPosStop remains unchanged bHomingStartStop = FALSE

SetProfilPosition with PosExecute

If bit 2 has been set in [C01297](#) and control bit ("PosExecute") is being set, the setpoint position being applied is incorporated in the currently selected profile and then the profile is started immediately.

- If the "Positioning" operating mode has been set on the MCK, the "PosExecute" control bit has the following effect when activated:

Signals at the input	Signals in the control word to the MCK
bPosExecute = TRUE	bPosExecute = TRUE bPosStop = FALSE bHomingStartStop remains unchanged bPosTeachSetPos = TRUE (edge)
bPosExecute = FALSE	bPosExecute = FALSE bPosStop remains unchanged bHomingStartStop remains unchanged bPosTeachSetPos = FALSE

SetProfilPosition at position change

If bit 3 is set in [C01297](#), the setpoint positions at the MCKInterface are automatically accepted into the profile with the applied profile number if a change of data is detected at the corresponding input for the setpoint position.

- If the "0: dnPosOut_p=dnPosIn_p" mode has been set in [C01296/1](#) for converting the position, automatic acceptance is executed if the incremental position selection at the *dnPosIn_p* input was changed.
- If another mode (>0) has been set in [C01296/1](#), automatic acceptance is executed if the incremental position selection at the *wPosUnitsLW* and *wPosUnitsHW* inputs was changed.
- From version 02.00.00 a hysteresis can be set in [C01245/3](#) for the position change.

PosExecute at position change

(from version 02.00.00)

If bit 4 is set in [C01297](#), an automatic "PosExecute" takes place if the incremental position selection changes and this change is higher than set in the hysteresis for position change ([C01245/3](#)).

If the selection is made in units, so that in a first step it has to be converted into increments, and if this automatic function is then activated, the "PosExecute" will only be created automatically when the internal conversion is completed (*bPosSetDataValid*).



Tip!

This option serves to start travel requests very easily by simply defining the new target position.

9.3.1.2 Operating mode change with profile number

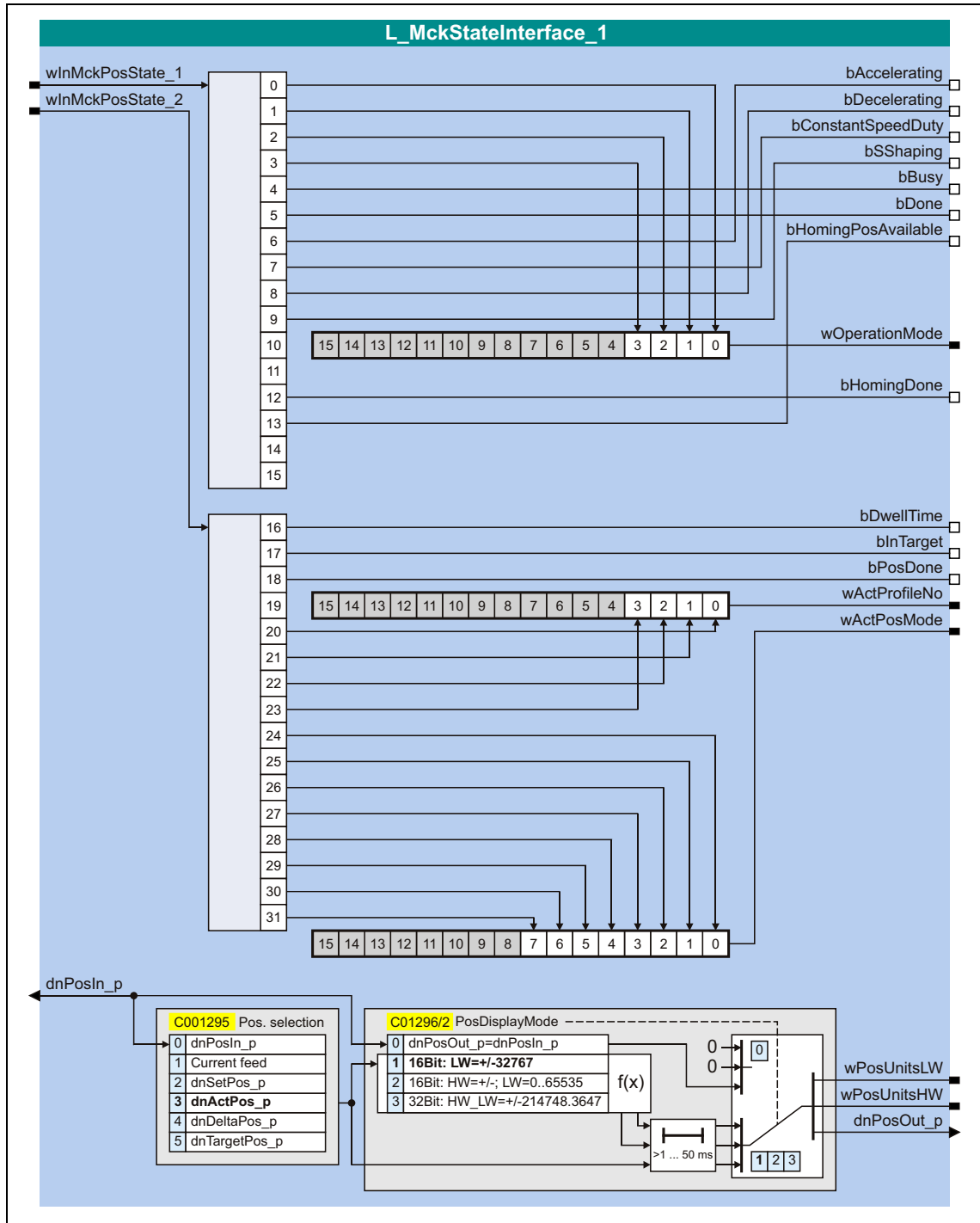
One of the operating modes of the **LS_MotionControlKernel** system block can be assigned to the positioning profiles via the four subcodes of [C01298](#):

Parameter	Info	Lenze setting
C01298/1	Operating mode if profile 0 is selected	Speed follower
C01298/2	Operating mode if profile 1 is selected	Homing
C01298/3	Operating mode if profile 2 is selected	Manual jog
C01298/4	Operating mode if profile 3 ... 15 is selected	Positioning

- When a changeover to the corresponding profile is carried out, the set operating module is requested at the same time.
- In the case of the setting "0: No change", the operating mode is not changed when the profile changeover occurs. Instead, the operating mode requested "from outside" via the [MCK control word](#) is applicable.

9.3.2 Status outputs | FB "L_MckStateInterface"

This FB provides the application with different status information of the **Motion Control Kernel** via process outputs.



**Note!**

When [C01296/2](#) > 0, the position selected in [C01295](#) is calculated in [units]. In this case, the output values *wPosUnitsLW*, *wPosUnitsHW* and *dnPosOut_p* are not updated in a 1-ms cycle (not in real time). However, they are applied consistently to each other. For this reason, we recommend the use of these outputs only for diagnostic purposes where an update in real time is not important.

Inputs

Identifier	Data type	Information/possible settings
wInMckPosState_1 wInMckPosState_2	WORD	Inputs for accepting the status words from the LS_MotionControlKernel system block.
dnPosIn_p	DINT	Position in [increments] <ul style="list-style-type: none"> Is converted into [units] if C01295 = "0: dnPosIn_p" and output at the <i>wPosUnitsLW</i> and <i>wPosUnitsHW</i> outputs. The mode for calculating the position is selected in C01296/2.

Outputs

Identifier	Data type	Value/meaning
bAccelerating	BOOL	TRUE Acceleration phase active.
bDecelerating	BOOL	TRUE Braking phase active.
bConstantSpeedDuty	BOOL	TRUE Constant phase active.
bSShaping	BOOL	From version 12.00.00: TRUE Profile rounding active.
bBusy	BOOL	TRUE Setpoint generation active.
bDone	BOOL	TRUE Target position (setpoint) has been approached.
bHomingPosAvailable	BOOL	TRUE Home position is known.
wOperationMode	WORD	Active setpoint-generating state of the Motion Control Kernel . <ul style="list-style-type: none"> Bit B0 ... B3 contain the information of the MCK status word. Bits B4 ... B15 are fixed at "0".
bHomingDone	BOOL	TRUE Homing has been executed.
bDwellTime	BOOL	TRUE Settling in target position is active
bInTarget	BOOL	TRUE Target position (actual value) is in the target window.
bPosDone	BOOL	TRUE Target position from the profile has been approached.
wActProfileNo	WORD	Current traversing profile number <ul style="list-style-type: none"> Bit B0 ... B7 contain the information of the MCK status word. Bits B8 ... B15 are fixed at "0".

Identifier	Data type	Value/meaning
wActPosMode	WORD	Current positioning mode <ul style="list-style-type: none"> • Bit B0 ... B3 contain the information of the MCK status word. • Bits B4 ... B15 are fixed at "0".
wPosUnitsLW wPosUnitsHW	WORD	Output of the position selected in C01295 in [units] <ul style="list-style-type: none"> • <i>wPosUnitsLW</i> = LOW word, <i>wPosUnitsHW</i> = HIGH word • The mode for calculating the position is selected in C01296/2. • These values are <u>not</u> updated in a 1-ms cycle (<u>not</u> in real time)!
dnPosOut_p	DINT	Output of the position selected in C01295 in [increments] <ul style="list-style-type: none"> • The mode for calculating the position is selected in C01296/2. • When C01296/2 > 0, <i>dnPosOut_p</i> is updated isochronously with the outputs <i>wPosUnitsLW</i> and <i>wPosUnitsHW</i> and hence <u>not</u> in a 1-ms cycle (<u>not</u> in real time)!

9.4 Basic settings

9.4.1 Machine parameters

The motor end, among other things, is described by the machine parameters indicated below in respect of the mechanics used.



Note!

Setting the machine parameters is a basic prerequisite for the operating modes "[Homing](#)", "[Manual jog](#)" and "[Positioning](#)".

The more precisely the machine parameters are set, the better the results of positioning!

For [TA "Table positioning"](#), you can set the machine parameters in the »Engineer« on the tab headed **Application Parameters** on the dialog level *Overview → Machine parameters*:



Tip!

You are provided with more detailed information on the machine parameters "[Gearbox ratio](#)" and "[Feed constant](#)" in the following subchapters.

Short overview of machine parameters:

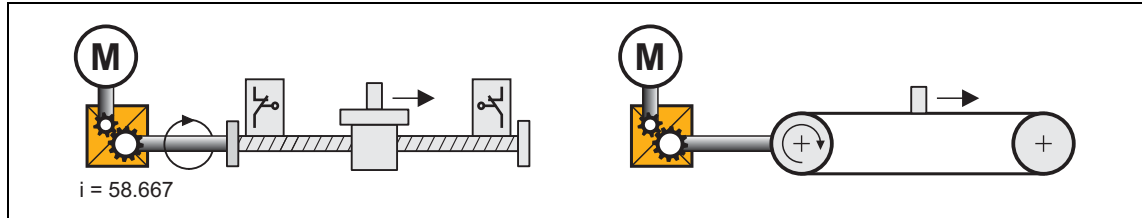
Parameter	Info	Lenze setting	
		Value	Unit
C01206/1	Mounting direction: Motor	0: Not inverted	
C01202/1	iM: Nominator of gearbox factor Z2	1	
C01202/2	iM: Denominator of gearbox factor Z1	1	
C01206/2	Mounting direction: Position encoder	0: Not inverted	
C01203/1	iG: Numerator (motor speed)	1	
C01203/2	iG: Denominator (encoder speed)	1	
C01201/1	Axis data: Axis cycle ▶ Activation of the modulo measuring system	0.0000	units
C01204	Axis data: Feed constant	360.0000	units/rev.
C00011	Appl.: Reference speed	1500	rpm

After the machine parameters have been entered, the drive controller sends back application-relevant data via the following display parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C01211/1	Max. traversing speed 100%_C11 • Is used for orientation when the velocity is being set in the profile sets.	-	units/s
C01205	Axis data: Position resolution • Is needed for the incremental specification of positions.	-	incr/unit
C01210/5	MCK: Positioning accuracy • Theoretical accuracy during positioning with account being taken of the machine data and encoder data.	-	units
C00057	Maximum torque	-	Nm
C01213/1	MCK: Max. traversing distance	-	units
Highlighted in grey = display parameter			

9.4.1.1 Gearbox ratio

The gearbox ratio indicates the number of revolutions of the motor axis it takes for exactly one revolution of the load axis (e.g. spindle or drive roll) to take place.

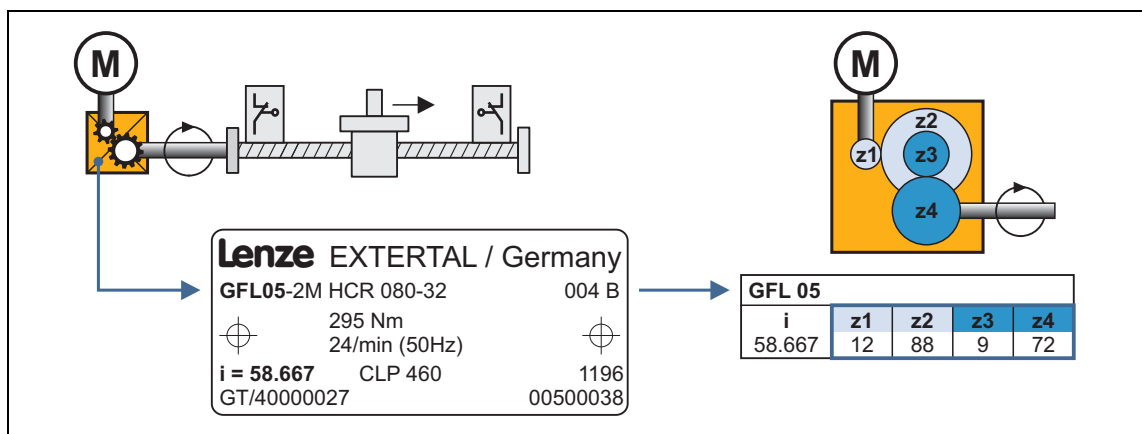


[9-7] Schematic diagram of gearbox ratio

- In the example shown in the illustration [9-7], the spindle rotates exactly once for every 58,667 rotations of the motor axis.

Specification of the gearbox ratio

- The gearbox ratio is to be defined in the form of a quotient (numerator/denominator); the data required can be found in the technical data for the gearbox:



[9-8] Example: Technical data relating to the gearbox (from gearbox catalogue)



Tip!

In order to specify the gearbox ratio exactly, use the number of teeth indicated on the data sheet or in the catalogue, if possible, instead of the information on the nameplate (see following calculation).

Example calculation on the basis of the technical gearbox data:

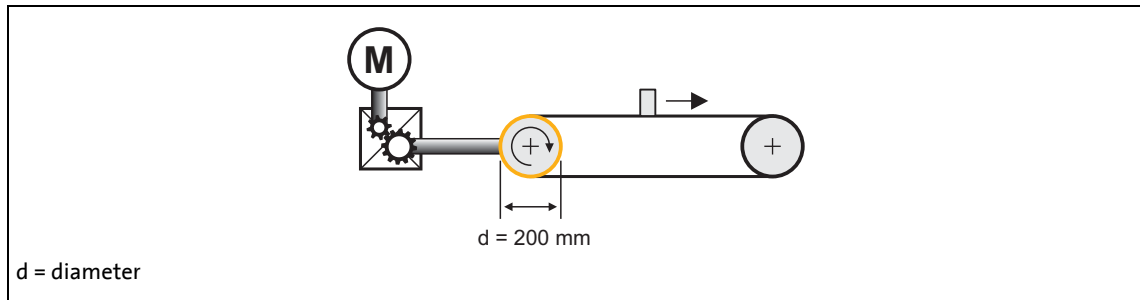
Gearbox factor numerator (C01202/1)	=	$z2 \times z4$	=	88×72	=	6336
Gearbox factor denominator (C01202/2)	=	$z1 \times z3$	=	12×9	=	108

[9-9] Calculation example (for 2-stage gearbox)

9.4.1.2 Feed constant

The feed constant corresponds to the movement of the machine during one revolution of the gearbox output shaft.

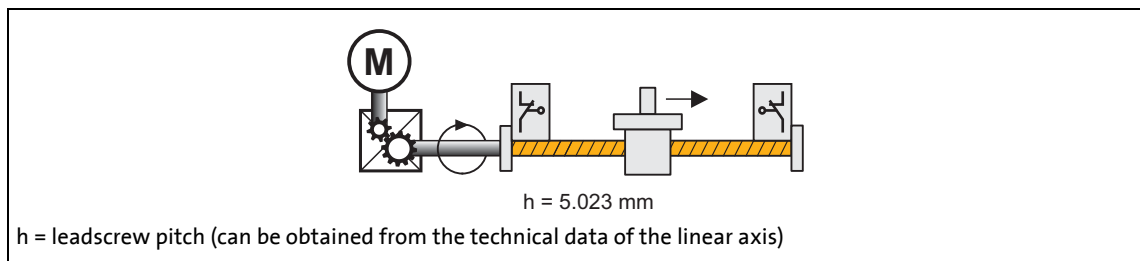
- The entry in the **Feed constant** ([C01204](#)) field is made in the user unit [units] in respect of the revolution.
- In the case of a conveyor drive, the feed constant is obtained from the drive roll's circumference, which, in the following example, is calculated on the basis of the indicated diameter:



$$\text{Feed constant} = \pi \cdot d \frac{[\text{unit}]}{\text{Revolution}} = \pi \cdot 200 \frac{\text{mm}}{\text{Revolution}} = 628.3185 \frac{\text{mm}}{\text{Revolution}}$$

[9-10] Schematic diagram: Feed constant for a conveyor driver

- In the case of a spindle drive (linear axis), the feed constant is derived from the leadscrew pitch. The feed constant indicates the distance the slide travels during one revolution of the spindle (in the following example: 5.023 mm).

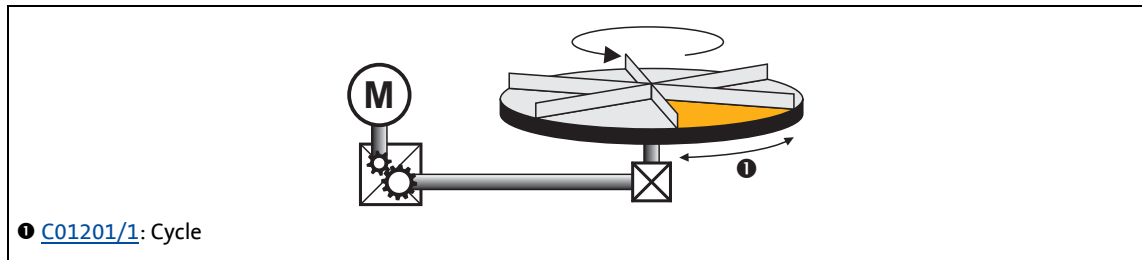


[9-11] Schematic diagram: Feed constant for a spindle drive

- In the case of a rotary table and its specification as an angle, the feed constant is = 360°/revolution.

9.4.1.3 Activation of the modulo measuring system

The modulo measuring system is also called "rotary table application".



[9-12] Example: Rotary table application

- The measuring system is repeated.
- If the set cycle is exceeded, a defined overflow takes place.
 - In a rotary system, the cycle corresponds to one revolution or a tool distance.
- For positioning, the home position must be known.
 - Exception: Positioning modes relative (TP) and continuous (TP)
- Software limit positions are not effective.
- Absolute targets can be approached by exceeding the measuring system limit, e.g. from 10° via 0° to 350°.

Activating the modulo measuring system

The Modulo system is activated by setting a cycle ([C01201/1](#)) > 0 units.

- The setting of the cycle is possible when the controller is enabled.
- When the cycle ([C01201/1](#)) is set to 0 units (Lenze setting), the traversing range is unlimited (classical measuring system).

Creation of the modulo measuring system

When the Modulo measuring system is active, it is displayed internally via an integrator. The Modulo position is provided at the *dnPosSet_p* process output of the SB [LS MotionControlKernel](#) and displayed in [C01210/7](#). When the Modulo measuring system is not active, the continuous (*dnPosSetValue_p*) setpoint position is output instead.

Blocking zone for "absolute (Cw)" and "absolute (Ccw)" positioning modes

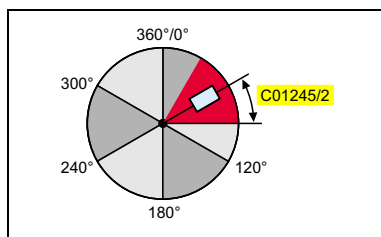
Set a blocking zone in [C01245/2](#) for the "absolute (Cw)" and "absolute (Ccw)" positioning modes in which no target positions are approached. This blocking zone around the current setpoint position serves to consider drift motions of the shaft in case of controller inhibit/enable cycles in order to prevent e.g. an unwanted motion by one cycle.



Stop!

With the "absolute (Cw)" and "absolute (Ccw)" positioning modes, target positions that are located in the set blocking zone are always approached by the shortest possible path!

If the blocking zone is set too large, the drive may travel in the opposite direction!



[9-13] Definition of the blocking zone

- Target positions outside the blocking zone are approached with the selected positioning mode.
- The blocking zone is internally limited to half the cycle.

Display of the target position in the "positioning" mode

Positioning mode	Target position displayed in C01210/6 in [units]
Absolute (shortest path)	Defined position
absolute (Cw)	Defined position
absolute (Ccw)	Defined position
Continuous	214748.3647
Relative	Modulo position + defined position

Case studies for modulo positioning

In the following, some case studies with the different positioning modes are represented. The target positions are defined by the user.

Positioning mode "absolute (shortest path)"			
Case 1	Case 2	Case 3	Case 4
Positioning mode "absolute (Cw)"			
Case 1	Case 2	Case 3	Case 4
Positioning mode "absolute (Ccw)"			
Case 1	Case 2	Case 3	Case 4

9.4.2 Min/Max speed

For the "[Speed follower](#)" operating mode, you can initially limit the speed setpoint by means of the following parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C02610/2	MCK: Ramp time synchr. setpoint	2.000	s
C02611/1	MCK: Pos. max. speed	199.99	%
C02611/2	MCK: Pos. min. speed	0.00	%
C02611/3	MCK: Neg. min. speed	0.00	%
C02611/4	MCK: Neg. max. speed	199.99	%

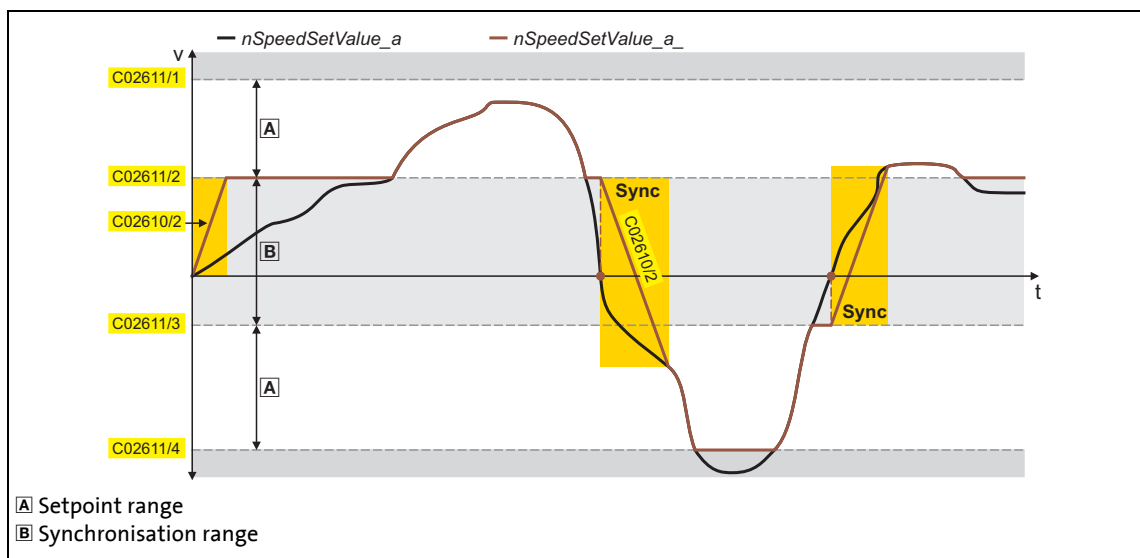
In the »Engineer«, you can set the initial limit by means of the dialog box *Min/Max speed*.

- Open the *Min/max speed* dialog box by opening the **Application Parameters** tab and clicking on the following button on the dialog level *Overview* → *Signal flow*:



Speed setpoint generation

When the speed limit values are set, the **Motion Control Kernel** influences the setpoint generation with a synchronisation mode. The synchronisation mode serves to travel the synchronisation range dynamically with the synchronisation ramp set in [C02610/2](#). Synchronisation always starts in the zero crossing of the defined speed.



[9-14] Example: Speed setpoint generation in the "Speed follower" operating mode (with $nSpeedAddValue_v = 0$)

9.4.3 Limit position monitoring

9.4.3.1 Software limit positions

The parameterisable limit positions are used by the software to limit the traversing range.

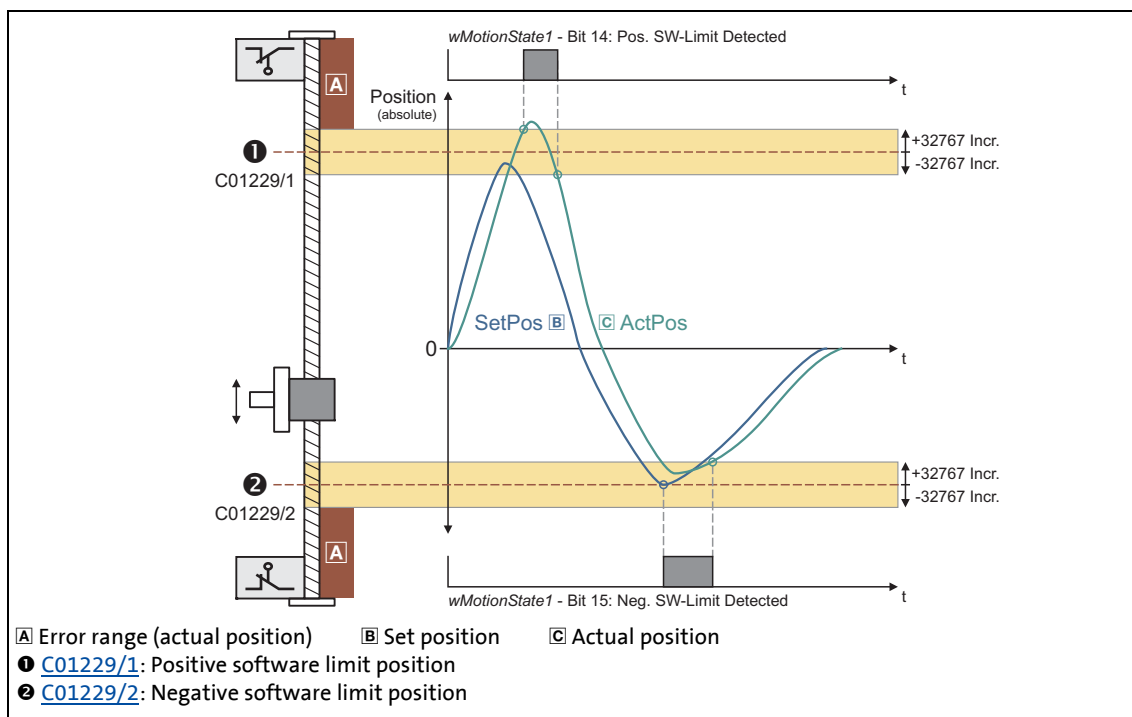
- The positive software limit position is set in [C01229/1](#) and the negative software limit position is set in [C01229/2](#).



Stop!

The software limit positions are only evaluated and monitoring if the drive knows the home position and the software limit positions for the respective operating mode have been activated (see the following table)!

Operating mode	Effective software limit positions (if home position is known)
Speed follower	Yes (adjustable in C01219 - bit 3)
Homing	Yes
Manual jog	No (adjustable in C01230 - bit 3)
Positioning	Yes
Position follower	Yes (adjustable in C01218 - bit 3)



[9-15] Definition of the software limit position trigger limits

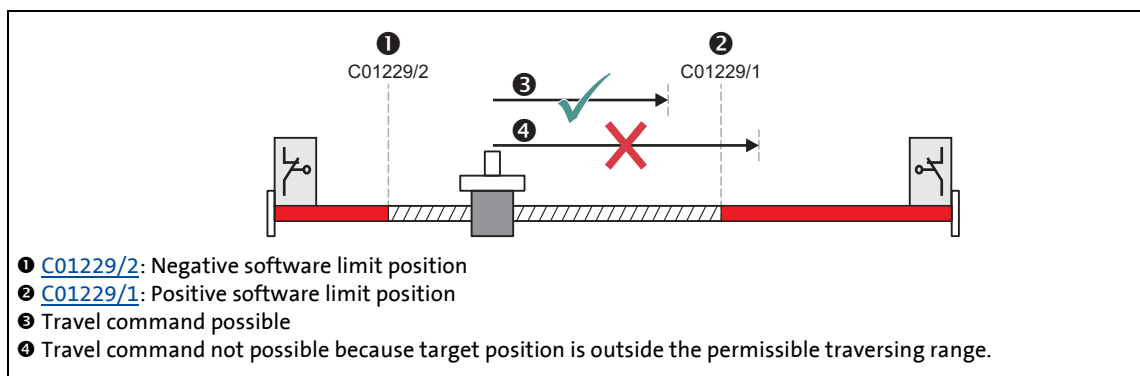
Behaviour in the case of active software limit positions



Note!

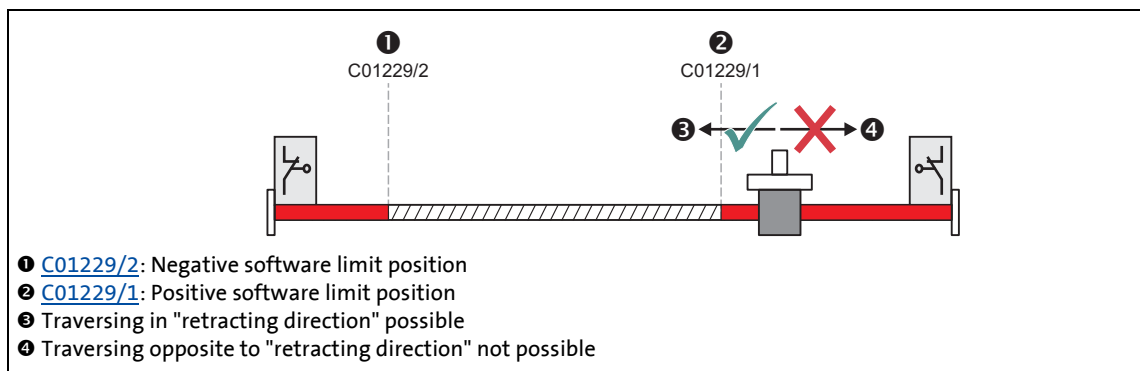
The "travel commands" mentioned in the following description are no speed setpoint selections. In the operating modes "[Speed follower](#)" and "[Position follower](#)", an acknowledged software limit position error ensures that traversing into the impermissible travel range remains possible afterwards. This is because in these two operating modes, there is no preview whether a software limit position is approached or not with a setpoint selection.

If the software limit positions are active, travelling commands that would result in exiting from the permissible travel range can no longer be executed:



[9-16] Example: Traversing range limitation by means of software limit positions

If the drive is already outside the permissible travel range and the software limit positions have been activated, only travel commands that result in the drive moving back into the permissible travel range can be executed:



[9-17] Example: Permissible traversing direction if software limit positions active

If the software limit positions are active and a software limit position is passed ("overtravel"):

- The error response "TroubleQuickStop" takes place in the Lenze setting, i.e. the drive is brought to a standstill in the deceleration time set for the quick stop function and does so irrespective of the setpoint selection. The error response can be parameterised in [C00595/3](#) and [C00595/4](#).
- The error message "Ck03: Pos. SW limit position" or "Ck04: Neg. SW limit position" is entered in the logbook of the drive controller.
- Depending on the parameterised fault response, the drive cannot traverse until the error has been acknowledged.

9.4.3.2 Hardware limit switch

The travel range limits are monitored by means of limit switches via the inputs *bLimitSwitchPos* and *bLimitSwitchNeg* of the [LS MotionControlKernel](#) system block.

- The two inputs react to the TRUE state.
- In [TA "Table positioning"](#), the two inputs are connected to the digital inputs provided for connection of the limit switches.



Stop!

The limit switches are only evaluated if the limit switches for the respective operating mode have been activated (see the following table)!

Operating mode	Hardware limit switch effective
Speed follower	Yes (adjustable in C01219 - bit 2)
Homing	Depending on the selected homing mode (see description of the homing modes)
Manual jog	No (adjustable in C01230 - bit 2)
Positioning	Yes
Stop	Yes
Position follower	Yes (adjustable in C01218 - bit 2)



Note!

If the digital inputs used for connecting the limit switches are fail-safe inputs (tripping at LOW level), you simply change the terminal polarity of the corresponding digital inputs in [C00114](#).

Behaviour when hardware limit switches are active

If one of the two monitoring inputs is set to TRUE:

- The error response "TroubleQuickStop" takes place in the Lenze setting, i.e. the drive is brought to a standstill in the deceleration time set for the quick stop function and does so irrespective of the setpoint selection. The error response can be parameterised in [C00595/1](#) and [C00595/2](#).
- The error message "Ck01: Pos. HW limit switch" or "Ck02: Neg. HW limit switch" is entered in the logbook.
- Bit 10 ("Pos. HW-Limit Detected") or bit 11 ("Neg. HW-Limit Detected") is set in the [MCK status word](#).
- Depending on the parameterised fault response, the drive cannot traverse until the error has been acknowledged.



Note!

An activated limit switch can be retracted again by manual jog in the opposed direction or with the "Retract limit switch" function. ▶ [Retracting of an operated limit switch](#) (632)

Only in the "[Manual jog](#)" operating mode, retracting of the limit switch resets bit 10 ("Pos. HW-Limit Detected") or bit 11 ("Neg. HW-Limit Detected") in the [MCK status word](#).

Re-activation after acknowledging the error

When the error has been acknowledged and the limit switch is still active, the following action is required for a renewed activation of the monitoring depending on the operating mode:

Operating mode	Action for (re) activation
Speed follower	Limit switch is activated and setpoint in direction of the activated limit switch is pending Note: If the setpoint e.g. is specified via an analog potentiometer, potentiometer noise can mean an unintentional setpoint causing the error to be set again.
Homing	Limit switch is activated and <i>bHomStartStop</i> = TRUE
Manual jog	Limit switch is activated and manual jog in direction of the activated limit switch
Positioning	Limit switch is activated and setpoint command has been transmitted
Stop	Setting of the operating mode
Position follower	Limit switch is activated and setpoint in direction of the activated limit switch is pending

9.4.4 Target position monitoring (status "drive in target")

The target position monitoring detects whether the drive has reached the target.



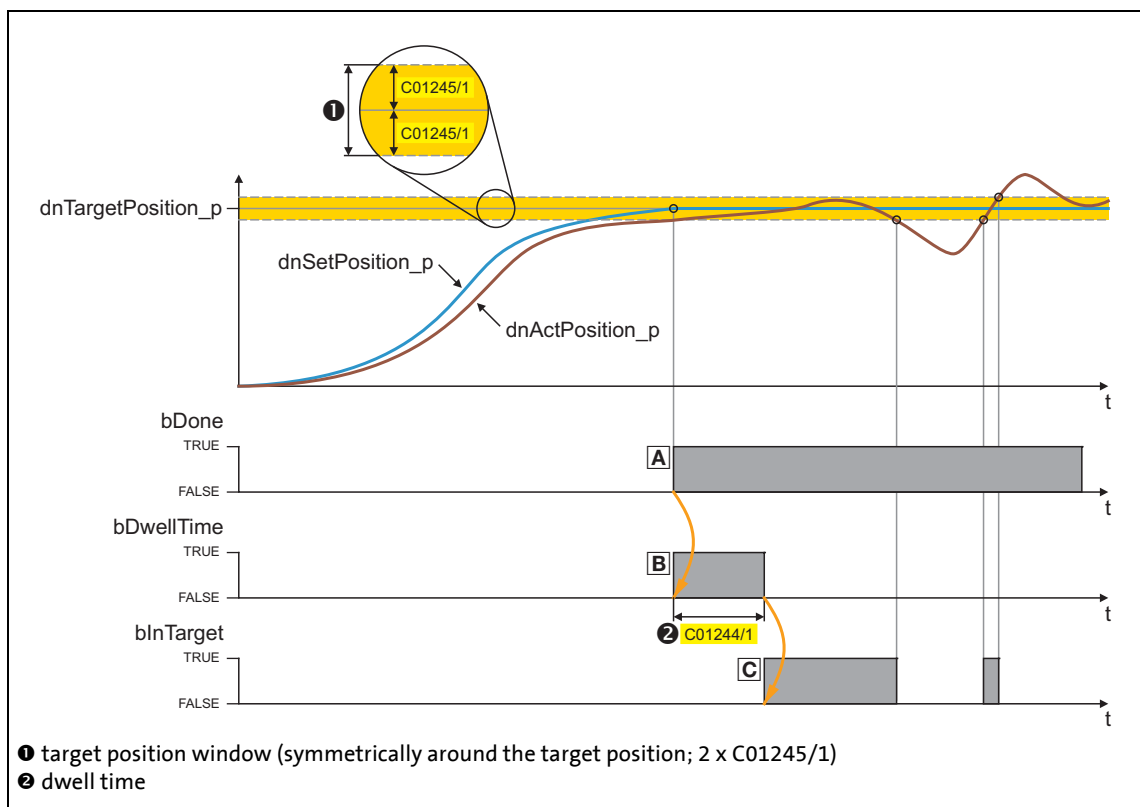
Note!

- The target position detection is active with the following operating modes/functions:
 - Operating mode "[Positioning](#)": Absolute and relative positioning mode
 - Operating mode "[Homing](#)": After approaching the starting position via start profile (if start profile has been selected)
 - Operating mode "[Manual jog](#)": When the breakpoints and the software limit positions are approached
- The target position monitoring is active until the operating mode changes or a new travel command influences the setpoint.

Short overview of the parameters for target position monitoring:

Parameter	Info	Lenze setting	
		Value	Unit
C01244/1	MCK: Dwell time - target position <ul style="list-style-type: none"> • For considering mechanical transient phenomena of the tool when the target position is reached. 	100	ms
C01245/1	MCK: Window target position <ul style="list-style-type: none"> • Symmetrical window around the target position. 	1.0000	units

Principal procedure of the position detection



[9-18] Signal characteristics

Status "Done" (A)

- The position setpoint has reached the target position.

Status "DwellTime" (B)

- Bit 16 in the [MCK status word](#) or the *bDwellTime* output of the [L_MckStateInterface](#) FB is set when the setpoint position has been reached after the dwell time set in [C01244/1](#) has expired.
- The status detects the time after the *bDone* signal when settling to target position is executed and actual position detection is not active yet.

Status "InTarget" (C)

- If the actual position is within the symmetrical target position window after the dwell time has expired, bit 17 is set to "1" in the [MCK status word](#) or the *bInTarget* output of the [L_MckStateInterface](#) FB is set to TRUE.

**Note!**

- The target position including the target position window has to be within the maximum traversing range.
- Please observe the following if you use *bInTarget* as stepping condition in a step sequence:
The *bInTarget* signal needs the set position to be located in the target. A profile restart immediately deletes the setpoint position in the first cycle and thus also resets *bInTarget*.

- The "InTarget" status is reset if:
 - the motor shaft leaves the target position window,
 - a new profile or a new motion process is started,
 - *bInTarget* has been set via manual jog (intermediate stops) and the "[Manual jog](#)" mode is left,
 - the target position window has been left in the "[Speed follower](#)" mode and a speed setpoint not equal to "0" is injected into the process,
 - a new homing process starts,
 - the reference is set,
 - the device is switched off/on.

9.4.5 Monitoring of the maximum travel distance

Continuous travel requests in the "[Positioning](#)" operating mode (or relative positioning with feed in the same direction) cause an overflow of the position integrators when the max. display area of the position is reached and the reference is set. The same behaviour takes place in the "[Speed follower](#)" and "[Manual jog](#)" operating modes. For this reason, a monitoring mode of the maximum travel distance is implemented in the **Motion Control Kernel**.

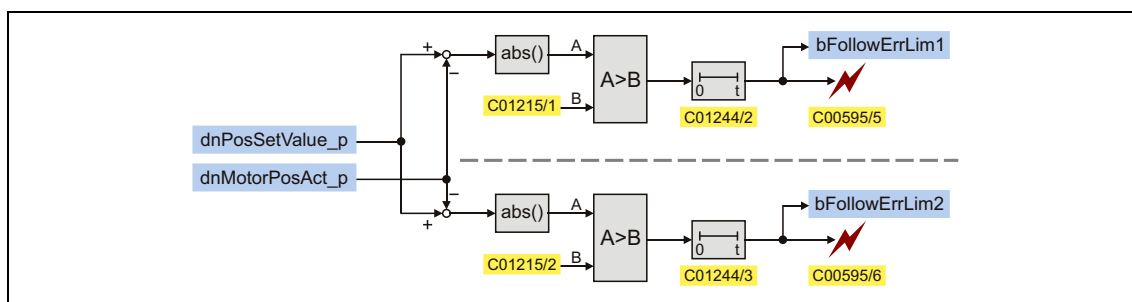
- If the maximum travel distance ([C01213/1](#)) is exceeded:
 - The error response set in [C00595/7](#) will be carried out (Lenze setting: "TroubleQuickStop").
 - The "[Ck07: Travel range limit exceeded](#)" error message is entered into the logbook.
 - The internal status "reference known" is reset (the controller is no longer referenced).
- A setting of [C00595/7](#) = "0: No Reaction" deactivates the monitoring.

9.4.6 Following error monitoring system

The difference between set position and actual position is called the following error. Ideally, the following error should be "0". The set position is created by the internal definition of the traversing profiles of the **Motion Control Kernel**. The actual position is created by the integration of the speed supplied by the position encoder. If the position control is adjusted optimally, only a minimum following error arises which is always compensated dynamically and not increases continuously.

Certain processes, however, require that a defined limit as a difference between set position and actual position is not exceeded. If it is exceeded, it may have been caused by a mechanical blocking in the machine and the system part is not situated at the position defined at that time. In such a case, it makes sense to activate the "Fault" error response to make the motor torqueless.

In the 8400 TopLine controller, two independent following error monitoring systems can be parameterised:



[9-19] Two-channel following error monitoring system

Parameter	Info	Lenze setting	
		Value	Unit
C01215/1	MCK: Following error limit 1	0.0000	units
C01215/2	MCK: Following error limit 2	0.0000	units
C01244/2	MCK: Following error deceleration 1	0.000	s
C01244/3	MCK: Following error deceleration 2	0.000	s
C00595/5	MCK: Resp. to following error 1	Warning	
C00595/6	MCK: Resp. to following error 2	Warning	



Note!

If the limit for the following error is set to "0.0000 units" (Lenze setting, the following error monitoring system is not active.



Tip!

In certain situations (e.g. dynamic acceleration of the load), higher system-dependent following errors occur than while approaching the target position.

In order that no error is triggered during acceleration and a close tolerance limit can be monitored all the same at standstill in the target, the addressing of the following error monitoring system can be decelerated. Thus, dynamic processes or torque impulses occurring for short periods can be "masked out".

Operating mode

If the limit for the following error in [C01215/1..2](#) is set higher than "0.0000 units" and if the current following error exceeds this limit over the time set in [C01244/x](#):

- The error response set in [C00595/5](#) or [C00595/6](#) will be carried out (Lenze setting: "Warning").
- The error message "[Ck05: Error, following error 1](#)" or "[Ck06: Error, following error 2](#)" will be entered into the logbook.
- The status output *bFollowErrLim1* or *bFollowErrLim2* at the SB [LS_MotionControlKernel](#) is set to TRUE.

9.4.6.1 Monitoring of the following error in case of controller inhibit

Up to and including version 13.xx.xx, the setpoint position is always set = actual position in case of controller inhibit.

From version 14.00.00 onwards, the setpoint position is only set = actual position if the current following error reaches the limit value set in [C01215/3](#).

- In the Lenze setting [C01215/3](#) = "0.0000 units" the behaviour is as before, i.e. the setpoint position is immediately set = actual position in case of controller inhibit.

Parameter	Info	Lenze setting	
		Value	Unit
C01215/3	MCK: Following error SetPos=ActPos	0.0000	units



Note!

The limit value set in [C01215/3](#) should not be set higher than the drift of the actual position at standstill of the drive plus a possible safety option. Otherwise, the position controller carries out an intermittent compensation after the controller inhibit is deactivated due to the pending system deviation!

Application example

In case of a continuous relative positioning by 100 units and a setting of the controller inhibit after each positioning process (e.g. by means of the [Holding brake control](#) in the "automatically controlled" mode), it is expected that after 10 positioning processes, an absolute target of 10 x 100 units = 1000 units has been reached.

Without setting a limit value ([C01215/3](#) = 0), the continuous setting of the setpoint position to the actual position in case of controller inhibit causes a drifting of the setpoint position due to the drifting of the actual position at standstill. After ten positioning processes, only e.g. 999.5 units have been reached instead of 1000 units. If, however, the setpoint position is not set to the actual position ([C01215/3](#) <> 0) in case of controller inhibit, the setpoint position is exactly in the target after 10 positioning processes and 9 x controller inhibits (in case of 10 x relative traverse paths).

9.4.7 Setpoint holdback for bus runtime compensation

This function extension is available from version 12.00.00!

Basics of the "setpoint holdback" function

In case of a master/slave application in which a slave drive must follow a master drive with a precise angle, the data coupling from axis to axis is mostly effected via real-time capable fieldbuses (e.g. CAN).

- Here, the data is always transferred in a time-controlled way. The axes are synchronised, i.e. the reading of the process data and its internal processing are effected at the same time.
- For such applications, the 8400 TopLine controller provides the [Axis bus](#) which is very easy to configure.

During a synchronous run between a master and several slaves, mostly a position and speed setpoint generated by the master are transferred to the slaves.

- The setpoints are generated in the master, usually by the [LS_MotionControlKernel](#) system block.
- The setpoints are transferred to the slaves via PDOs.
- The output to the respective fieldbus is effected via the corresponding port blocks (e.g. [LP_CanOut1](#) or [LP_MciOut](#)) or in case of the axis bus via the [LS_AxisBusOut](#) system block.

Due to the bus cycle time (e.g. 1 ms or 2 ... 4 ms for buses with a higher load) and the telegram runtimes (approx. 260 µs per PDO @500 kbits), the setpoints generated by the master arrive in the slave axes with a delay. At this time, the master has already transferred the setpoints to the control loops of the motor control. This offset causes an error in the synchronism of the axes.

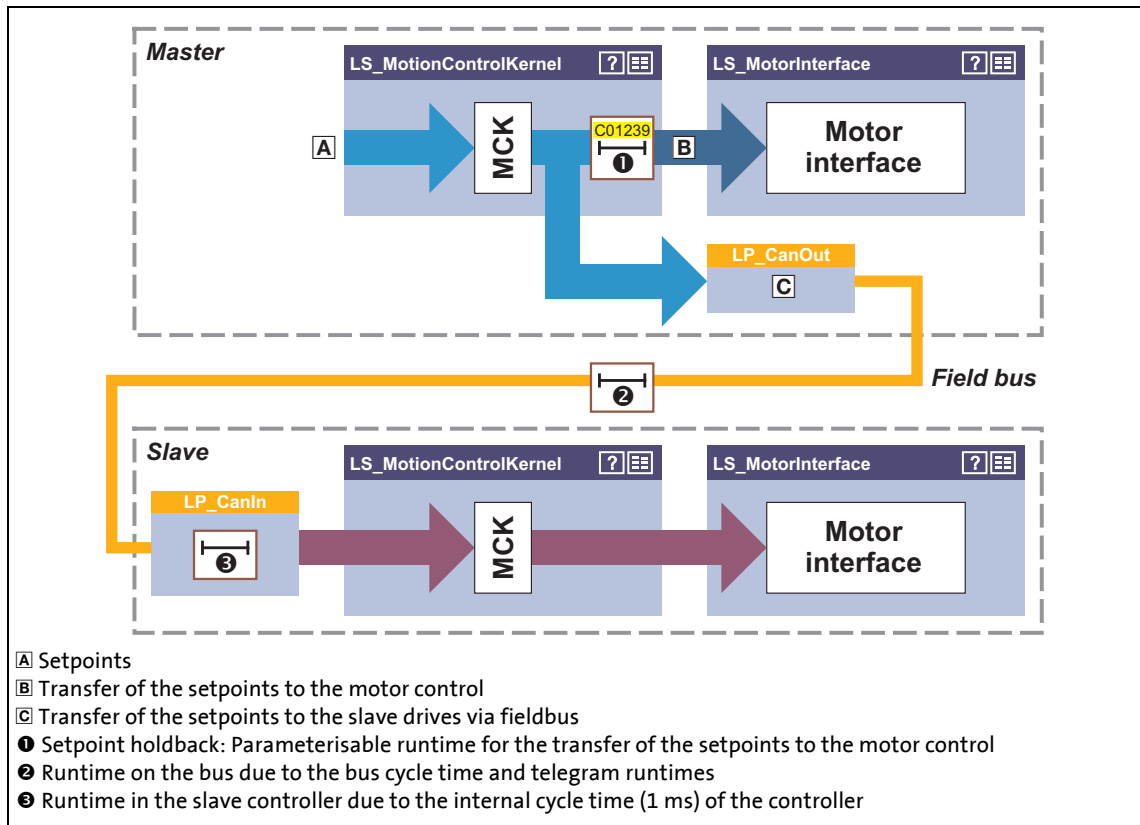
- In case of a mechanical coupling, e.g. a portal feed with two drives, an inclination of the two feed drives is caused.
- This behaviour is more or less distinctive for all serial bus systems depending on the transmission speed and cycle time.

A further delay between the reading of the received data and the forwarding to the control loops is caused by the internal cycle time of the controllers (1 ms for the 8400 device series).

Parameterising the "setpoint holdback" function

For compensating the runtimes described before, a setpoint holdback can be parameterised in [C01239](#). The function directly affects the setpoint forwarding from the **Motion Control Kernel** to the motor control.

- Internally, the setpoints are transmitted with a delay by the time set in [C01239](#) from the [LS_MotionControlKernel](#) system block to the motor control.
- Setting rule: [C01239](#) = bus cycle time + 1 ms
- The Lenze setting "0 ms" corresponds to the previous behaviour (no setpoint holdback).



[9-20] Principle of the setpoint holdback (here only in the master for "setpoint line" topology)



Note!

In which drives the function is to be parameterised, depends on the bus topology:

- Setpoint line (1 master, many slaves):
Only in the master, the setpoint holdback ([C01239](#)) has to be set.
- Setpoint cascade (setpoints from one to drive to the other):
In all drives, the setpoint holdback ([C01239](#)) has to be set.

As the setpoint holdback is implemented in the **Motion Control Kernel**, the [LS_MotionControlKernel](#) system block is required for this function independent of the setpoint source.

Behaviour when the "setpoint holdback" function is parameterised online

The setpoint holdback can also be set "online", i.e. without inhibiting the controller before. This provides for an adjustment during commissioning while the setpoint generation is running, similar to the setting of the gain of the speed or position controller.



Stop!

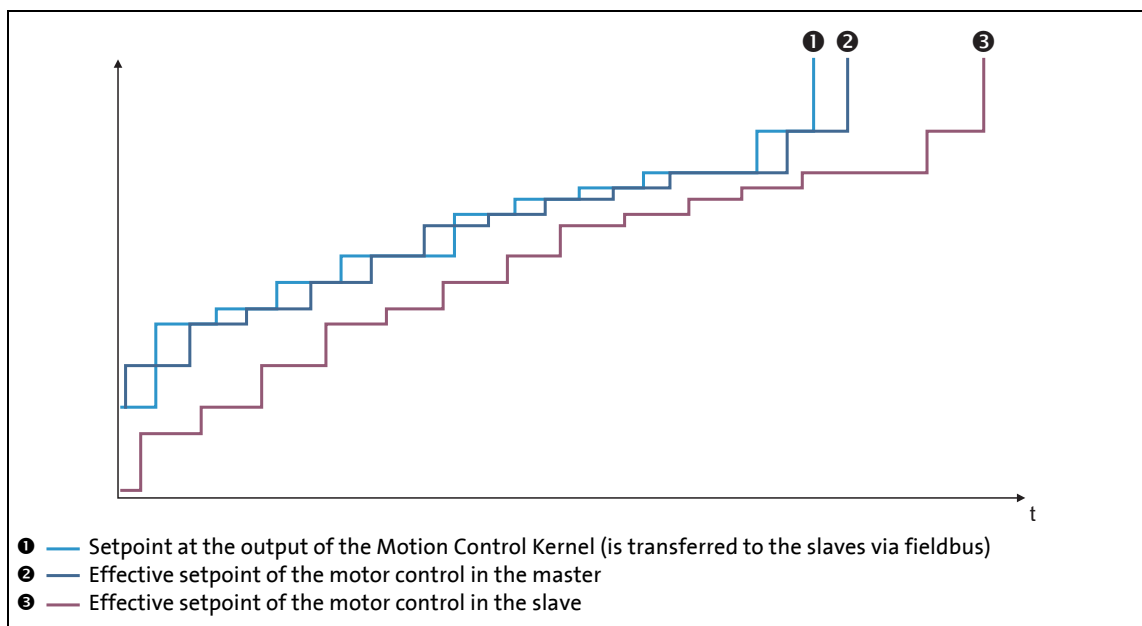
The setting while the setpoint generation is running causes a system-dependent time change of the setpoint processing so that e.g. considerable step-changes or setpoint holding processes occur.

In order to prevent setpoint step-changes which have a negative effect on the mechanics:

- Always change the setting of the setpoint holdback in 1-ms steps only.
- Make the online parameterisation at low speeds only.

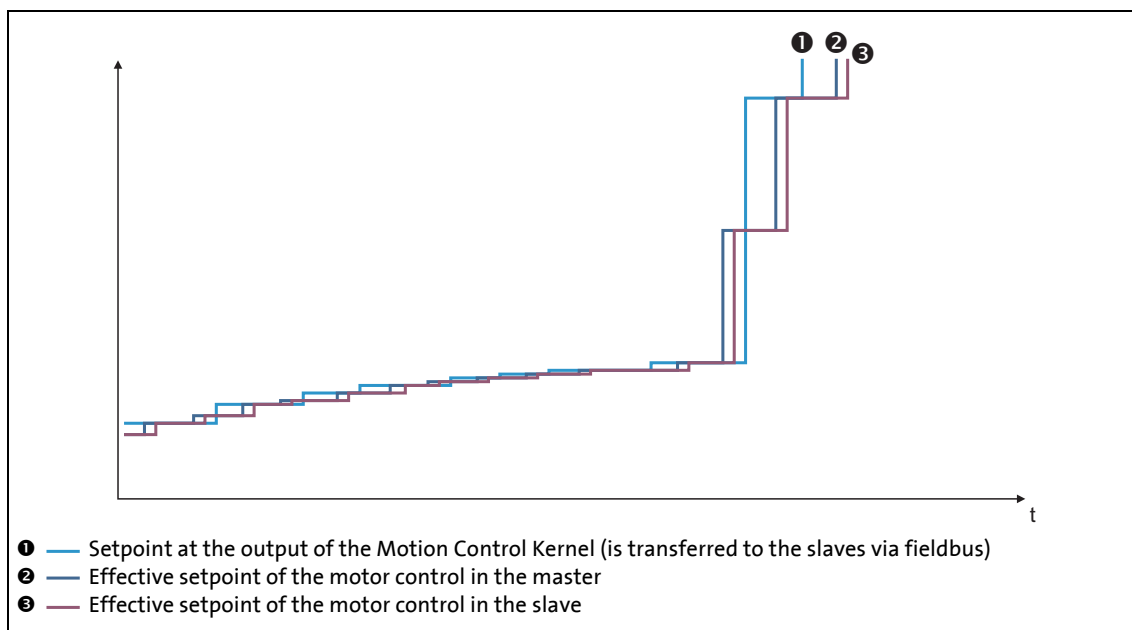
Example: Runtime behaviour without and with setpoint holdback

Example 1 shows the behaviour without setpoint holdback. Due to the runtimes, there is an offset between master and slave of 2 ms.



[9-21] Example 1: Runtime behaviour without setpoint holdback

In example 2, the setpoint holdback in the master is set to 2 ms. This removes the offset between master and slave. Only time differences are visible due to the telegram runtimes on the bus.



[9-22] Example 2: Runtime behaviour with setpoint holdback = 2 ms

9.4.8 Setting or activation of maximum jerk for traversing profiles

This function extension is available from version 14.00.00!

Basics of the "maximum jerk" function

A change over of a traversing profile within an acceleration or deceleration ramp to a sequence profile which has a lower jerk than the traversing profile from the calculation of the new acceleration and S-ramp time causes an increase of the speed which may be not wanted for process technology reasons. The reason is that the new jerk reduces the acceleration in a too long time period which generates a too high speed.

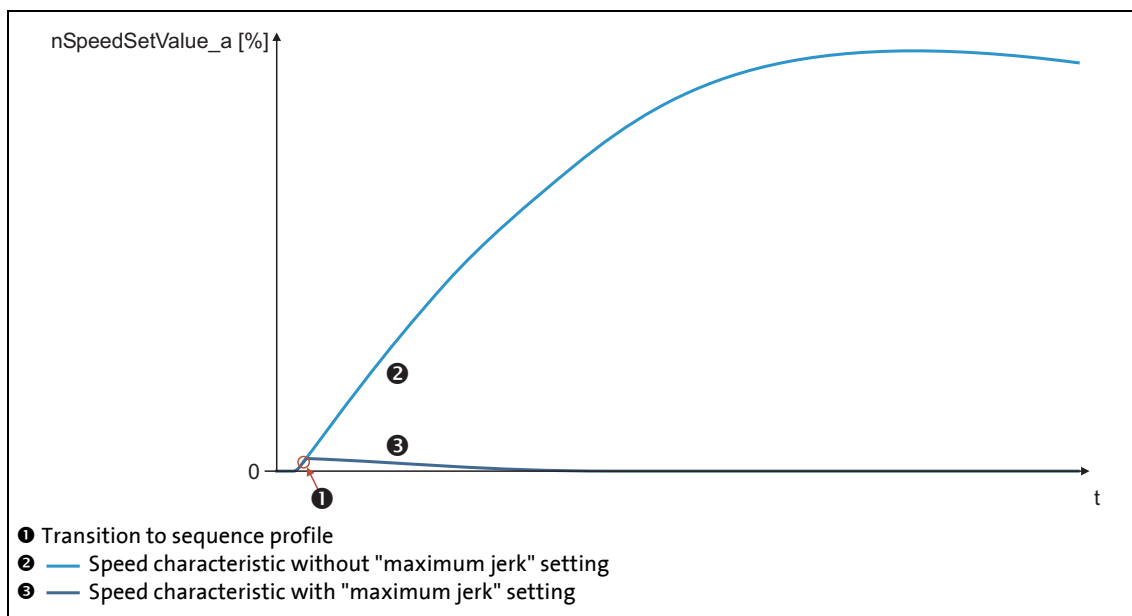
As a remedy, the "maximum jerk" function can be activated which integrates the currently pending acceleration into the acceleration of the new traversing profile or to zero.

Parameterising the "maximum jerk" function

The "maximum jerk" function can be individually activated for the operating modes "[Positioning](#)", "[Homing](#)" and "[Manual jog](#)" via the following setting parameters:

Parameter	Info	Lenze setting
C01216 - bit 5	Maximum jerk for positioning on/off	Off
C01220/1 - bit 5	Maximum jerk for homing on/off	Off
C01230 - bit 5	Maximum jerk for manual jog on/off	Off

When the function is activated, the maximum jerk is calculated from the higher value of both acceleration values and the lower value of both S-ramp time values based on the acceleration and S-ramp time of the current and sequence profile. This maximum jerk is then used for an accelerated drive in order to reduce the acceleration to 0 or to the acceleration of the sequence profile.



[9-23] Example: Behaviour during transition to sequence profile with accelerated drive

If the sequence profile is started with a non-accelerated drive, the parameters of the sequence profile are continued to be used for the jerk calculation without maximum comparison to the current profile.

9.5 Speed follower

In the "speed follower" operating mode, the drive follows a speed setpoint.

9.5.1 Parameter setting

Short overview of parameters for the "speed follower" operating mode:

Parameter	Info	Lenze setting	
		Value	Unit
C01219	MCK: Speed follower setting	Bit coded	
C02610/2	MCK: Ramp time synchr. setpoint	2.000	s
C02611/1	MCK: Pos. max. speed	199.99	%
C02611/2	MCK: Pos. min. speed	0.00	%
C02611/3	MCK: Neg. min. speed	0.00	%
C02611/4	MCK: Neg. max. speed	199.99	%

9.5.1.1 Functional settings

In [C01219](#), various functional settings for the speed follower can be made in bit-coded form.

Function		Lenze setting
Bit 0	Reserved	Off
Bit 1	Reserved	Off
Bit 2	HW limit switch on In the "speed follower" operating mode, a travel range monitoring mode via hardware limit switch is active. ▶ Limit position monitoring (□ 590)	On
Bit 3	SW limit switch on In the "speed follower" operating mode, a travel range monitoring mode via parameterised software limit positions. ▶ Limit position monitoring (□ 590)	On
Bit 4	Reserved	Off
Bit 5	Reserved	Off
Bit 6	Reserved	Off
Bit 7	Position controller off In the "Speed follower" operating mode, the position controller is deactivated. Thus, the compensation of the following error is switched off.	Off

9.5.2 Requesting the operating mode

Request for "speed follower" operating mode by means of the [MCK control word](#):

MCK control word						
Bit 31	...	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
			OpMode_Bit3	OpMode_Bit2	OpMode_Bit1	OpMode_Bit0
X	...	X	0	0	0	0

X = Status not significant

If the **MCKInterface** is connected upstream to the **Motion Control Kernel** and if the operating mode is requested at the [L_MckCtrlInterface](#) FB, the *wOperationMode* and *bOperationMode_1...8* process inputs are available.

9.5.3 Setpoint selection

The speed setpoint is selected via the *nSpeedSetValue_a* process input and additively via the *nSpeedAddValue_v* process input.

- Usually, the ramp generator [L_NSet](#) and, optionally, the process controller [L_PCTRL](#) are upstream of the *nSpeedSetValue_a* process input.
- The speed setpoint is limited internally to the speed limits set in [C02611/1...4](#).



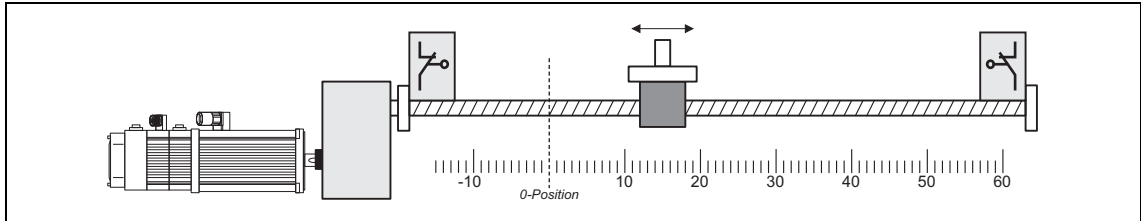
Note!

When the speed limit values are set, the **Motion Control Kernel** influences the setpoint generation with a synchronisation mode. The synchronisation mode serves to travel the synchronisation range dynamically with the synchronisation ramp set in [C02610/2](#).

► [Min/Max speed](#) (□ 589)

9.6 Homing

The measuring system in the machine is selected by means of homing and the 0 position is set within the possible physical travel range:



[9-24] Homing (selection of 0 position)

The zero position (home) can be defined by a reference run or by setting a home position:

- If a reference run is carried out, the drive follows a previously selected path to find the home position.
- When the reference is set, it is selected manually when the drive stands still.



Danger!

During homing operations, specially assigned profile parameters are effective. If these parameters are not set correctly, the drive may execute unexpected movements!



Tip!

A reference run is mainly used for systems with feedback via encoders, resolvers, or single-turn absolute value encoders, as in the case of these systems the home position is lost when the supply voltage is switched off.

Usually the reference is set only once during commissioning or in the event of service (e. g. if drive components are replaced), and it is mostly used for systems with feedback via absolute value encoders.

9.6.1 Parameter setting

Parameterisation dialog in the »Engineer«

Application Parameters

Overview -> Basic Functions -> Homing

Ref. TP signal source: [C] No TP

Setting up TouchProbe ...

Homing mode: [C] >_Lp

Homing Mode

Ref. home position: [C] 0,0000 unit

Ref. reference offset: [C] 0,0000 unit

Ref. sequence profile: [C] 0

System of measurement sett.: [C] 0x0

bHomeStartStop

bHomeSetPosition

bHomeResetPosition

Actual MCTRL position

Homing active

Homing done

Home position available

Dist. Ref-Mark to Ref-TP: [C] 0,0000 units

Actual position: [C] 0,0000 units

1 Sensor mark (TP, MP) - home position in machine measuring system

2 Reference target position

Ref. S-ramp time: [C] 0,000 s

Ref. start speed: [C] 720,0000 unit/s

Ref. search speed: [C] 180,0000 unit/s

Ref. M-Limit mode 14/15: [C] 10,00 %

Ref. start acceleration: [C] 720,0000 unit/s²

Ref. search acceleration: [C] 720,0000 unit/s²

Ref. waiting time mode 14/15: [C] 100 ms

Positive SW limit position: [C] 0,0000 units

Negative SW limit position: [C] 0,0000 units

Short overview of parameters for "Referencing" operating mode:

Parameter	Info	Lenze setting	
		Value	Unit
C01220/1	MCK: Ref. setting (from version 14.00.00)	Bit coded	
C01221	MCK: Homing mode	12: >_Lp	
C01224/1	MCK: Ref. initial speed	720.0000	unit/s
C01225/1	MCK: Ref. initial acceleration	720.0000	unit/s ²
C01224/2	MCK: Ref. search speed	180.0000	unit/s
C01225/2	MCK: Ref. search acceleration	720.0000	unit/s ²
C01226/1	MCK: Ref. S-ramp time	0.000	s
C01222	MCK: Ref. M limit mode 14/15	10.00	%
C01223	MCK: Ref. waiting time mode 14/15	100	ms
C01227/1	MCK: Ref. offset reference degree	0.0000	unit
C01227/2	MCK: Ref. home position	0.0000	unit
C01228	MCK: Ref. sequence profile	0	
C01229/1	MCK: Positive SW limit position	0.0000	units
C01229/2	MCK: Negative SW limit position	0.0000	units
C01246/1	MCK: Ref. TP signal source	0: No TP	
C01246/2	MCK: Set.Ref. signal source	0: No TP	

9.6.1.1 Functional settings

From version 14.00.00, various functional settings for homing can be carried out bit-coded in [C01220/1](#).

Function		Lenze setting
Bit 0	Reserved	Off
Bit 1	Reserved	Off
Bit 2	Reserved	Off
Bit 3	Reserved	Off
Bit 4	Start deletes bHomePosAvailable When homing is started (mode 4 ... 15), the reference information is deleted.	Off
Bit 5	Maximum jerk ▶ Setting or activation of maximum jerk for traversing profiles (603)	Off
Bit 6	Reserved	Off
...		
Bit 15		

9.6.1.2 Homing mode

Specify the referencing mode in [C01221](#), i.e. the way in which referencing is to take place.

- For reference setting, the referencing mode "100" is to be selected in [C01221](#).
- For a reference search, [C01221](#) contains referencing modes "4" ... "15" which can be selected from.

Referencing mode C01221	Evaluated signals/sensors			
	Touch probe sensor (Sensor reference signal)	Travel range limit switch		Pre-stop mark at <i>bHomingMark</i>
		Negative limit switch	Positive limit switch	
4 *	<input checked="" type="checkbox"/>			<input checked="" type="checkbox"/>
5 *	<input checked="" type="checkbox"/>			<input checked="" type="checkbox"/>
6	<input checked="" type="checkbox"/>			<input checked="" type="checkbox"/>
7	<input checked="" type="checkbox"/>			<input checked="" type="checkbox"/>
8	<input checked="" type="checkbox"/>			
9	<input checked="" type="checkbox"/>			
10	<input checked="" type="checkbox"/>		<input checked="" type="checkbox"/>	
11	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>		
12			<input checked="" type="checkbox"/>	
13		<input checked="" type="checkbox"/>		
14	Positive direction of rotation to torque limit.			
15	Negative direction of rotation to torque limit.			
100	Set reference directly.			

* From version 14.00.00

Internal interfaces

The switches/sensors are evaluated via the following internal interfaces:

Switch/sensor	Internal interface for digital input signal
Touch probe sensor (Sensor reference signal)	<p>The touch probe signal source can be selected in C01246/1.</p> <ul style="list-style-type: none"> • If the reference signal is to follow a real touch probe, configure the touch probe signal accordingly. ▶ Touch probe detection (411) <p>Note: In case of setting "0: No TP" in C01246/1, the digital input DI3 is used as signal source. An inversion of DI3 via C00114 is considered.</p>
Positive travel range limit switch	<i>bLimitSwitchPos</i>
Negative travel range limit switch	<i>bLimitSwitchNeg</i>
Pre-stop mark/pre-stop signal	<p><i>bHomingMark</i></p> <ul style="list-style-type: none"> • This input has to be connected to the corresponding digital input to which the pre-switch off sensor is connected. • The edge sensitivity of this input and the response to the pre-switch off signal depend on the selected homing mode (see the following description of the homing modes).

**Note!**

For a reference search with touch probe detection:

- The touch probe signal source can be selected in [C01246/1](#).
- Go to [C02810/x](#) and select the edge, the digital input used for the connection of the touch-probe sensor is to respond. In the Lenze setting of [C02810/x](#), no touch probe is detected!
- Moreover, no "acceptance window" must be set in [C2813/x](#) and [C02814/x](#) for accepting the touch probe signal in order that a touch probe will always be detected independent of the position.

► [Touch probe detection](#) (📖 411)

Start and search profile data set

Certain referencing modes use two different profile data sets for homing in order to shorten the homing time and, at the same time, increase accuracy.

- At first, a quick approach of the limit switch/pre-stop mark (depending on the selected mode) is carried out using the start profile data set.
- After reversing at the limit switch/pre-stop mark, the search profile data set results in slower – but more accurate – approaching of the touch probe sensor.

Start profile data set		Search profile data set	
C01224/1	Start speed	C01224/2	Search speed
C01225/1	Start acceleration (deceleration as well)	C01225/2	Search acceleration (deceleration as well)
C01226/1	S-ramp time (identical in the two profile data sets)	C01226/1	S-ramp time (identical in the two profile data sets)

**Note!**

A changeover to the search profile data set is only carried out if the search speed has been set to ([C01224/2](#)) > "0"!

The exact time of the changeover to search profile data set occurs in the respective homing mode is indicated in the process descriptions of the homing modes.

**Tip!**

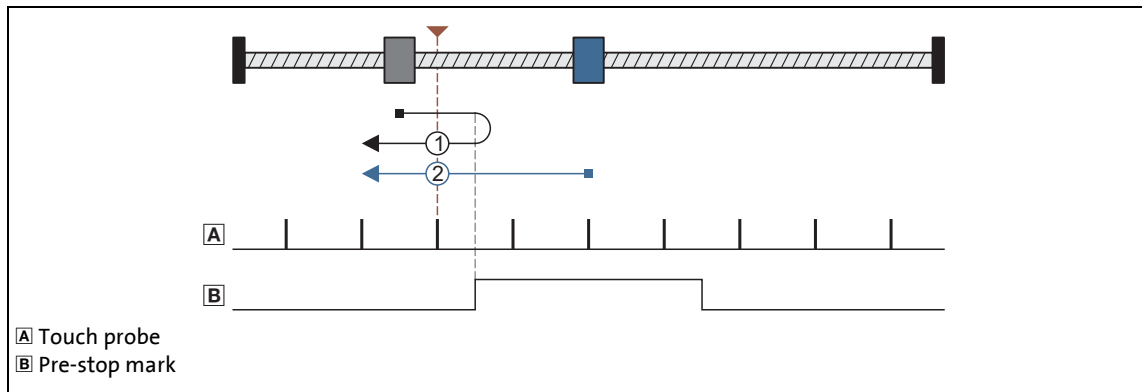
The result of setting a lower search speed in [C01224/2](#) and a high search acceleration in [C01225/2](#) is that deceleration to search speed takes place quickly and position detection is exact (at slower search speed).

Abbreviations used for the referencing modes:

Abbreviation	Meaning
>	Movement in positive direction
<	Movement in negative direction
Lp	Positive travel range limit switch
Ln	Negative travel range limit switch
Rp	Positive edge pre-stop mark/pre-stop signal
Rn	Negative edge - pre-stop mark/pre-stop signal
TP	Touch probe or sensor reference signal/reference switch detected
Mlim	Torque limit value reached

Mode 4: >_Rp_<_TP

(from version 14.00.00)



Mode 4	>	Rp	<	TP	Offset path	Sequence profile (optional)
	Start speed		Search speed		Profile speed	
Lp	Active	Active	Active	Active	Active	Active
Ln	Inactive	Active	Active	Active	Active	Active

Process of case 1 → Axis has not yet reached the pre-stop mark (*bHomingMark* = FALSE):

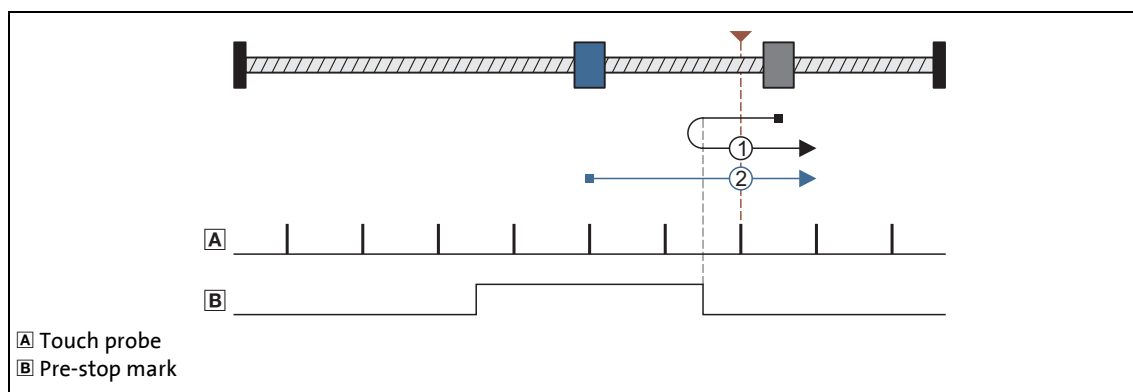
1. Movement in positive direction with start profile data set.
2. Reversing in case of positive edge at *bHomingMark* and, at the same time, activating the search profile data set for continued reference searching.
3. Negative edge at *bHomingMark* enables home position detection.
4. Following edge of the touch probe sensor sets home position.

Process of case 2 → Axis is already on the pre-stop mark (*bHomingMark* = TRUE):

1. Movement in negative direction with search profile data set.
2. Negative edge at *bHomingMark* enables home position detection.
3. Following edge of the touch probe sensor sets home position.

Mode 5: <_Rp_>_TP

(from version 14.00.00)



Mode 5	<	Rp	>	TP	Offset path	Sequence profile (optional)
	Start speed		Search speed		Profile speed	
Lp	Inactive	Active	Active	Active	Active	Active
Ln	Active	Active	Active	Active	Active	Active

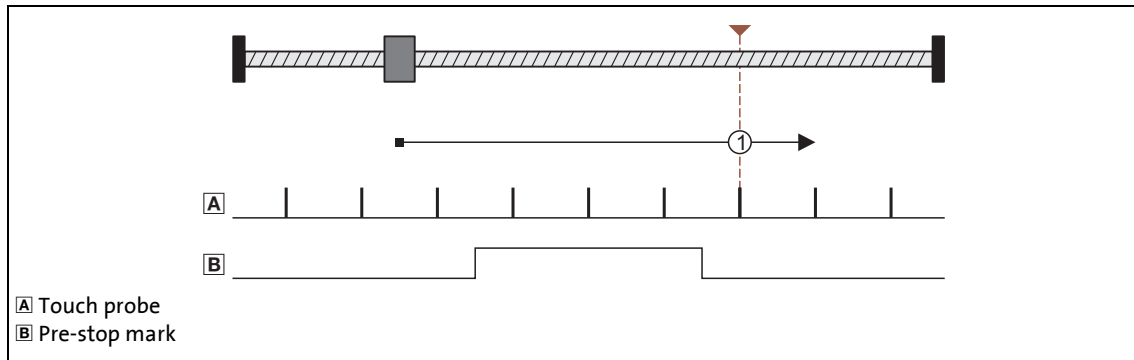
Process of case 1 → Axis has not yet reached the pre-stop mark (*bHomingMark* = FALSE):

1. Movement in negative direction with start profile data set.
2. Reversing in case of positive edge at *bHomingMark* and, at the same time, activating the search profile data set for continued reference searching.
3. Negative edge at *bHomingMark* enables home position detection.
4. Following edge of the touch probe sensor sets home position.

Process of case 2 → Axis is already on the pre-stop mark (*bHomingMark* = TRUE):

1. Movement in positive direction with search profile data set.
2. Negative edge at *bHomingMark* enables home position detection.
3. Following edge of the touch probe sensor sets home position.

Mode 6: >_Rn_>_TP

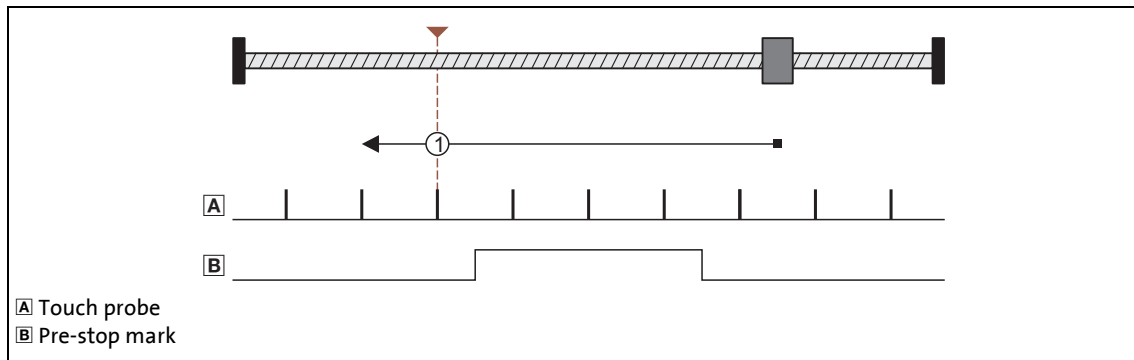


Mode 6	>	Rn	>	TP	Offset path	Sequence profile (optional)
	Start speed		Search speed		Profile speed	
Lp	Active	Active	Active	Active	Active	Active
Ln	Inactive	Inactive	Inactive	Inactive	Active	Active

Procedure:

1. Movement in positive direction with start profile data set.
2. Positive edge at *bHomingMark* activates search profile data set for further reference search.
3. Negative edge at *bHomingMark* enables home position detection.
4. Following edge of the touch probe sensor sets home position.

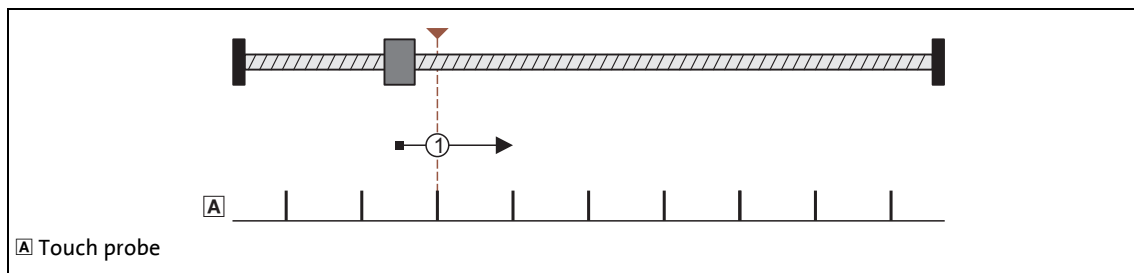
Mode 7: <_Rn_<_TP



Mode 7	<	Rn	<	TP	Offset path	Sequence profile (optional)
	Start speed		Search speed		Profile speed	
Lp	Inactive	Inactive	Inactive	Inactive	Active	Active
Ln	Active	Active	Active	Active	Active	Active

Procedure:

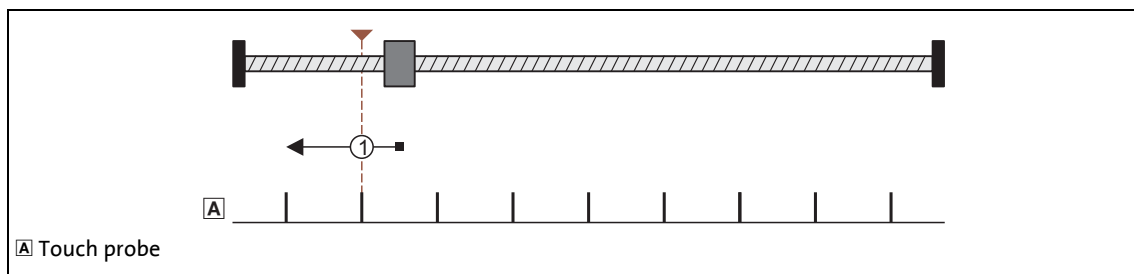
1. Movement in negative direction with start profile data set.
2. Positive edge at *bHomingMark* activates search profile data set for further reference search.
3. Negative edge at *bHomingMark* enables home position detection.
4. Following edge of the touch probe sensor sets home position.

Mode 8: >_TP

Mode 8	>	TP	Offset path	Sequence profile (optional)
	Start speed			Profile speed
Lp	Active	Active	Active	Active
Ln	Inactive	Inactive	Active	Active

Procedure:

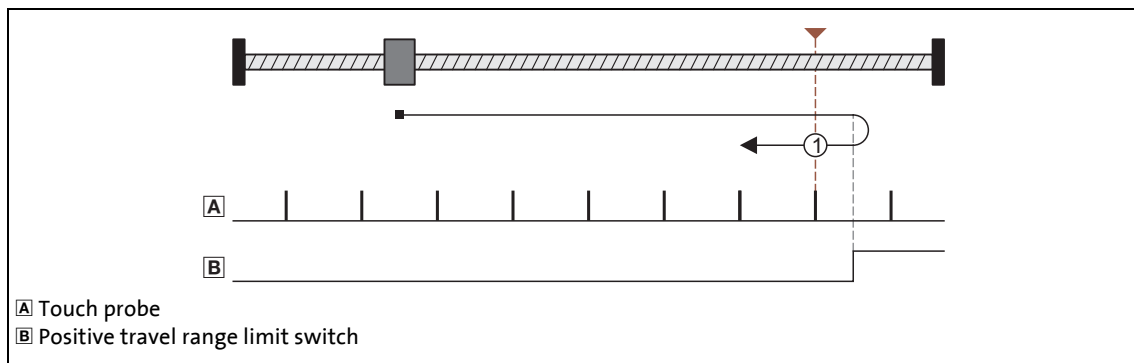
1. Movement in positive direction with start profile data set.
2. Following edge of the touch probe sensor sets home position.

Mode 9: <_TP

Mode 9	<	TP	Offset path	Sequence profile (optional)
	Start speed			Profile speed
Lp	Inactive	Inactive	Active	Active
Ln	Active	Active	Active	Active

Procedure:

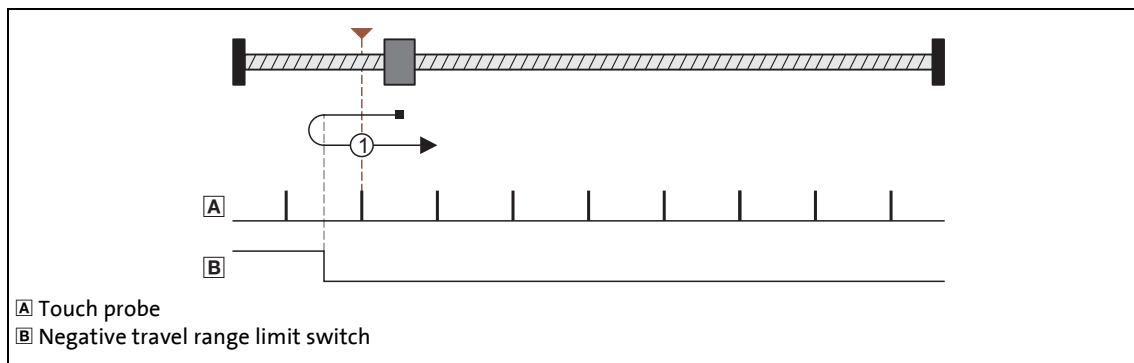
1. Movement in negative direction with start profile data set.
2. Following edge of the touch probe sensor sets home position.

Mode 10: >_Lp_<_TP

Mode 10	>	Lp	<	TP	Offset path	Sequence profile (optional)
	Start speed		Search speed			Profile speed
Lp	Inactive	Inactive	Inactive	Inactive	Inactive	Active
Ln	Inactive	Inactive	Active	Active	Active	Active

Procedure:

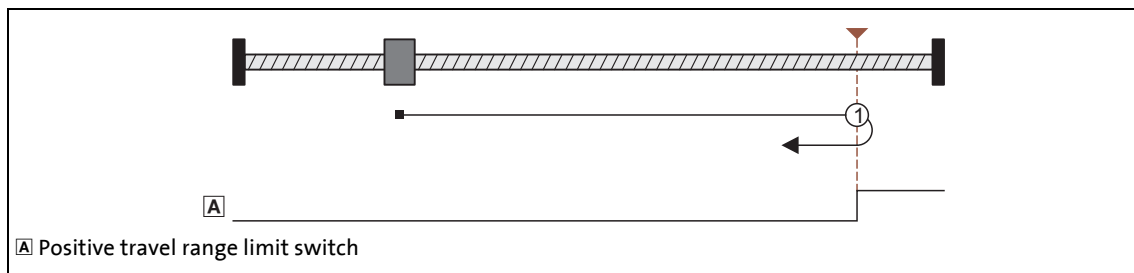
1. Movement in positive direction with start profile data set.
2. Reversing when the edge of the positive travel range limit switch is positive and, at the same time, activation of search profile data set for continued reference searching.
3. Negative edge of the travel range limit switch enables home position detection.
4. Following edge of the touch probe sensor sets home position.

Mode 11: <_Ln_>_TP

Mode 11	<	Ln	>	TP	Offset path	Sequence profile (optional)
	Start speed		Search speed			Profile speed
Lp	Inactive	Inactive	Active	Active	Active	Active
Ln	Inactive	Inactive	Inactive	Inactive	Inactive	Active

Procedure:

1. Movement in negative direction with start profile data set.
2. Reversing when the edge of the negative travel range limit switch is positive and, at the same time, activation of search profile data set for continued reference searching.
3. Negative edge of the travel range limit switch enables home position detection.
4. Following edge of the touch probe sensor sets home position.

Mode 12: >_Lp

Mode 12	>	Lp	Offset path	Sequence profile (optional)
	Start speed			Profile speed
Lp	Inactive	Inactive	Inactive	Active
Ln	Inactive	Inactive	Active	Active

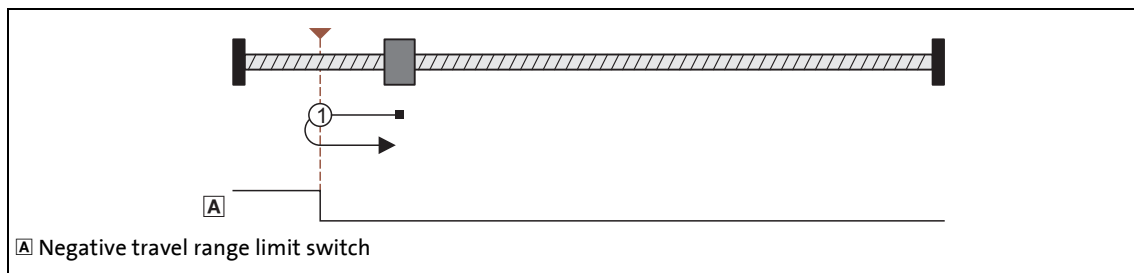
Procedure:

1. Movement in positive direction with start profile data set.
2. Positive edge of the travel range limit switch sets reference.

**Note!**

The load machine can also leave the travel range limit switch. There follows a return to the home position that was set with the positive edge of the travel range limit switch.

- It is possible that, as a result, the machine will remain on an operated limit switch.
- It is therefore recommended that a home value offset be set in [C01227/1](#) in order to release the operated limit switch.

Mode 13: <_Ln

Mode 13	<	Ln	Offset path	Sequence profile (optional)
	Start speed			Profile speed
Lp	Inactive	Inactive	Active	Active
Ln	Inactive	Inactive	Inactive	Active

Procedure:

1. Movement in negative direction with start profile data set.
2. Positive edge of the travel range limit switch sets reference.

**Note!**

The load machine can also leave the travel range limit switch. There follows a return to the home position that was set with the positive edge of the travel range limit switch.

- It is possible that, as a result, the machine will remain on an operated limit switch.
- It is therefore recommended that a home value offset be set in [C01227/1](#) in order to release the operated limit switch.

Mode 14: >_Mlim



Mode 14	>	Mlim	Offset path	Sequence profile (optional)
	Start speed			Profile speed
Lp	Active	Active	Active	Active
Ln	Inactive	Inactive	Active	Active

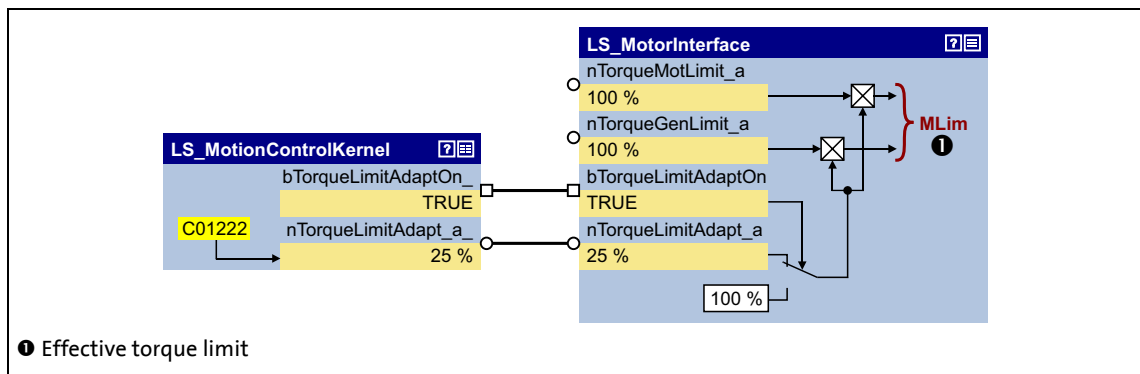
Procedure:

1. Movement in a positive direction with reduced torque and start profile data set.
2. The reference is set if it is detected that the torque limit set in [C01222](#) is exceeded beyond the time set in [C01223](#) ("Homing to positive stop").
 - If a home value offset has not been set, this position is the home position.
 - If a home value offset has been set, correctly signed traversing by this offset takes place and the home position is set at the end of this travel distance.

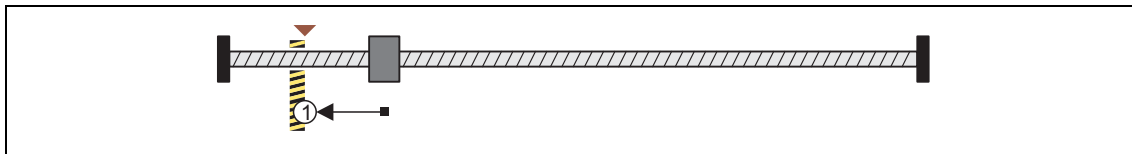


Tip!

Set a home value offset in [C01227/1](#) to avoid stopping at the positive stop.



[9-25] Wiring for torque limit when homing to "Positive stop" (homing modes 14/15)

Mode 15: <_Mlim

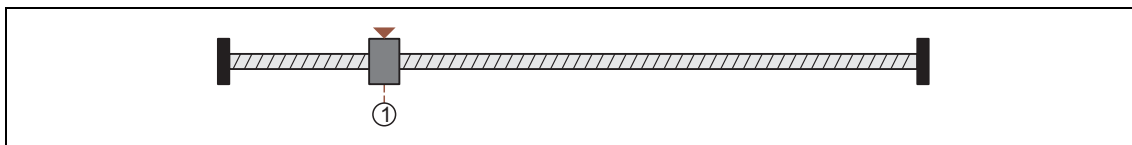
Mode 15	<	Mlim	Offset path	Sequence profile (optional)
	Start speed			Profile speed
Lp	Inactive	Inactive	Active	Active
Ln	Active	Active	Active	Active

Procedure:

1. Movement in a negative direction with reduced torque and start profile data set.
2. The reference is set if it is detected that the torque limit set in [C01222](#) is exceeded beyond the time set in [C01223](#) ("Homing to positive stop").
 - If a home value offset has not been set, this position is the home position.
 - If a home value offset has been set, correctly signed traversing by this offset takes place and the home position is set at the end of this travel distance.

**Tip!**

Set a home value offset in [C01227/1](#) to avoid stopping at the positive stop.

Mode 100: SetRef

Mode 100	SetRef	Offset path	Sequence profile (optional)
	-	Start speed	Profile speed
Lp	Active	Active	Active
Ln	Active	Active	Active

When the drive is at standstill, the measuring system is set via the bit 9 ("HomSetPos") in [MCK control word](#). The current actual position now corresponds to the home position set in [C01227/2](#) in the machine measuring system.

9.6.1.3 Home position & home value offset

If the home position is set in the course of the reference search, this determined position in the machine measuring system now corresponds to the home position set in [C01227/2](#).

If a home value offset has been set in [C01227/1](#), the drive continues correctly signed traversing by this offset at search speed after the home position has been found. The home position is not set until after this movement.

9.6.1.4 Traversing a sequence profile after completion of homing

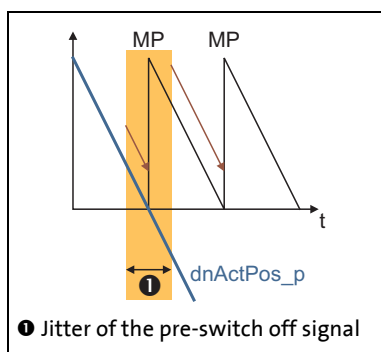
If necessary, a sequence (following or subsequent) profile can be entered in [C01228](#) in order to arrange for a positioning movement to be carried out immediately after completion of homing.



Note!

The positioning movement for the sequence profile set in [C01228](#) is also carried out in the "referencing" mode. If a second sequence (following or subsequent) profile has been defined in the sequence profile, it is not automatically started!

9.6.1.5 Measurement of the distance between pre-stop mark/limit switch and TP/MP



Depending on how close the pre-stop mark is located to the encoder zero pulse and even jittering around it, it might occur that the drive performs one more or one less revolution after the home position detection has been enabled.

From version 14.00.00, the display parameter [C01210/9](#) is available for this purpose. This parameter shows the distance between the signal which starts the home position detection and the detected touch probe signal or encoder zero pulse (MP) in [units].

The measurement is executed for the homing modes 4, 5, 6, 7, 10 and 11.

Referencing mode	Display in C01210/9 in [units]
4 / 5	$dnActPos_P_{(TP/MP)} - dnActPos_P_{(bHomingMark_TRUE_to_FALSE)}$
6 / 7	$dnActPos_P_{(TP/MP)} - dnActPos_P_{(bHomingMark_TRUE_to_FALSE)}$
10	$dnActPos_P_{(TP/MP)} - dnActPos_P_{(bLimitSwitchPos_TRUE_to_FALSE)}$
11	$dnActPos_P_{(TP/MP)} - dnActPos_P_{(bLimitSwitchNeg_TRUE_to_FALSE)}$

9.6.1.6 Option "Actual MCTRL position received at mains switch-off"

The encoder position can be saved with mains failure protection in the controller. For this purpose, the bit 0 has to be set in [C02652](#).

- From version 14.00.00, the "Actual MCTRL position received at mains switch-off" option can also be accessed in the »Engineer« via the parameterisation dialog for the basic function **Homing** (depending on the set position encoder system).
- If bit 0 is set in [C02652](#), the actual position of the motor control is saved in the controller (not in the memory module) and thus remains known to the drive control after mains switching.

The following overview shows the actual position after mains connection depending on the setting [C02652](#)/bit 0, [C00490](#), [C00422](#), [C00925](#) (if resolver is selected) and the existence of the reference information:

C02652 bit 0	Reference available in case of mains switch-off (Status bit "HomePos Available")	Actual position and status reference in case of mains switch-on with setting		
		C00490 = 4 C00925 = 1 • Resolver with number of pole pairs = 1	C00490 = 0, 3, 4, 10 C00422 = 0, 1 C00925 > 1 (with resolver) • Incremental encoder (TTL) • Sin/cos encoder (Singleturn) • Resolver with number of pole pairs > 1 • No sensor	C00490 = 3 C00422 = 2, 3, 4 • Absolute value encoder (Multiturn)
0	0	0 incr.	0 incr.	$dnActPos_{(mains\ switch-off)} \pm \vartheta$
		Reference is unknown	Reference is unknown	Reference is unknown
	1	0 incr.	0 incr.	$dnActPos_{(mains\ switch-off)} \pm \vartheta$
		Reference is unknown	Reference is unknown	Reference available
1	0	$dnActPos_{(mains\ switch-off)} \pm \vartheta$	$dnActPos_{(mains\ switch-off)}$	$dnActPos_{(mains\ switch-off)} \pm \vartheta$
		Reference is unknown	Reference is unknown	Reference is unknown
	1	$dnActPos_{(mains\ switch-off)} \pm \vartheta$	$dnActPos_{(mains\ switch-off)}$	$dnActPos_{(mains\ switch-off)} \pm \vartheta$
		Reference available	Reference available	Reference available

$\pm \vartheta \equiv$ A rotation within the max. possible angle of rotation is possible at mains switch-off.

9.6.2 Requesting the operating mode

Request for the "referencing" operating mode by means of the [MCK control word](#):

MCK control word						
Bit 31	...	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
			OpMode_Bit3	OpMode_Bit2	OpMode_Bit1	OpMode_Bit0
X	...	X	0	0	0	1

X = Status not significant

If the **MCKInterface** is connected upstream to the **Motion Control Kernel** and if the operating mode is requested at the [L_MckCtrlInterface](#) FB, the *wOperationMode* and *bOperationMode_1...8* process inputs are available.

9.6.3 Execute homing

Control is exercised by means of bits 8 ... 10 in the [MCK control word](#):

Homing	MCK control word		
	Bit 10	Bit 9	Bit 8
	HomResetPos	HomSetPos	HomStartStop
Stop homing	0	0	0
Start homing	0	0	1
Set home position	0	1	X
Delete home position	1	0	X
X = Status not significant			

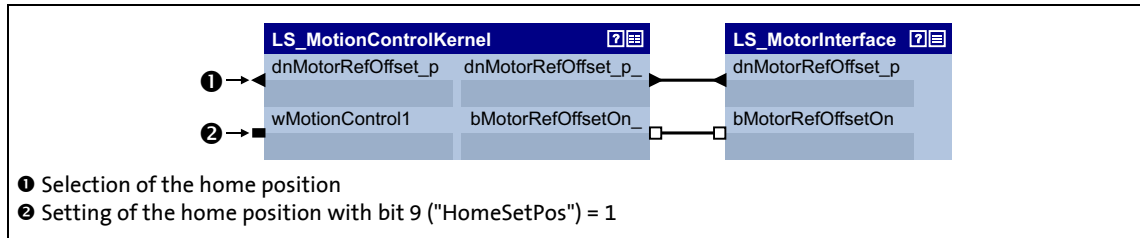
If the **Motion Control Kernel** is downstream from the **MCKInterface** in the circuit, the [L_MckCtrlInterface](#) FB provides the following process inputs for controlling the operating mode:

Identifier	Data type	Information/possible settings				
bHomingStartStop	BOOL	Start/stop homing <ul style="list-style-type: none">Only possible in the "referencing" operating mode.				
		<table><tr><td>TRUE</td><td>If one of homing modes "4" ... "15" in C01221 is selected: Start reference search<ul style="list-style-type: none">The current status of the reference search is indicated via the status outputs <i>bHomingDone</i> and <i>bHomePosAvailable</i>.If the 100_Set_Ref_directly" referencing mode has been selected in C01221, the home position can be set manually via the <i>bHomeStartStop</i> input with the drive at a standstill. The current actual position is set as the home position (C01227/2)</td></tr><tr><td colspan="2">If homing mode "100: SetRef" is selected: Setting the home position manually<ul style="list-style-type: none">The home position is set manually with the drive at a standstill. The current actual position now corresponds to the reference position set in C01227/2 in the machine measuring system.</td></tr></table>	TRUE	If one of homing modes "4" ... "15" in C01221 is selected: Start reference search <ul style="list-style-type: none">The current status of the reference search is indicated via the status outputs <i>bHomingDone</i> and <i>bHomePosAvailable</i>.If the 100_Set_Ref_directly" referencing mode has been selected in C01221, the home position can be set manually via the <i>bHomeStartStop</i> input with the drive at a standstill. The current actual position is set as the home position (C01227/2)	If homing mode "100: SetRef" is selected: Setting the home position manually <ul style="list-style-type: none">The home position is set manually with the drive at a standstill. The current actual position now corresponds to the reference position set in C01227/2 in the machine measuring system.	
		TRUE	If one of homing modes "4" ... "15" in C01221 is selected: Start reference search <ul style="list-style-type: none">The current status of the reference search is indicated via the status outputs <i>bHomingDone</i> and <i>bHomePosAvailable</i>.If the 100_Set_Ref_directly" referencing mode has been selected in C01221, the home position can be set manually via the <i>bHomeStartStop</i> input with the drive at a standstill. The current actual position is set as the home position (C01227/2)			
If homing mode "100: SetRef" is selected: Setting the home position manually <ul style="list-style-type: none">The home position is set manually with the drive at a standstill. The current actual position now corresponds to the reference position set in C01227/2 in the machine measuring system.						
TRUE↗FALSE	Stop homing. <ul style="list-style-type: none">If the <i>bHomingStartStop</i> input is reset to FALSE during active referencing, homing is cancelled and the drive is brought to a standstill.					
bHomingSetPos	BOOL	Set home position (Homing on the fly) <ul style="list-style-type: none">With referencing "on the fly", the home position of a machine can be set during ongoing movement. Jerking and compensating movements do not occur.				
		<table><tr><td>FALSE↗TRUE</td><td>The position applied at the <i>dnMotorRefOffset_p</i> input of the SB LS_MotionControlKernel at the time of activation is set as home position if C01246/2 = "0: No TP" is set.</td></tr></table>	FALSE↗TRUE	The position applied at the <i>dnMotorRefOffset_p</i> input of the SB LS_MotionControlKernel at the time of activation is set as home position if C01246/2 = "0: No TP" is set.		
FALSE↗TRUE	The position applied at the <i>dnMotorRefOffset_p</i> input of the SB LS_MotionControlKernel at the time of activation is set as home position if C01246/2 = "0: No TP" is set.					
bHomingResetPos	BOOL	Delete home position Note: With this function, positions are not deleted but only the status signals <i>bHomePosAvailable</i> and <i>bHomePosDone</i> are reset. Setpoints and actual positions remain untouched until a renewed reference setting or homing.				
		<table><tr><td>FALSE↗TRUE</td><td>The internal status "reference known" is reset.<ul style="list-style-type: none">The controller is no longer referenced.The process outputs <i>bHomePosAvailable</i> and <i>bHomingDone</i> are reset to FALSE.</td></tr></table>	FALSE↗TRUE	The internal status "reference known" is reset. <ul style="list-style-type: none">The controller is no longer referenced.The process outputs <i>bHomePosAvailable</i> and <i>bHomingDone</i> are reset to FALSE.		
FALSE↗TRUE	The internal status "reference known" is reset. <ul style="list-style-type: none">The controller is no longer referenced.The process outputs <i>bHomePosAvailable</i> and <i>bHomingDone</i> are reset to FALSE.					

9.6.3.1 Homing on the fly

With referencing "on the fly", the home position of a machine can be set during ongoing movement. Jerking and compensating movements do not occur.

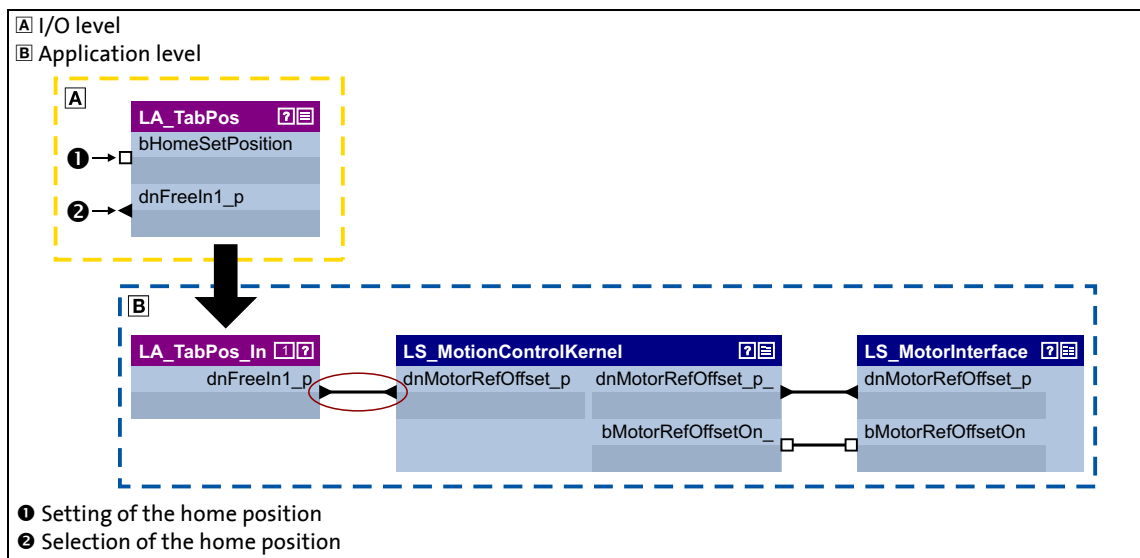
The following illustration shows the relevant interfaces for selecting the home position at the SB [LS_MotionControlKernel](#) and SB [LS_MotorInterface](#):



[9-26] Interface for selecting the home position

In order that position selections can be accepted while homing on the fly, an additional connection is required in the application level.

- The following illustration shows the required modification using the example of the "table positioning" technology application.
- For transmitting the home position from the I/O level to the application level, the "free" input **dnFreeIn1_p** is used here:



[9-27] Modified interconnection for selecting the home position

9.7

Manual jog

In this operating mode, the drive can be traversed manually in a clockwise or anticlockwise direction ("jogging mode").

- As an option, it is possible to change over to a second speed during traversing.
- "Retraction" of operated (travel range) limit switches is also supported. Only traversing in the corresponding retracting direction is then possible.

**Danger!**

During manual jog, specially assigned profile parameters are effective. If these parameters are not set correctly, the drive may execute unexpected movements!

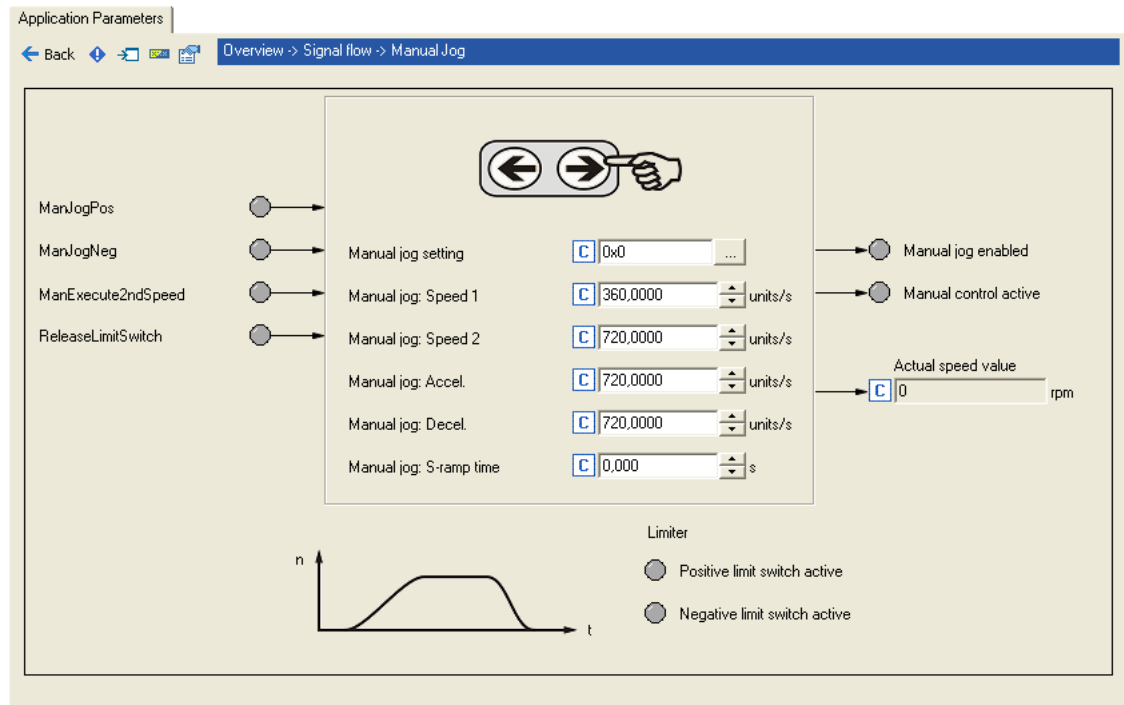
**Stop!**

In the Lenze setting, travel range monitoring is switched-off in [C01230](#) by means of hardware limit switches and software limit positions for the "Manual jog" operating mode!

If travel range monitoring has been deactivated, the drive can travel into a mechanical limit during manual jogging and machine parts can be destroyed or damaged!

9.7.1 Parameter setting

Parameterisation dialog in the »Engineer«



Short overview of parameters for "manual jogging" mode":

Parameter	Info	Lenze setting	
		Value	Unit
C01230	MCK: Manual jog setting	Bit coded	
C01231/1	Manual jog: speed 1	360.0000	units/s
C01231/2	Manual jog: Speed 2	720.0000	units/s
C01232/1	Manual jog: Acceleration	720.0000	units/s ²
C01232/2	Manual jog: Deceleration	720.0000	units/s ²
C01233/1	Manual jog: S-ramp time	0.000	s
C01235/1	Waiting time - 2nd speed	5.000	s
C01234/1	Manual jog: Breakpoint 1	0.0000	unit
C01234/2	Manual jog: Breakpoint 2	0.0000	unit
C01234/3	Manual jog: Breakpoint 3	0.0000	unit
C01234/4	Manual jog: Breakpoint 4	0.0000	unit



Note!

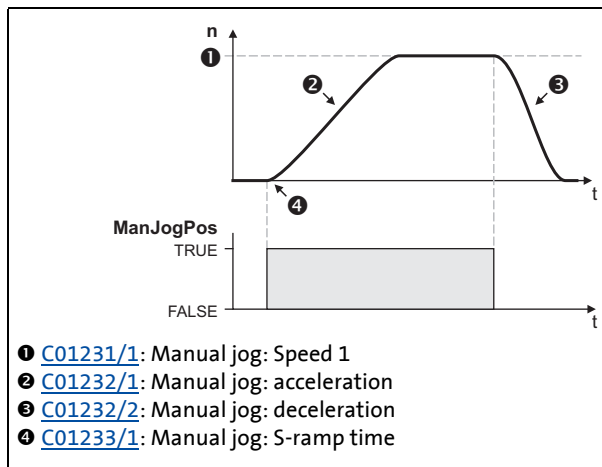
For trouble-free operation, the [Machine parameters](#) (at least gearbox factor and feed constant) must also be set correctly!

9.7.1.1 Functional settings

In [C01230](#), various functional settings for manual jogging can be carried out in bit-coded form.

Function		Lenze setting
Bit 0	Manual jog with breakpoint During manual jog, a stop is automatically made at the breakpoint positions set in C01234/1...4 . <ul style="list-style-type: none"> • The home position must be known for this function. • Travelling is continued when the pushbutton is "released" and pressed again. This button has been assigned the <i>ManJogPos</i> and/or <i>ManJogNeg</i> control function. 	Off
Bit 1	Time-based start of second speed In manual jog mode, an automatic changeover to manual speed 2 takes place after a parameterisable waiting time. ▶ Time-based start of second speed (□ 629)	Off
Bit 2	HW limit switch on In the "manual jog" operating mode, a travel range monitoring mode via hardware limit switch is active. ▶ Limit position monitoring (□ 590)	Off
Bit 3	SW limit switch on In the "manual jog" operating mode, a travel range monitoring mode via parameterised software limit positions. ▶ Limit position monitoring (□ 590)	Off
Bit 4	Reserved	Off
Bit 5	Maximum jerk ▶ Setting or activation of maximum jerk for traversing profiles (□ 603)	Off
Bit 6	Reserved	Off
Bit 7	Position controller off In the "manual jog" operating mode, the position controller is deactivated. Thus, the compensation of the following error is switched off.	Off

9.7.1.2 Smooth start and quick stop of the drive



[9-28] Example: Smooth start and quick stop

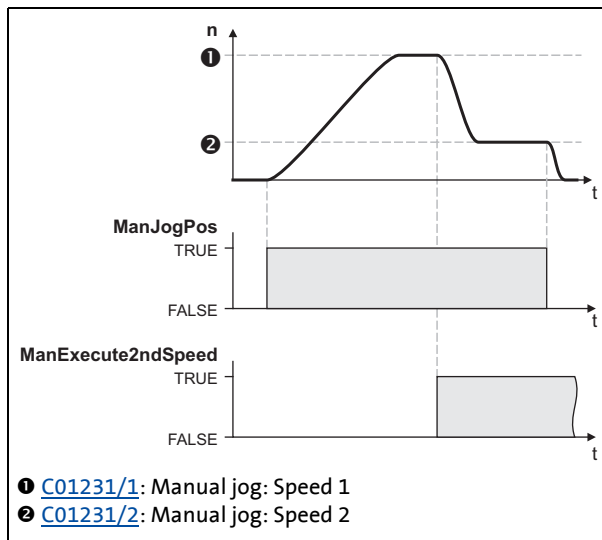


Tip!

Rapid deceleration ([C01232/2](#)) reduces the time from releasing of the "jog button" to actual stopping of the drive, with the result that it is easier to position the drive "by sight" and the desired stop position is not passed.

- For accelerating and decelerating, different values can be set in [C01232/1...2](#) so that smooth starting and quick stopping of the drive can be implemented.
- In order to reduce jerking, the two ramps can be set in such a way that they are s-shaped. This is done by entering a relative S-ramp time in [C01233/1](#).

9.7.1.3 Second speed



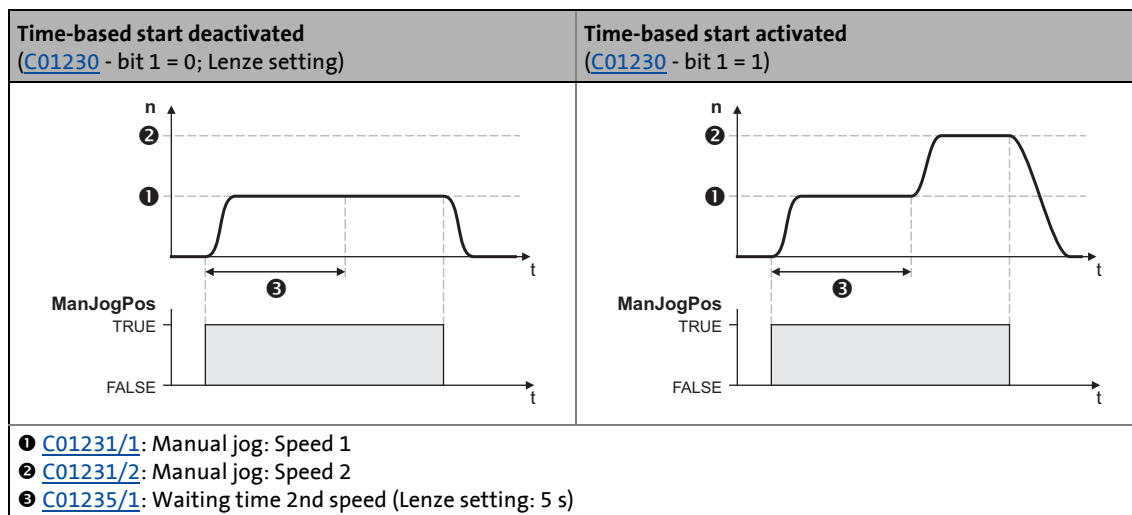
[9-29] Example: Change-over to second speed

- By setting control bit 6 (*ManExecute2ndSpeed*) in the [MCK control word](#), you can changeover to a second speed ([C01231/2](#)) during traversing.

9.7.1.4 Time-based start of second speed

If this function has been activated by means of bit 1 in [C01230](#) and a waiting time > "0 s" has been set in [C01235/1](#), an automatic change-over to manual jog speed 2 takes place when the manual jog function is activated and after the waiting time has expired.

- When the waiting time is set = 0 s, the automatic change-over is deactivated.



[9-30] Time-based start of second speed



Tip!

By leaving the corresponding button for manual jog pressed down for longer than the waiting time and parameterising manual jog speed 2 so that it is higher than manual jog speed 1, you can enable longer distances to be travelled by means of manual jogging with this function.

9.7.2 Requesting the operating mode

Request for "manual jog" mode via the [MCK control word](#):

MCK control word						
Bit 31	...	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
			OpMode_Bit3	OpMode_Bit2	OpMode_Bit1	OpMode_Bit0
X	...	X	0	0	1	0
X = Status not significant						

If the **MCKInterface** is connected upstream to the **Motion Control Kernel** and if the operating mode is requested at the [L_MckCtrlInterface](#) FB, the *wOperationMode* and *bOperationMode_1...8* process inputs are available.

9.7.3 Executing manual jogging

Control is exercised by means of bits 4 ... 7 in the [MCK control word](#):

Manual jog	MCK control word			
	Bit 7	Bit 6	Bit 5	Bit 4
	Release LimitSwitch	ManExecute 2ndSpeed	ManJogNeg	ManJogPos
Stop manual jogging	0	X	0	0
Manual jog, right • With speed 1 (C01231/1)		0	0	1
Manual jog, right • With speed 2 (C01231/2)		1		
Manual jog, left • With speed 1 (C01231/1)		0	1	0
Manual jog, left • With speed 2 (C01231/2)		1		
No change in relation to previous state		X	1	1
Retract operated limit switch	1	0	0	0
X = Status not significant				

If the **Motion Control Kernel** is downstream from the **MCKInterface** in the circuit, the [L_MckCtrlInterface](#) FB provides the following process inputs for controlling the operating mode:

Identifier	Data type	Information/possible settings
bManJogPos bManJogNeg	BOOL	bManJogPos = TRUE: Manual jog right bManJogNeg = TRUE: Manual jog left Both inputs = TRUE: No change compared to previous state Both inputs = FALSE: Stop manual jog
bManJogExecute2ndVel	BOOL	Change over to speed 2 for manual jog
		FALSE Speed 1 (C01231/1) active.
		TRUE Speed 2 (C01231/2) active.
bReleaseLimitSwitch	BOOL	Retract operated limit switch
		TRUE Retract operated limit switch (in opposite direction)

Case 1: Reference known

If the reference is known and the software limit positions have been set, i.e. at least one software limit position is > 0 , manual jogging is carried out until a position at the corresponding software limit position is reached unless manual jogging is aborted first. Overtravelling the set software limit positions is not possible.

Case 2: Reference not known

If the reference is not known, the travel range limits are only monitored via the limit switches (if connected).

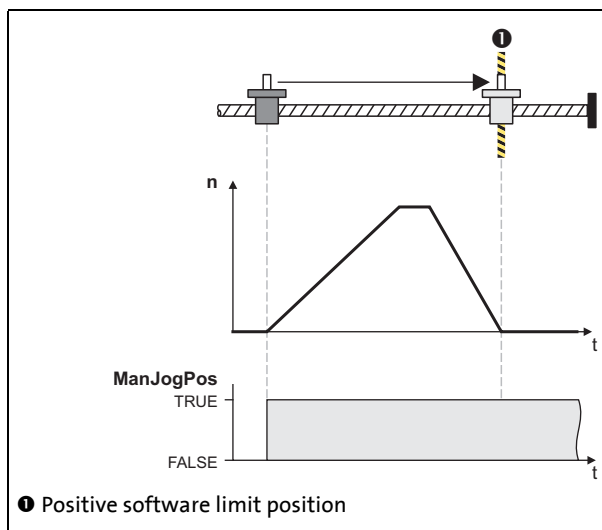
If you end manual jogging manually by resetting *bManJogNeg* or *bManJogPos*, the drive is brought to a standstill at the rate of deceleration set for manual jogging.

9.7.3.1 Manual jog to limit position**Stop!**

In the Lenze setting, travel range monitoring is switched-off in [C01230](#) by means of hardware limit switches and software limit positions for the "Manual jog" operating mode!

If travel range monitoring has been deactivated, the drive can travel into a mechanical limit during manual jogging and machine parts can be destroyed or damaged!

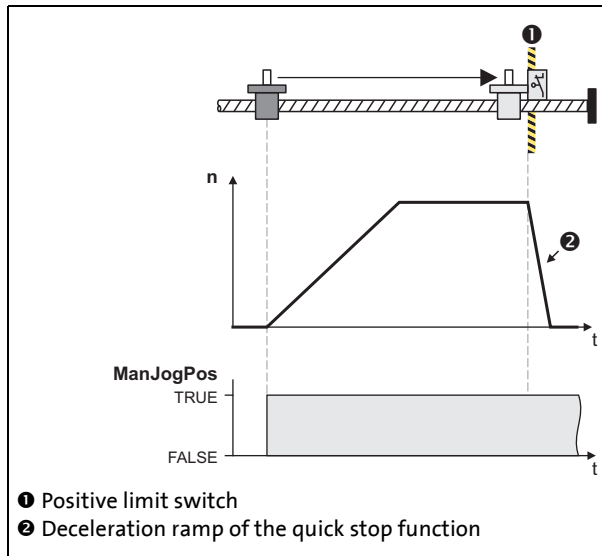
► [Limit position monitoring](#) (▢ 590)

Manual jog to software limit position

[9-31] Example: Manual jog to positive software limit position

- If the reference is known and the software limit positions have been set and are active, positioning to the corresponding software limit position is carried out unless you manually stop manual jogging first by resetting control bit 4/5 (*ManJogPos/ManJogNeg*) in the [MCK control word](#).
- The drive decelerates at the set rate of deceleration ([C01232/2](#)) to the position of the corresponding software limit position.

Manual jog to hardware limit position (limit switch)



[9-32] Example: Manual jog to positive limit switch

- When monitoring of the limit switches is switched on and a limit switch is approached during manual jog, the drive is braked within the deceleration time set for the quick stop function if the "TroubleQuickStop" error response is set in [C00595/1](#) or [C00595/2](#).

9.7.3.2 Retracting of an operated limit switch

If control bit 7 (*ReleaseLimitSwitch*) in the [MCK control word](#) is set, retracting from an operated limit switch is possible. Traversing is carried out in the corresponding retracting direction until the limit switch is no longer operated.

- If a direction preselection is made for retracting by means of control bit 4/5 (*ManJogPos/ManJogNeg*) in the retracting direction, travelling is continued, even after the limit switch has been left, until the corresponding control bit is reset.
- If, instead, a direction preselection is made against the retracting direction, the drive remains at a standstill.



Note!

Retracting from a limit switch is only possible if this switch is still in the operated state, i.e. the corresponding limit switch input is still active. You must therefore make sure that, when travelling to a limit switch, its tripping mechanism is not "driven over" due to e.g. an excessively high mass or too much momentum so that the limit switch is no longer in the operated state as a result.

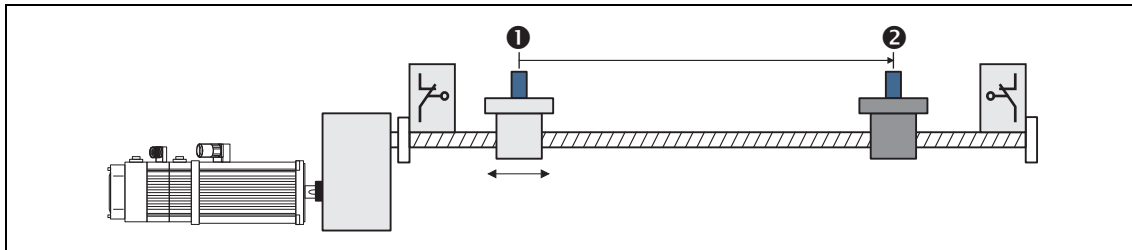


Tip!

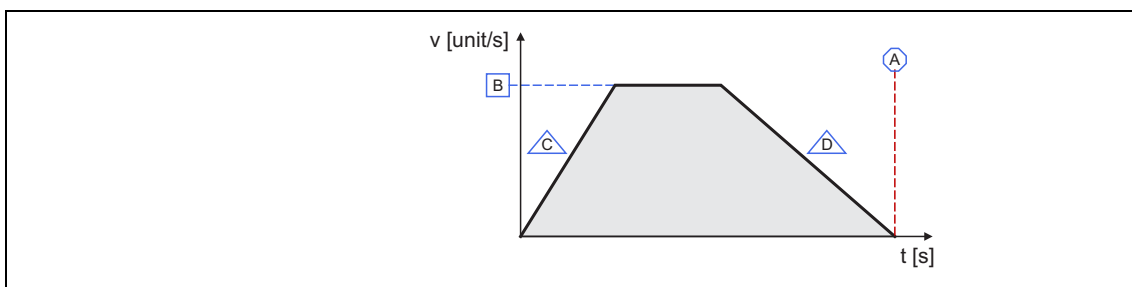
A limit switch that is in the operated state can also be moved away from again through manual jogging in the retracting direction by means of control bits 4/5 (*ManJogPos/ManJogNeg*).

9.8 Positioning

Positioning means that a workpiece/tool or material is moved from a starting position ❶ to a defined destination ❷:



To carry out positioning, a travel profile has to be stored in the drive controller for at least the following profile parameter:

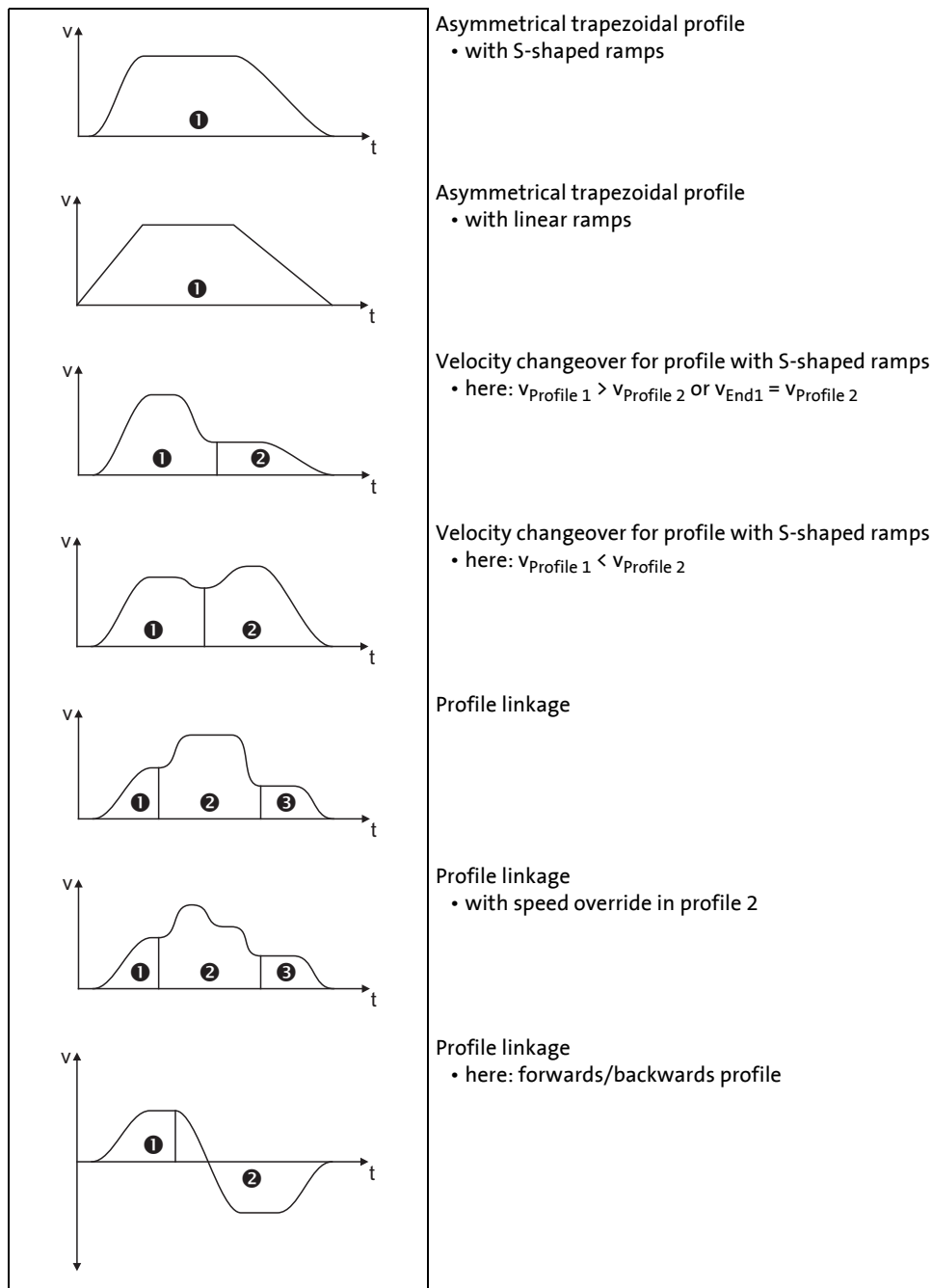


Icon	Profile parameter
❶	Position Target position or distance to be traversed.
❷	Velocity Maximum speed during the positioning process.
❸	Acceleration Maximum acceleration during the positioning process.
❹	Delay Maximum deceleration during the positioning process.

- A profile describes a motion task that can be converted into a rotary motion of the motor shaft by the **Motion Control Kernel** in the "Positioning" operating mode.
- A positioning process can be composed of a large number of profiles that are executed in a fixed manner.
- 15 different profiles can be parameterised for the 8400 TopLine controller.
- You can find a detailed explanation of all profile parameters in the subchapter entitled "[Profile entry](#)". (📖 637)

9.8.1 Possible motion profiles

The following illustration shows different movement profiles that can be travelled in the "positioning" mode:



[9-33] Examples of possible motion profiles

9.8.2 Parameter setting

Short overview of parameters for "positioning" mode:

Parameter	Info	Lenze setting	
		Value	Unit
C01216	MCK: Positioning setting	Bit coded	
C01300/1...15	Profile 1 ... 15: Mode	1: absolute (beeline)	
C01301/1...15	Profiles 1 ... 15: Position	360.0000	unit
C01302/1...15	Profile 1 ... 15: Speed	360.0000	unit/s
C01303/1...15	Profile 1 ... 15: Accel.	720.0000	unit/s ²
C01304/1...15	Profile 1 ... 15: Decel.	720.0000	unit/s ²
C01305/1...15	Profile 1 ... 15: Final speed	0.0000	unit/s
C01306/1...15	Profiles 1 ... 15: S-ramp time	0.000	s
C01307/1...15	Profiles 1 ... 15: Sequence profile	0	
C01308/1...15	Profile 1 ... 15: TP profile	0	
C01309/1...15	Profile 1 ... 15: TP signal source	3: TP-DigIn3	
C00595/9	MCK: Resp. to invalid PosModus	4: WarningLocked	
C00595/10	MCK: Resp. to invalid profile data	4: WarningLocked	
C00595/12	MCK: Resp. to invalid profile no.	4: WarningLocked	
C00595/14	MCK: React target out of travel range	4: WarningLocked	
C01210/1	MCK: Curr. feed	-	units
C01210/2	MCK: Curr. set position	-	units
C01210/3	MCK: Curr. actual position	-	units
C01210/4	MCK: Curr. following error	-	units
C01210/5	MCK: Positioning accuracy	-	units
C01210/6	MCK: Target position	-	units
C01211/1	Max. traversing speed 100%_C11	-	units/s
C01213/1	MCK: Max. traversing distance	-	units
C01242	MCK: Current pos profile number	-	
Highlighted in grey = display parameter			



Note!

For trouble-free operation, the [Machine parameters](#) (at least gearbox factor and feed constant) must also be set correctly!

9.8.2.1 Functional settings

In [C01216](#), various functional settings regarding behaviour in the case of a changeover to the "positioning" mode can be made in bit-coded form.

- When this is being done, any mode change must be taken into account.
- Positioning with controller inhibit/enable is also possible if the corresponding setting is made.

Function		Lenze setting
Bit 0	PosAbort at PosInit When a changeover to "positioning" mode is made, ramping down at the rate of deceleration set in C01251 for normal stopping is carried out.	On
Bit 1	PosExecute active at PosInit When a changeover is made to the "positioning" mode, the specified profile is immediately executed if the "MCK PosExecute" control bit has also been set. If the MCK "PosExecute" control bit has not been set, the setpoint is continued.	Off
Bit 2	Reserved	Off
Bit 3	Reserved	Off
Bit 4	ProfilStart at PosInit When it is changed to the "Positioning" operating mode, the defined profile is executed immediately without the need to set the MCK control bit "PosExecute". Note: If the FB L_MckCtrlInterface writes to the MCK control word due to the setting in C01297 , a profile start may be prevented. Remedy: Set bit 0 in C01297 to "0". ▶ Alternative functions for control bit "PosExecute" (657)	Off
Bit 5	Maximum jerk ▶ Setting or activation of maximum jerk for traversing profiles (603)	Off
Bit 6	Reserved	Off
Bit 7	Reserved	Off



Note!

In the case of multiple selection, the "PosAbort at PosInit" function, which can be activated by means of bit 0, has priority over the other functions (see the following truth table).

Bit 4 ProfilStart	Bit 1 PosExecute active	Bit 0 PosAbort	MCK control bit "PosExecute"	Behaviour when it is changed to "Positioning" operating mode	
X	X	1	X		Ramping down the setpoint
0	0	0	X		Continuing the setpoint
0	1	0	0		
0	1	0	1		Positioning from the setpoint
1	X	0	x*		

printed in bold = Lenze setting; x = any state; * see note on bit 4 in table above

Related topics:

- ▶ [Stipulation of the profile to be executed](#) (644)
- ▶ [Starting/cancelling a traversing task](#) (645)

9.8.2.2 Profile entry

In the »Engineer«, the following parameterisation dialog is available for setting the profile parameters:

Application Parameters

Overview -> Profile input

Profile number: 01

Profile 1: Mode: Absolute (shortest path)

Profile 1: Position: 360,0000 Unit

Profile 1: Speed: 360,0000 Unit/s

Profile 1: Accel.: 720,0000 Unit/s²

Profile 1: Decel.: 720,0000 Unit/s²

Profile 1: S-ramp time: 0,000 s

Profile 1: Final speed: 0,0000 Unit/s

Profile 1: Sequence profile: 0

Profile 1: TP-profile: 0


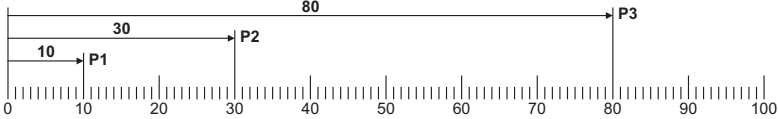
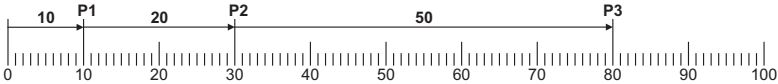

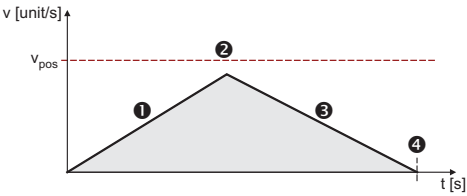

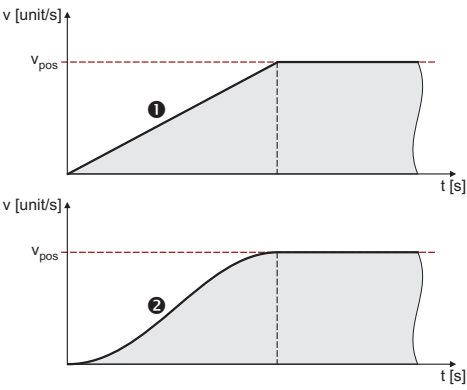

Profile 1: TP-source: TP-DigIn3


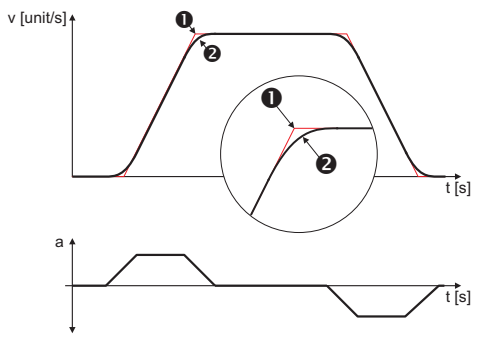

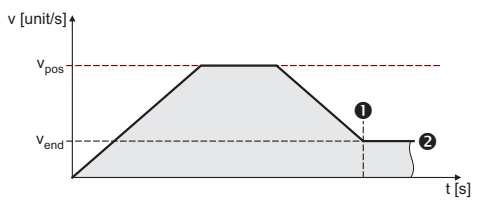


The TP window is only supported by digital inputs DI3, DI4 and DI5.

Setting up TouchProbe ...

A profile is described by the following profile parameters:

Icon	Profile parameter
	(Standard) profile Profile data set (profile numbers 1 ... 15), in which the profile data are stored.
	Mode (C01300/1...15) Selection of the way in which positioning is to be carried out. ▶ Positioning modes (640)

Icon	Profile parameter
	<p>Position (C01301/1...15) Target position or distance to be traversed. When the position is indicated, a distinction is made between absolute position and relative position:</p> <ul style="list-style-type: none"> An absolute position always indicates the distance to the defined zero position: Absolute position = Target position  <ul style="list-style-type: none"> A relative position indicates the distance to the starting position (current position): Relative position = Target position - Starting position 
	<p>Speed (C01302/1...15) Maximum speed during the positioning process.</p> <ul style="list-style-type: none"> Depending on the profile parameters of position, acceleration and deceleration, it is possible that the drive will not even reach the maximum speed. In this case, the graphic representation will be a trapezium instead of a triangle:  <ul style="list-style-type: none"> 1 Acceleration 2 Travelling speed (is not reached in this case) 3 Deceleration 4 Target position (or traversing distance)
	<p>Acceleration (C01303/1...15) Maximum acceleration during the positioning process.</p> <ul style="list-style-type: none"> Two types of acceleration are distinguished: <ul style="list-style-type: none"> Constant acceleration: the speed increases linearly. Linearly increasing acceleration: Speed increases in S-shape. A linearly increasing acceleration (S-profile) results from the setting of an S-ramp time (see more below).  <ul style="list-style-type: none"> 1 Constant acceleration (L-profile) 2 Linearly increasing acceleration (S-profile)
	<p>Deceleration (C01304/1...15) Maximum deceleration during the positioning process.</p>

Icon	Profile parameter
	<p>S-ramp time (C01305/1...15)</p> <p>Due to stipulation of an S-ramp time for a profile, the profile is executed with S-shaped ramps, i.e. acceleration and braking processes are initiated smoothly in order to reduce jerk and thus the stress on the drive components.</p> <ul style="list-style-type: none"> • The acceleration/deceleration stipulated in the profile is not achieved until after the specified S-ramp time. • This kind of acceleration/deceleration is needed for sensitive machine parts with a certain amount of play. • The unavoidable consequence of the slower increase in acceleration in the case of the S profile is that the positioning time is longer compared to the L profile, which is more efficient in terms of time. <p>► S-ramp time for jerk limitation (642)</p>
	<div>  </div> <p> 1 Without jerk limitation (L profile) 2 With jerk limitation (S profile) </p>
	<p>Final speed (C01305/1...15)</p> <p>This specifies the speed at which the drive is to start the next profile after reaching the target position. With a final speed not equal to "0", "velocity changeover" or "overchange" is possible, i.e. when the target position is reached, a second positioning process is started immediately without the drive coming to a standstill at the first target position.</p>
	<div>  </div> <p> 1 Target position 2 Final speed (in this case, not equal to "0") </p>
	<p>Sequence profile (C01307/1...15) for profile linkage/following block control</p> <p>A special feature is automatic advancing to subsequent profiles with and without velocity changeover. For this purpose, the profile number of the desired subsequent profile (1 to 15) is simply set in the parameter "Sequence profile" (C01307/1...15) of a profile.</p> <p>After execution of the profile (target position reached), the set following (subsequent) profile is started automatically. In this way, profile chains can be stipulated without additional control processes.</p> <ul style="list-style-type: none"> • If the profile parameter "Final speed" (C01305/1...15) is set to \neq "0", there is a velocity changeover leading into the following (subsequent) profile at the set final speed. • If "0" is set for the following (i.e. subsequent) profile, profile linkage does not take place. • This function can be performed in all positioning modes.
	<p>TP profile (C01308/1...15)</p> <p>Profile number of the profile (1 ... 15) that is to be executed after a touch probe has been detected.</p> <ul style="list-style-type: none"> • If "0" is set, there will be no profile stepping through touch probe. • Only relevant for positioning modes with touch-probe. <p>► Touch probe positioning (641)</p>
	<p>TP signal source (C01309/1...15)</p> <p>Selection of the signal source for touch probe detection.</p> <ul style="list-style-type: none"> • Only relevant for positioning modes with touch-probe. <p>► Touch probe positioning (641)</p>

9.8.2.3 Positioning modes

For positioning, it is possible to select from different positioning modes in relation to the type of axis/application. These modes are described in the following table.



Stop!

In the positioning modes "continuous" and "relative", the "TroubleQuickStop" error response occurs in the Lenze setting when the maximum travel distance is exceeded ([C01213/1](#)). ▶ [Monitoring of the maximum travel distance](#) (📖 596)



Note!

For absolute positioning, the home (reference) position must be known!

- If absolute positioning (positioning modes 1, 4, 5, 8, 11, 12) is started although the home position is not known:
 - The error message set in [C00595/8](#) is displayed (Lenze setting: "WarningLocked").
 - The error message "[Ck08: Home position unknown](#)" is entered into the logbook.

Positioning mode		Info
1	Absolute (shortest path)	Travelling along the axis takes place until an absolute position is reached via the shortest path. <ul style="list-style-type: none">• Reference for the absolute position is the zero position.
8	Absolute (shortest path) to TP	
2	Continuous	In these two modes, no particular position is approached but travelling takes place at the traversing speed stipulated by means of the profile. <ul style="list-style-type: none">• The values of the profile are used for accelerating and decelerating.• The direction of travel is determined by the sign of the traversing speed.
9	Continuous to TP	
3	Relative	The axis is traversed by a distance. <ul style="list-style-type: none">• Reference for the distance is the target position of the previously executed profile.
10	Relative to TP	
Positioning modes for modulo measuring system (rotary table application) ▶ Activation of the modulo measuring system (📖 586)		
4	absolute (Cw)	Travelling along the axis takes place <u>clockwise</u> until an absolute position is reached. <ul style="list-style-type: none">• Reference for the absolute position is the zero position.• In this direction, the zero position of the axis can be exceeded.
11	Absolute (Cw) on TP	
5	absolute (Ccw)	Travelling along the axis takes place <u>counter-clockwise</u> until an absolute position is reached. <ul style="list-style-type: none">• Reference for the absolute position is the zero position.• In this direction, the zero position of the axis can be exceeded.
12	Absolute (Ccw) on TP	

9.8.2.4 Touch probe positioning

In case of a touch probe positioning, first the profile is executed according to the set profile parameters. If a touch probe is detected during the process, it is automatically changed to the profile defined in the "TP profile" profile parameter. This profile mode is also defined via the mode selection like in the following profile start processes.

If no valid TP profile is set, the travel request is aborted ("PosStop").

Preconditions for touch probe positioning

- The mode of the current profile data set contains the setting "to TP".
- For absolute positioning, the home (reference) position must be known.
- In the corresponding profile data set, the following profile parameters must be set in addition:
 - TP profile ([C1308/x](#))
 - TP signal source ([C1309/x](#))
- The touch probe interface is configured such that the selected TP signal source is enabled.
 - See chapter entitled "[Touch probe detection](#)". ([411](#))



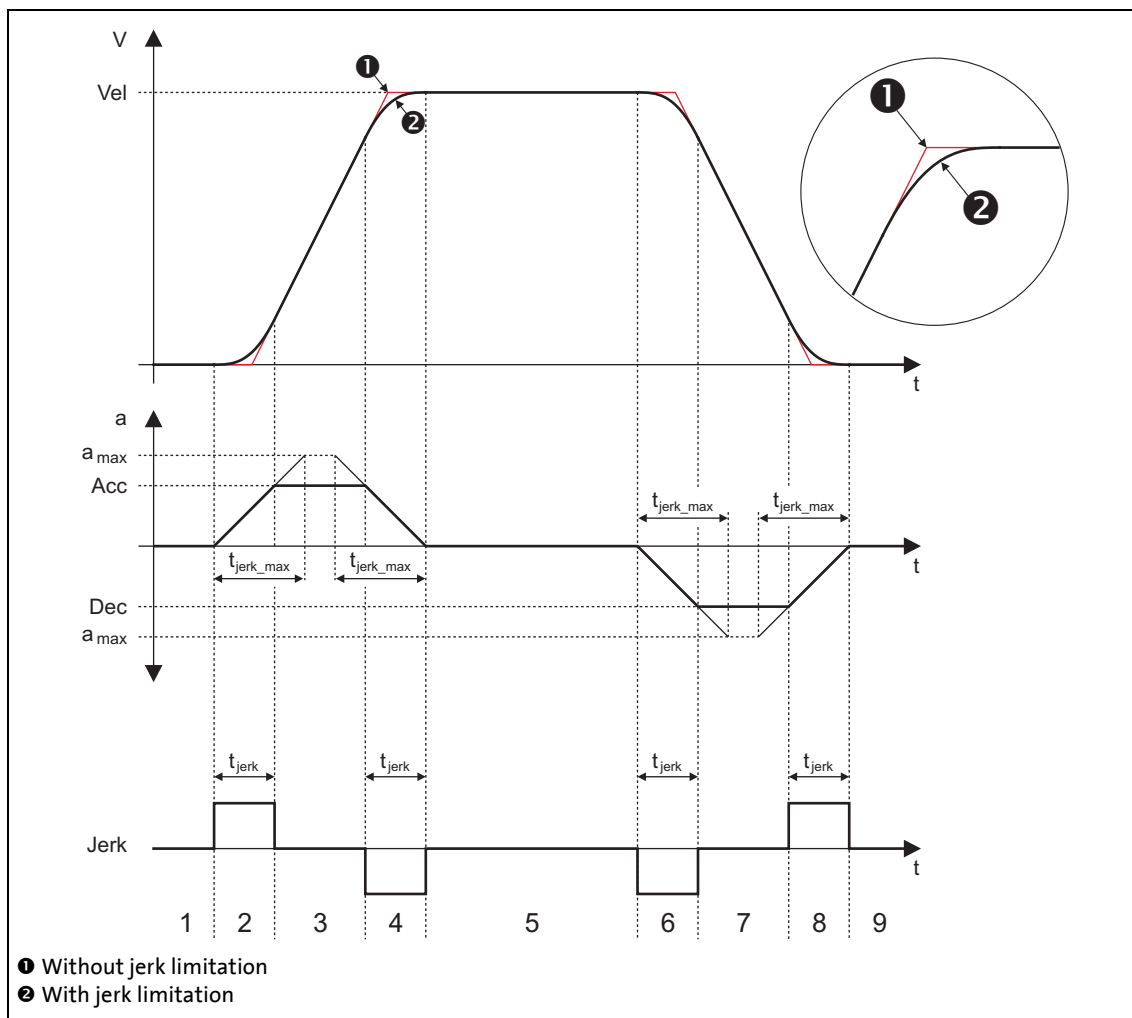
Note!

Go to [C02810/x](#) and select the edge, the digital input used for the connection of the touch-probe sensor is to respond. In the Lenze setting of [C02810/x](#), no touch probe is detected!

9.8.2.5 S-ramp time for jerk limitation

The maximum jerk is defined by the selection of an S-ramp time $t_{\text{jerk_max}}$, after which the max. acceleration (a_{max}) only is reached.

- The actual jerk time t_{jerk} is reduced according to the actual acceleration Acc:



- | | |
|---|---|
| 1. Standstill | 6. Deceleration with set jerk limitation |
| 2. Acceleration with set jerk limitation | 7. Deceleration according to deceleration profile (Dec) |
| 3. Acceleration according to acceleration profile (Acc) | 8. Reduce deceleration (jerk limitation) |
| 4. Reduce acceleration (jerk limitation) | 9. Standstill (position target reached) |
| 5. Traversing with Vel according to speed profile | |

**Note!**

If disproportionately high S-ramp times are set for low acceleration times, this may result in an incorrect profile generation.

Example: $v = 100 \text{ mm/s}$, $a = 1000 \text{ mm/s}^2$

→ $t_{\text{acc}} = 0.1 \text{ s}$

→ $t_{\text{jerk_max}} = 1 \text{ s}$

For this reason, you must only set plausible S-ramp times (this should not exceed half the value of t_{acc}).

9.8.3 Requesting the operating mode

Request for "positioning" mode by means of the [MCK control word](#):

MCK control word							
Bit 31	...		Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
				OpMode_Bit3	OpMode_Bit2	OpMode_Bit1	OpMode_Bit0
X	...	X	X	0	0	1	1

X = Status not significant

If the **MCKInterface** is connected upstream to the **Motion Control Kernel** and if the operating mode is requested at the [L_MckCtrlInterface](#) FB, the *wOperationMode* and *bOperationMode_1...8* process inputs are available.

9.8.4 Carrying out positioning

9.8.4.1 Stipulation of the profile to be executed

The profile to be executed is stipulated by means of the [MCK control word](#) in bit-coded form:

Bit	Designation	Description								
24	ProfileNo_Bit0	Profile	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
...	...	Profile 0	0	0	0	0	0	0	0	0
...	...	Profile 1	0	0	0	0	0	0	0	1
31	ProfileNo_Bit7	Profile 2	0	0	0	0	0	0	1	0
								
		Profile 15	0	0	0	0	1	1	1	1

All other possible settings are reserved for future extensions!

If the **Motion Control Kernel** is downstream from the **MCKInterface**, the [L_MckCtrlInterface](#) FB provides the following processing inputs for stipulating the profile to be executed:

Identifier	Data type	Information/possible settings
wProfileNo	WORD	Selection of the profile number <ul style="list-style-type: none">• Optionally as a data word or binary coded.• In the Lenze setting, an operating mode change is carried out by the L_MckCtrlInterface FB at the same time as the profile is stipulated:<ul style="list-style-type: none">• If profile 0 is selected: Activation of "Speed follower" operating mode• If profile 1 is selected: Activation of "Homing" operating mode• If profile 2 is selected: Activation of "Manual jog" operating mode• If profile 3 ... 15 is selected: Activation of "Positioning" operating mode• The operating mode change with profile number can be set in C01298/1...4.
bProfileNo_1 ... bProfileNo_8	BOOL	



Note!

The profile 0 is no valid profile for the "positioning" operating mode.

If a driving request with an invalid profile number is started, the response set in [C00595/12](#) occurs (Lenze setting: "WarningLocked").

9.8.4.2 Starting/cancelling a traversing task

Control is exercised by means of bits 16 ... 19 in the [MCK control word](#):

Homing	MCK control word			
	Bit 19	Bit 18	Bit 17	Bit 16
	PosStop	Pos DisableFollowProfile	PosFinishTarget	PosExecute
Start travelling	0	0	0	01
Complete interrupted profile	0	0	01	0
Do not travel sequence profile	0	1	X	X
Cancel travelling*	1	X	X	X
*From version 02.00.00, more travel requests will be inhibited ("PosExecute" will be blocked).				
X = Status not significant				

If the **Motion Control Kernel** is downstream from the **MCKInterface** in the circuit, the [L_MckCtrlInterface](#) FB provides the following process inputs for controlling the operating mode:

Identifier	Data type	Information/possible settings
bPosExecute	BOOL	Start travelling FALSE → TRUE Execute selected profile
bPosExecuteFinish	BOOL	Complete interrupted profile FALSE → TRUE A positioning process previously cancelled, e.g. by <i>bPosStop</i> or due to a device error, is resumed by travelling to the original target. From version 14.00.00, <i>bPosExecuteFinish</i> serves to permanently retravel to the original target even if the profile has been completed once or several times.
bPosDisableFollowProfile	BOOL	Do not execute following profile (switch off profile linkage) TRUE Evaluation of the sequence profile number parameterised in C01307/1...15 for the selected profile is suppressed.
bPosStop	BOOL	Cancel travelling TRUE Stop positioning From version 02.00.00, more travel requests will be inhibited ("PosExecute" will be blocked).



Tip!

Travel requests/profiles can also be started while the drive is running. The drive does not need to be at standstill.

Related topics:

- ▶ [Target position monitoring \(status "drive in target"\)](#) (📘 594)
- ▶ [Monitoring of the maximum travel distance](#) (📘 596)
- ▶ [Following error monitoring system](#) (📘 597)

9.8.4.3 Override of the parameterised positioning mode

The setting of the positioning mode in [MCK control word](#) superimposes the mode selection via the "Mode" profile parameter ([C1300/1...15](#)). This means that for selected profiles the mode selection and the request of a touch probe positioning via process data are possible. The value set in [C01300/1...15](#) is not overwritten. The following applies to the override:

- A. Valid positioning mode in the MCK control word:
The positioning mode set in the MCK control word is used.
- B. Positioning mode in the MCK control word = 0:
The positioning mode set in "mode" profile parameter ([C1300/1...15](#)) is used.
- C. Invalid positioning mode in the MCK control word:
Ck09Error message "Ck09: Invalid positioning mode". The response set in [C00595/9](#) occurs (Lenze setting: "WarningLocked").

Bit	Designation	Description	Bit 3	Bit 2	Bit 1	Bit 0
20	PosModeBit0	Positioning mode				
...	...	Positioning mode = setting in C01300/1...15	0	0	0	0
23	PosModeBit3	Absolute (shortest path)	0	0	0	1
		Continuous	0	0	1	0
		Relative	0	0	1	1
		absolute (Cw)	0	1	0	0
		absolute (Ccw)	0	1	0	1
		Absolute (shortest path) to TP	1	0	0	0
		Continuous to TP	1	0	0	1
		Relative to TP	1	0	1	0
		Absolute (Cw) on TP	1	0	1	1
		Absolute (Ccw) on TP	1	1	0	0
		All other possible settings are reserved for future extensions!				

If the **Motion Control Kernel** is downstream from the **MCKInterface** in the circuit, the [L_MckCtrlInterface](#) FB provides the following process input for stipulating an override of the positioning mode:

Identifier	Data type	Information/possible settings
wPosMode	WORD	Override of the positioning mode set in the profile data • Only bit 0 ... bit 3 of wPosMode are evaluated.
		0 Positioning mode = setting in C01300/1...15
		1 Absolute (shortest path)
		2 Continuous
		3 Relative
		4 absolute (Cw)
		5 absolute (Ccw)
		8 Absolute (shortest path) to TP
		9 Continuous to TP
		10 Relative to TP
		11 Absolute (Cw) on TP
		12 Absolute (Ccw) on TP
		All other possible settings are reserved for future extensions!

9.8.4.4 Position teaching

The [MCK control word](#) can be used to initiate "teaching" or "latching" of the MCK setpoint position or the current position into the currently selected profile.

Bit	Designation	Description
14	PosTeachSetPos	"1" ≡ Teach MCK set position into the selected profile
15	PosTeachActPos	"1" ≡ Teach current position into the selected profile

If the **Motion Control Kernel** is downstream from the **MCKInterface**, the [L_MckCtrlInterface](#) FB provides the following process inputs for teaching:

Identifier	Data type	Information/possible settings
bPosTeachSetPos	BOOL	Teach MCK setpoint position
		TRUE Teach MCK setpoint position into the selected profile.
bPosTeachActPos	BOOL	Teach current position
		TRUE Teach current position into the selected profile.



Note!

If request is made at the same time, the current position is taught.

9 Basic drive functions (MCK)

9.9 Stop

9.9 Stop

If the "normal stop" operating mode is active, the drive is brought to a standstill with a parameterisable deceleration ramp.

9.9.1 Parameter setting

Short overview of parameters for "Normal stop" operating mode:

Parameter	Info	Lenze setting	
		Value	Unit
C01251/1	Normal stop: Deceleration	720.0000	units/s ²
C01252/1	Stop: S-ramp time	0.000	s

9.9.2 Requesting the operating mode

Request for "Normal stop" operating mode by means of the [MCK control word](#):

MCK control word						
Bit 31	...	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
			OpMode_Bit3	OpMode_Bit2	OpMode_Bit1	OpMode_Bit0
X	...	X	0	1	0	0
X = Status not significant						

If the **MCKInterface** is connected upstream to the **Motion Control Kernel** and if the operating mode is requested at the [L_MckCtrlInterface](#) FB, the *wOperationMode* and *bOperationMode_1...8* process inputs are available.

9.10 Position follower

In the "position follower" operating mode, the drive follows a position setpoint.

9.10.1 Parameter setting

Short overview of parameters for "position follower" operating mode:

Parameter	Info	Lenze setting	
		Value	Unit
C01218	MCK: PosFollower setting	Bit coded	
C01236/1	PosFollower: Sync. speed	360.0000	units/s
C01237/1	Pos follower: Sync. accel.	720.0000	units/s ²
C01237/2	Pos follower: Sync. decel.	720.0000	units/s ²
C01238/1	Pos follower: Sync. S-ramp time	0.000	s

9.10.1.1 Functional settings

In [C01218](#), various functional settings for the position follower can be made in bit-coded form.

Function		Lenze setting
Bit 0	Speed FF control.: nSpeedSetValue_a	Off
Bit 1	Speed FF control: nSpeedAddValue_v	Off
Bit 2	HW limit switch on	On
Bit 3	SW limit switch on	On
Bit 4	Reserved	Off
Bit 5	Reserved	Off
Bit 6	Reserved	Off
Bit 7	Position controller off	Off

Speed feedforward control by means of nSpeedSetValue_a

If this function has been activated by means of bit 0 in [C01218](#), the main setpoint *nSpeedSetValue_a* is used as the speed feedforward control value.

Speed feedforward control by means of nSpeedAddValue_v

If this function has been activated by means of bit 1 in [C01218](#), the additive speed value *nSpeedAddValue_v* is used as the speed feedforward control value.

HW limit switch on

If this function has been activated by means of bit 2 in [C01218](#), travel range monitoring by means of hardware limit switches is active in this mode.

► [Limit position monitoring](#) (590)

SW limit switch on

If this function has been activated by means of bit 3 in [C01218](#), travel range monitoring by means of parameterised software limit positions is active in this mode.

► [Limit position monitoring](#) (590)

Position controller off

If this function is activated via bit 7 in [C01218](#), the position controller is deactivated in this operating mode. Hence, following error control is switched-off.

9.10.2 Requesting the operating mode

Requesting the "position follower" operating mode by means of the [MCK control word](#):

MCK control word						
Bit 31	...	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
			OpMode_Bit3	OpMode_Bit2	OpMode_Bit1	OpMode_Bit0
X	...	X	0	1	0	1

X = Status not significant

If the **MCKInterface** is connected upstream to the **Motion Control Kernel** and if the operating mode is requested at the [L_MckCtrlInterface](#) FB, the *wOperationMode* and *bOperationMode_1...8* process inputs are available.

9.10.3 Setpoint selection

The absolute position setpoint is stipulated via the *dnPosSetValue_p* process input.



Note!

The *bPosCtrlOn* process input must be set to TRUE so that position/angle control is active within motor control.

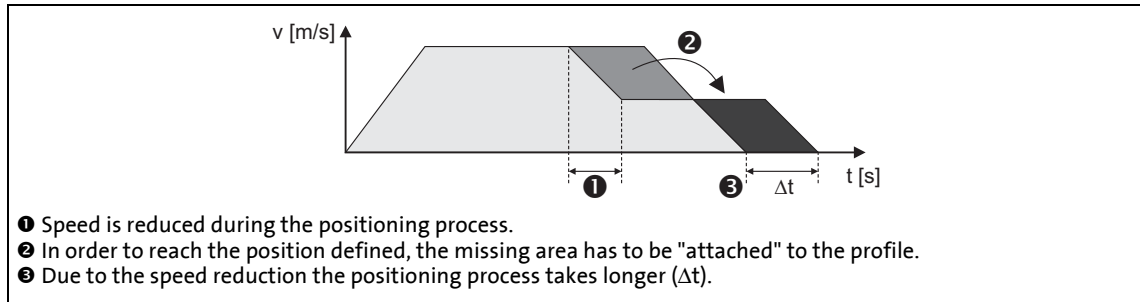
Compensating following errors

If the *bDeltaPosOn* process input is set to TRUE, a position difference (following error) is compensated for which is not internally generated from setpoint/actual positions but must be defined via the *dnDeltaPos_p* process input instead.

9.11 Override

An "Override" is the change of profile parameters and their acceptance during the positioning process.

- In this case the traversing profile has to be adapted accordingly, so that positioning is carried out exactly to the target position defined, even if for example a change in speed occurs during the positioning process ("Speed override"):



[9-34] Override (here: speed override)

- The override for speed, acceleration, and S-ramp time affects all motion profiles that are controlled by the internal profile generator:
 - Manual jog
 - Retracting from limit switches
 - Homing
 - Point-to-point positioning



Note!

The online change of speed and acceleration is in effect from the start of the profile until the deceleration phase begins. Changing the deceleration phase by means of an override is therefore not possible!

- In the case of an override value of 0 % for the speed, the drive is brought to a standstill.
- In the case of an override value of 0 % for the acceleration, acceleration does not take place any longer.

The acceleration override also has the same effect on the deceleration ramp to the same extent specified, but only until the deceleration phase is initiated.

The override has no impact on:

- The "speed follower" operating mode
- Synchronising processes
- Setpoint controls via external setpoints
- Abort via input *bPosStop*
- Speed setpoint selection in case of error (e. g. "Fail-QSP")

9.11.1 Speed override

Activating override

If control bit 11 (*EnableSpeedOverride*) has been set to "1" in the [MCK control word](#), a speed override is carried out in accordance with the stipulated override value.

If the **Motion Control Kernel** is downstream from the **MCKInterface** in the circuit, the [L_MckCtrlInterface](#) provides the following process input for activating the speed override:

Identifier	Data type	Information/possible settings
bEnableVelOverride	BOOL	Speed override
		TRUE Activate speed override

Stipulate override value

The override value is selected via the *nSpeedOverride_a* input at the SB [LS_MotionControlKernel](#). The override value is a percentage of the speed of the current profile.

Identifier	Data type	Information/possible settings
nSpeedOverride_a	INT	Value for speed override <ul style="list-style-type: none"> Percentage multiplier (0 ... 199.99 %) for the currently active speed. 16384 \equiv 100 % of the maximum traversing speed (display in C01211/1). If the override value is 0 %, the drive is brought to a standstill.

Deactivate override

If control bit 11 (*EnableSpeedOverride*) is reset to "0", travelling takes place at the speeds that have been specified by means of the profile parameters. Acceleration/deceleration from the speed defined with override to the speed set in the profile takes places immediately in this case.

Deactivating the override within the braking/deceleration ramp does not have any effect.

9.11.2 Acceleration override

Activating override

If control bit 12 (*EnableAccOverride*) in the [MCK control word](#) has been set to "1", an acceleration override takes place in accordance with the stipulated override value.

If the **Motion Control Kernel** is downstream from the **MCKInterface** in the circuit, the [L_MckCtrlInterface](#) FB provides the following process input for activating the acceleration override:

Identifier Data type	Information/possible settings
bEnableAccOverride BOOL	Acceleration override
	TRUE Activate acceleration override

Stipulate override value

The override value is stipulated via the *nAccOverride_a* input at the [LS_MotionControlKernel](#) SB. The override value is a percentage of the maximum acceleration that has been set for the respective operating mode (referencing, manual jog, positioning etc.) in the corresponding profile parameter.

The acceleration override results in a deceleration override. Both ramps are evaluated by multiplication by the acceleration override until the deceleration process sets in.

Identifier Data type	Information/possible settings
nAccOverride_a INT	Value for acceleration override <ul style="list-style-type: none"> Percentage multiplier (0 ... 199.99 %) for the currently active acceleration. 16384 \equiv 100 % of the parameterised acceleration of the corresponding operating mode. If the override value is 0 %, acceleration ceases.

Deactivate override

If control bit 12 (*EnableAccOverride*) is reset to "0", travelling takes place at the acceleration rates specified by means of the profile parameters. "Ramping up" from the acceleration defined with override to the acceleration set in the profile takes place immediately in this case.

9.11.3 S-ramp smoothing override

Activating override

If control bit 13 (*EnableSRampOverride*) in the [MCK control word](#) is set to "1", S-ramp smoothing override is executed according to the selected override value.

If the **Motion Control Kernel** is downstream from the **MCKInterface** in the circuit, the [L_MckCtrlInterface](#) FB provides the following process input for activating the S-ramp smoothing override:

Identifier	Data type	Information/possible settings
bEnableSRampOverride	BOOL	S-ramp smoothing override
		TRUE Activate S-ramp smoothing override

Stipulate override value

Optional stipulation of the override value is carried out via the *nSRampOverride_a* input at the [LS_MotionControlKernel](#) SB. The override value is a percentage of the S-ramp time set in the profile data.



Note!

If the *nSRampOverride_a* input remains unconnected or if an override value of "0 %" is selected, activation of the S-ramp override causes deactivation of the S-ramp time.

- Deactivation of the S-ramp time before the start of a profile with S-ramp time causes linear ramp generation.
- Deactivation of the S-ramp time during a traversing process, however, is not accepted immediately in the profile generator, but the profile generator checks automatically when an online change of the ramp form can be carried out and then initiates it automatically.



Tip!

Thus it is possible to start a travel profile with S-ramp time and then deactivate the S-ramp time, e.g. to traverse with a linear characteristic after reaching the profile speed.

Identifier	Data type	Information/possible settings
nSRampOverride_a	INT	Value for S-ramp smoothing override <ul style="list-style-type: none"> • Percentage multiplier (0 ... 100 %) for the currently active acceleration. • 16384 \equiv 100 % of the parameterised S-ramp time (C01306/1...15). • Values > 16384 are ignored.

Deactivate override

If control bit 13 (*EnableSRampOverride*) is reset to "0", the S-ramp time specified by means of the profile parameters is used for profile generation.

9.12 Holding brake control

This basic function is used for low-wear control of a holding brake.



Danger!

Please note that the holding brake is an important element of the safety concept of the entire machine.

Thus, proceed very carefully when commissioning this system part!



Stop!

Holding brakes on Lenze motors are not intended for braking during operation. The increased wear caused by braking during operation can destroy the motor holding brake!



Note!

- **Deactivate automatic DC-injection braking when a holding brake is used!**
 - For this purpose, go to [C00019](#) and set the [Auto DCB](#) threshold to "0".
 - Background: Controller inhibit is already activated by the holding brake control.
- If an electrically holding (self-releasing) brake is to be controlled instead of an electrically released (self-holding) brake, the trigger signal must be inverted!
 - [Functional settings](#) (□ 661)
- Detailed information on mounting and electrical installation of the motor holding brake can be found in the documentation on the motor holding brake.

Intended use

Motor holding brakes are used to lock axes if the controller is inhibited or in case of "mains off" system status. This is not only important for vertical axes but also for e.g. horizontal axes which may cause various problems if the motion is not controlled.

Examples:

- Loss of the reference information after mains OFF and further spinning of the drive.
- Collision with other moving machine parts.

9.12.1 Internal interfaces

In the function block editor, the [LS MotionControlKernel](#) system block provides the following internal interfaces for the basic function "holding brake control":

Inputs

Identifier	Data type	Information/possible settings				
bMBrakeRelease	BOOL	<div>Releasing/applying the brake in connection with the selected operating mode</div> <table><tr><td>FALSE</td><td><div>Apply brake.</div><ul style="list-style-type: none">During automatic operation, the internal brake logic controls the brake.</td></tr><tr><td>TRUE</td><td><div>Release brake manually (forced release).</div><ul style="list-style-type: none">Note! The brake can also be released if the controller is inhibited!During automatic operation, the internal brake logic is deactivated and the brake is released (supervisor operation). If a controller inhibit has been set by the brake control, it will be deactivated.In semi-automatic operation, the brake is released including feedforward control.</td></tr></table>	FALSE	<div>Apply brake.</div> <ul style="list-style-type: none">During automatic operation, the internal brake logic controls the brake.	TRUE	<div>Release brake manually (forced release).</div> <ul style="list-style-type: none">Note! The brake can also be released if the controller is inhibited!During automatic operation, the internal brake logic is deactivated and the brake is released (supervisor operation). If a controller inhibit has been set by the brake control, it will be deactivated.In semi-automatic operation, the brake is released including feedforward control.
FALSE	<div>Apply brake.</div> <ul style="list-style-type: none">During automatic operation, the internal brake logic controls the brake.					
TRUE	<div>Release brake manually (forced release).</div> <ul style="list-style-type: none">Note! The brake can also be released if the controller is inhibited!During automatic operation, the internal brake logic is deactivated and the brake is released (supervisor operation). If a controller inhibit has been set by the brake control, it will be deactivated.In semi-automatic operation, the brake is released including feedforward control.					
bMBrakeStartValue2	BOOL	<div>Selection of the torque feedforward control value</div> <div>► Feedforward control of the motor before release</div> <table><tr><td>FALSE</td><td>Starting value 1 is active (see the following figure).</td></tr><tr><td>TRUE</td><td>Starting value 2 is active (see the following figure).</td></tr></table> <div>Creation of the feedforward control value for the release process of the brake:</div> <div>A Signal path for motor control <u>with</u> feedback</div> <div>B Signal path for motor control <u>without</u> feedback</div> <div>C Feedforward control value</div> <div><p>1 C02581/1: Switching threshold</p><p>2 C02581/2: Hysteresis for release</p><p>3 C02581/3: Hysteresis for application</p><p>4 C02581/4: Starting value 1 for manual feedforward control</p><p>5 C02581/5: Starting value 2 for manual feedforward control</p><p>6 C02582/Bit 4: Selection of the feedforward control value (automatic/manual selection)</p></div>	FALSE	Starting value 1 is active (see the following figure).	TRUE	Starting value 2 is active (see the following figure).
FALSE	Starting value 1 is active (see the following figure).					
TRUE	Starting value 2 is active (see the following figure).					
nMBrakeAddValue_a	INT	<div>Additive feedforward control value (speed or torque) in [%] for torque feedforward control when the respective control mode is started</div> <ul style="list-style-type: none">For speed control: 100 % \equiv reference speed (C00011)For torque control: 100 % \equiv maximum torque (C00057) <div>► Feedforward control of the motor before release</div>				

Identifier	Data type	Information/possible settings
bMBrakeApplied	BOOL	Input for status detection via switching contacts at the brake <ul style="list-style-type: none"> Only effective if bit 5 in C02582 is set to "1".
		FALSE Brake is released.
		TRUE Brake is applied.

Outputs

Identifier	Data type	Value/meaning
bMBrakeReleaseOut	BOOL	Trigger signal for switching element holding brake control via a digital output <ul style="list-style-type: none"> Use bit 0 under C02582 to activate inverted switching element triggering. <ul style="list-style-type: none"> ► Functional settings
		FALSE Apply brake.
		TRUE Release brake.
bMBrakeReleased	BOOL	"Brake released" status signal considering the brake release time <ul style="list-style-type: none"> When the holding brake is triggered to close, <i>bMBrakeReleased</i> is immediately set to FALSE even if the brake closing time has not yet elapsed!
		TRUE Brake released (after the brake release time has expired).



Stop!

The digital outputs are not suitable for the "direct" control of a holding brake!

- Connect the digital output connected to the trigger signal *bMBrakeReleaseOut* with a relay or power contactor which switches the brake supply.
- When a power contactor is used, the response and release time of the earth contact is added to the response and release time of the brake. Both times must also be considered for parameterising the closing and opening time of the holding brake



Tip!

For direct triggering of a holding brake, the high current output of the 8400 TopLine controller can be used that can switch max. 2.5 A. For this purpose, connect the *bMBrakeReleaseOut* trigger signal to the *bOutHC* input of the SB [LS_DigitalOutput](#).

From version 15.00.00, the *bOutHC_BrakeApplied* status signal of the SB [LS_DigitalInput](#) can be used for a simple monitoring of the switching status of a holding brake connected to the high current output. ► [Switching status of the motor holding brake at the high current output](#) (p. 397)

9.12.2 Parameter setting



Danger!

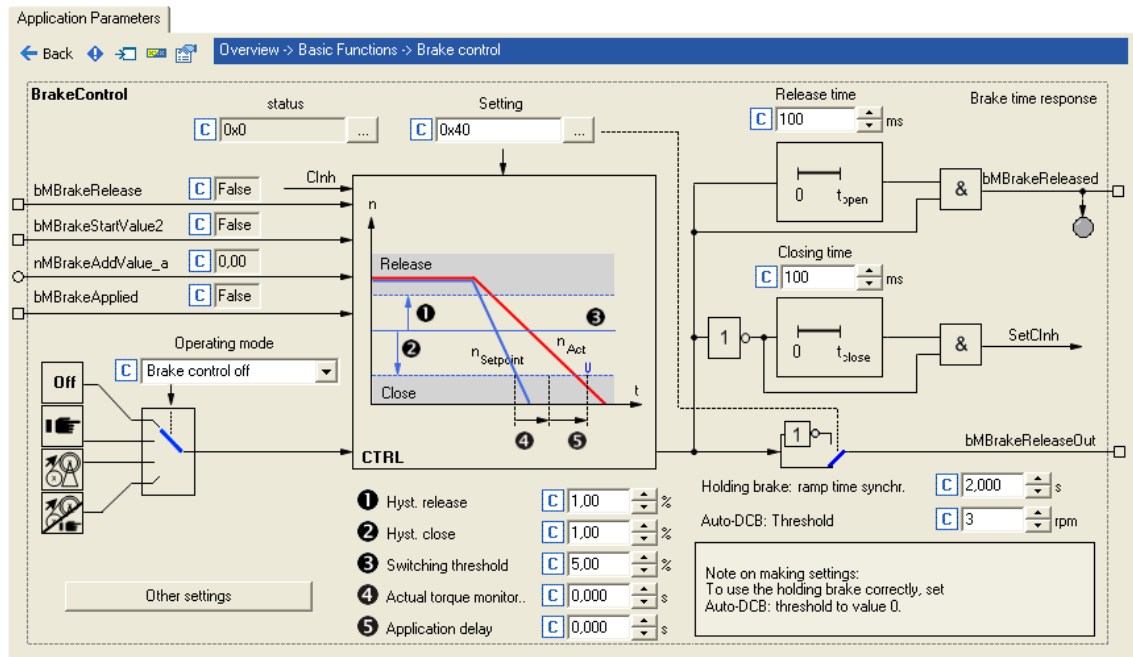
A faultless holding brake control function requires a correct setting of the different deceleration times in the following parameters!

A wrong setting of the delay times can cause a faulty control of the brake!



How to go to the parameterisation dialog of the holding brake control:

1. »Engineer« Go to the *Project* view and select the 8400 Topline controller.
2. Select the **Application parameters** tab from the *Workspace*.
3. Go to the *Overview* dialog level and click the "**Basic functions**" button.
4. Go to the *Overview* → *Basic functions* dialog box and click the **Holding brake control** button.



Short overview of parameters for holding brake control:

Parameter	Info	Lenze setting	
		Value	Unit
C02580	Holding brake: Operating mode	0: Brake control off	
C02581/1	Holding brake: Switching threshold	5.00	%
C02581/2	Holding brake: Hyst. release	1.00	%
C02581/3	Holding brake: Hyst. close	1.00	%
C02581/4	Holding brake: FF control starting value 1	0	%
C02581/5	Holding brake: FF control starting value 2	0	%
C02582	Holding brake: Setting	0	
Highlighted in grey = display parameter			

Parameter	Info	Lenze setting	
		Value	Unit
C02589/1	Holding brake: Closing time	100	ms
C02589/2	Holding brake: Release time	100	ms
C02589/3	Holding brake: Waiting time status	100	ms
C02589/4	Holding brake: Ramp FF control	0	ms
C02593/1	Holding brake: Actual value monitoring	0.000	ms
C02593/2	Holding brake: Application delay	0.000	ms
C02610/1	MCK: Holding brake ramp time synchr.	2.000	s
C02607	Holding brake: Status	-	
C00830/68	MCK: nMBrakeAddValue_a	-	%
C00833/80	MCK: bMBrakeRelease	-	
C00833/81	MCK: bMBrakeStartValue2	-	
C00833/82	MCK: bMBrakeApplied	-	
Highlighted in grey = display parameter			

9.12.2.1 Operating mode

For different applications and tasks, different operating modes are available in [C02580](#). The selected operating mode determines whether the holding brake control is used and how the holding brake will be switched.

Mode 0: Brake control off

In this mode, brake control is switched off (not active).

- The *bMBrakeReleaseOut* trigger signal for the holding brake control switching element is set to FALSE.
- The *bMBrakeReleased* status signal is set to FALSE.



Note!

In the Lenze setting, the mode 0 is preset to get into a safe state after the mains is switched on.

Mode 11: Manual control

In this mode, brake release and brake application can be directly controlled via the *bMBrakeRelease* input without special logic or automatic.

- Setting pulse inhibit or controller inhibit has no influence on the *bMBrakeReleaseOut* trigger signal for the holding brake control switching element.
- After the brake has been activated and the brake application time has expired, the controller is inhibited automatically by the basic "Holding brake control" function.



Tip!

You can use mode 11 to easily check if the brake switches correctly.

Mode 12: Automatic control

In this mode, the brake is controlled automatically.

**Danger!**

In this mode, the input *bMBrakeRelease* should be permanently set to FALSE unless manual release (supervisor operation) is required.

If the *bMBrakeRelease* input is set to TRUE, the brake is released immediately, even if the controller is inhibited!

- If the requested speed setpoint reaches a parameterisable upper speed threshold that allows traversing of the drive, the brake will be released and operation enabled.
- On the other hand, if speed setpoint and actual speed fall below a parameterisable lower speed threshold, the brake will be applied under consideration of different time parameters.
- For operating modes with setpoint request via control signal (e.g. "PosExecute" in the [Positioning](#) operating mode), the speed thresholds do not apply. Here the control logic opens and closes the holding brake through internal commands in the **Motion Control Kernel**.
- The brake will also be activated automatically if quick stop is activated in the drive, e.g. by a device command or as response to an error, and in the event of controller inhibit or pulse inhibit.
- After automatic brake activation and expiration of the brake application time, the controller is inhibited automatically by the basic "Holding brake control" function.

**Tip!**

The 2/12 mode is the usual mode to control the brake.

Mode 13: Semi-automatic control

In this mode, brake release and brake application can be directly controlled via the *bMBrakeRelease* input without special logic or automatic.

In contrast to the manual operation (mode 11)

- the feedforward control is active in this mode, preventing a sagging e.g. in case of a hoist.
- the brake in this mode also closes when the controller is inhibited in order to prevent the axis in a hoist from falling.

Related topics:

- ▶ [TroubleQSP](#) (📖 121)
- ▶ [Behaviour in case of pulse inhibit](#) (📖 670)

9.12.2.2 Functional settings

The following bit coded functional settings for the holding brake control can be made in [C02582](#):

Bit	Option	Info
Bit 0	bMBrakeReleaseOut invert.	Activation of inverted control <ul style="list-style-type: none"> "1" ≡ Inverted logic of the trigger signal for the holding brake control switching element
Bit 1	Horizontal brake protection	Brake response in case of pulse inhibit <ul style="list-style-type: none"> "1" ≡ In the case of a pulse inhibit, the actual speed value is monitored which must reach the "Close" threshold value to cause the holding brake to be applied. Note: <ul style="list-style-type: none"> This function is only active if bit 3 (horizontal/winding technology) is set as well. The function is used in order that, when the controller is inhibited, the holding brake of a drive with horizontal traverse path does not wear out during rotation. With vertical motion (bit 3 = 0), this function is not active. Especially with hoists and activated pulse inhibit of the controller, an immediate application of the brake is essential for safety-related reasons!
Bit 2	with hoist inv. feedfwd. control	Direction of feedforward control with vertical/hoist technology: <ul style="list-style-type: none"> "0" ≡ Positive direction "1" ≡ Negative direction Note: Reversal (Ccw) is then considered.
Bit 3	Horizontal application	Direction of movement of the axis <ul style="list-style-type: none"> "0" ≡ The axis performs vertical movements. Gravitational acceleration causes movements. "1" ≡ The direction of the axis is horizontal or rotary. The gravitational acceleration does not cause any movement.
Bit 4	Feedforward control C2581	Selection of the feedforward control value <ul style="list-style-type: none"> "0" ≡ Automatic selection. <ul style="list-style-type: none"> The torque saved at the last stop is used. "1" ≡ Manual selection. <ul style="list-style-type: none"> bMBrakeStartValue2 = FALSE: The feedforward control value 1 set in C02581/4 is used. bMBrakeStartValue2 = TRUE: The feedforward control value set in C02581/5 is used.
Bit 5	Feedback monitoring	Activation of status monitoring <ul style="list-style-type: none"> "1" ≡ The bMBrakeApplied input for status detection of the brake (via a switching contact at the brake) is monitored after the waiting time set in C02589/3 has expired.
Bit 6	Sync ramp L_NSet_1 (from version 02.00.00)	Selection of the ramp time for the synchronisation process to setpoint speed after the brake opening time has elapsed Revised behaviour from version 02.00.00: <ul style="list-style-type: none"> "1" ≡ The ramp time of the effective acceleration of the ramp function generator (L_NSet_1) is used (Lenze setting). "0" ≡ As before, the ramp time set in C02610/1 is used. Note: The changeover can be dynamically both via the ramp parameter and via bit 6.
Bit 7	Reserved	

Related topics:

- ▶ [Behaviour in case of pulse inhibit](#) (📖 670)
- ▶ [Feedforward control of the motor before release](#) (📖 671)

9.12.2.3 Switching thresholds**Stop!**

Do not set the lower speed threshold for closing the brake too high to prevent excessive wear of the brake!

**Note!**

When comparing speeds, only the absolute value of the motor speed and not the direction of rotation is considered.

Upper speed threshold for brake release:

Switching threshold ([C02581/1](#)) + hysteresis for release ([C02581/2](#))

Lower speed threshold for brake application:

Switching threshold ([C02581/1](#)) - hysteresis for application ([C02581/3](#))

**Tip!**

The lower speed threshold for brake application should be set to approximately 5 ... 20 % of the maximum speed to minimise the wear of the brake and provide for an optimum brake reaction by a low grinding of the brake.

Related topics:

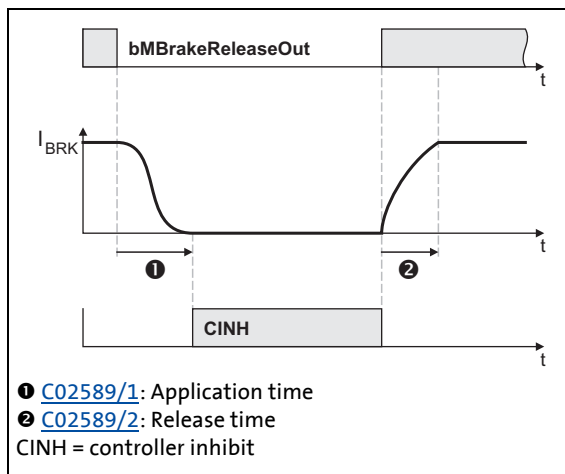
- ▶ [Process when brake is released](#) (📖 667)
- ▶ [Process when brake is closed](#) (📖 668)

9.12.2.4 Application and release time

**Danger!**

A wrong setting of the application and release time can cause a faulty control of the brake!

- If the application time is set too low, the controller is inhibited and the drive becomes torqueless before the brake is applied completely.



- Every mechanical holding brake comes with a construction-conditioned application and release time which must be considered by the holding brake control and is set in [C02589](#).
- The application and release time of the Lenze holding brake is indicated in the supplied operating instructions in the "Technical data" chapter.
- If the application and release times are too long, this is uncritical in respect of safety but leads to unnecessarily long delays during cyclical braking processes.

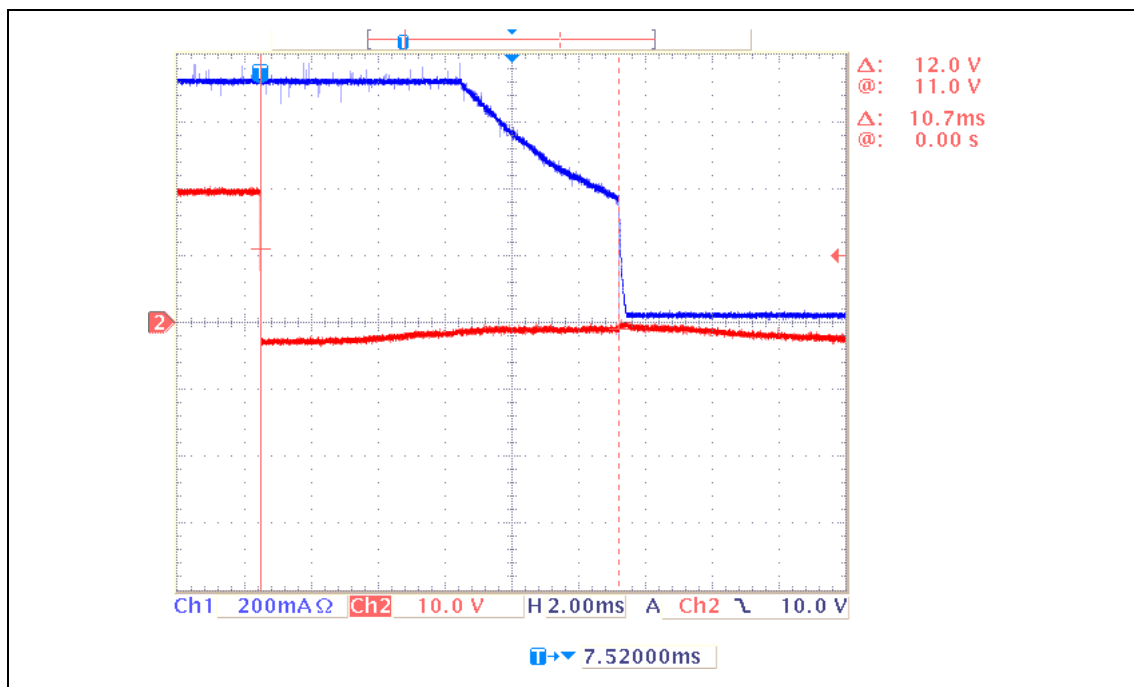
[9-35] Definition of the application and release time with the example of the PM brake

**Tip!**

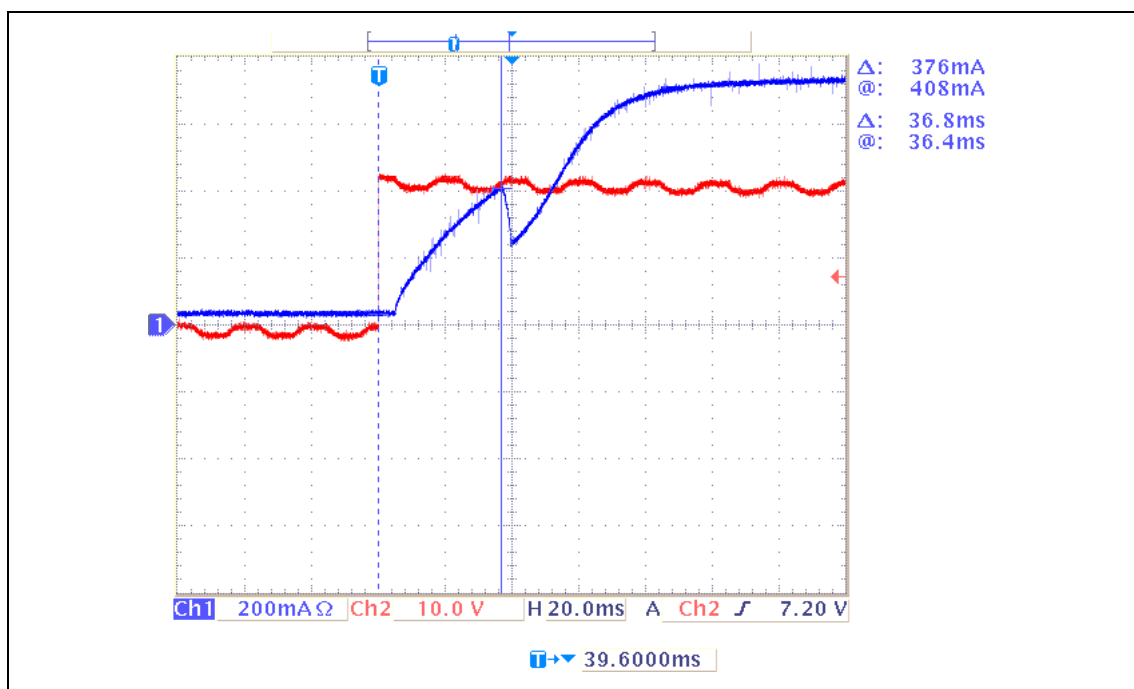
The application and release times do not only vary between the brake types but also depend on the basic conditions in the plant:

- Parameters of the hardware (cable length, temperature, level of supply voltage etc.)
- Contact elements used (brake module or contactor at the digital output)
- Type of overvoltage limitation/suppressor circuit

For optimisation purposes, detect in individual cases the response times by measurement.



[9-36] Oscillogram 1: Current characteristic for the application of a mechanical holding brake (application time: 10.7 ms)



[9-37] Oscillogram 2: Current characteristic for the release of a mechanical holding brake (release time: 36.8 ms)

Related topics:

- ▶ [Process when brake is released](#) (667)
- ▶ [Process when brake is closed](#) (668)

9.12.2.5 Ramp time for approaching the setpoint speed

For the "[Speed follower](#)" operating mode, a ramp time can be set in [C02610/1](#) if the setpoint is already out of reach while the holding brake is initiating the feedforward control process.



Note!

The "[Homing](#)", "[Manual jog](#)", and "[Positioning](#)" operating modes are based on a different control/release process of the holding brake. In these operating modes, the [C02610/1](#) setting parameter does not have any effect!

Example:

A setpoint of 90 % is selected via the ramp function generator while the brake is applied (controller is inhibited).

1. At the set ramp (in most cases [C00012](#)), the ramp function generator ramps up to 90 %.
2. The brake identifies the setpoint selection of 5 % (release switching threshold). The feedforward control of the brake provides 3 % of the setpoint and will not report the release of the brake after approx. 1 s has expired.

Conclusion: 90 % of the selected setpoint is already ramped up while the brake is only providing 3 % of the setpoint via the feedforward control.

Since at this point a step change from 3 % to 90 % may cause mechanical jerks, the setpoint is ramped up from 3 % to 90 %, using the ramp time set in [C02610/1](#) (Lenze setting: 2 s).

Our example is based on the V/f characteristic control (VFCplus) operating mode since the servo control (SC) operating mode does not use the switching threshold for the application of the holding brake for speed feedforward control. However, ramping up to a setpoint that is out of reach is carried out for all motor control operating modes because there is always a mechanical/electric delay when controlling a holding brake.

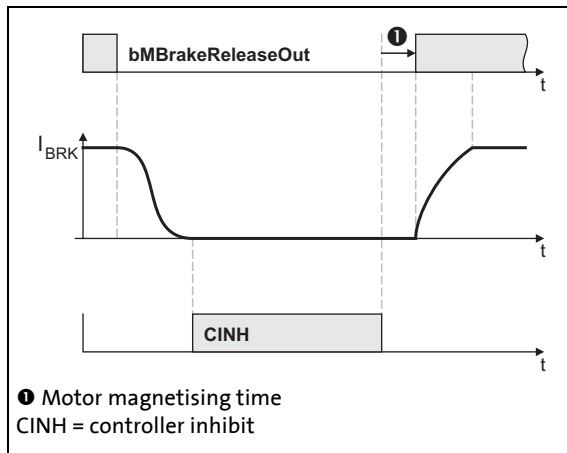
This delay is due to:

- Motor magnetisation (in the case of servo control only)
- Mechanical delay of all switching elements connected upstream to the holding brake
- Mechanical delay of the holding brake itself
- Generation of the holding torque by the motor

Related topics:

- ▶ [Process when brake is released](#) (📖 667)

9.12.2.6 Motor magnetising time (only with asynchronous motor)



- When an asynchronous motor is used, first the magnetic field required for the holding torque is created (which is already available when a synchronous motor is used) after the controller inhibit is deactivated.
- The motor is internally magnetised through internal feedforward control of the lower speed threshold. The release time set in [C02589/2](#) is considered here.

[9-38] Considering the motor magnetising time taking the PM brake as an example

Related topics:

► [Process when brake is released](#) (667)

9.12.2.7 Actual value monitoring

If an actual value monitoring time > 0 s is selected in [C02593/1](#), the actual speed time monitoring is active.

- The monitoring time starts when the speed setpoint has reached the lower switching threshold and the actual speed is still above this threshold. (see illustration [\[9-41\]](#) in chapter "[Process when brake is closed](#)".)
- If the actual speed is still above the threshold when the monitoring time has expired, the brake will be automatically applied in the automatic brake control mode (mode 12).



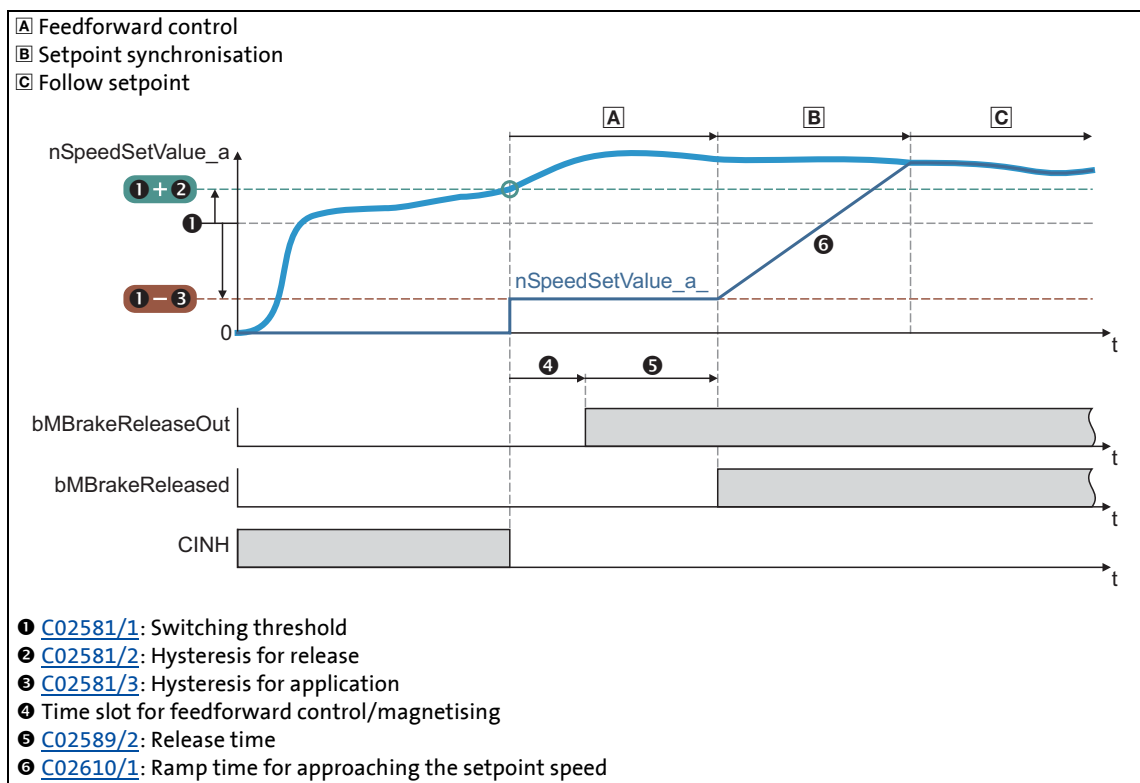
Note!

In the Lenze setting, the actual speed time monitoring is deactivated ([C02593/1](#) = "0 s"), i.e. the brake will only be applied when the actual speed has reached the lower switching threshold.

9.12.3 Process when brake is released

1. The controller inhibit is deactivated.
2. The magnetic field required for the holding torque is created in the motor (is already available when a synchronous machine is used).
3. The *bMBrakeReleaseOut* trigger signal for holding brake switching element is set to TRUE for releasing the brake.
4. After the brake opening time has elapsed:
 - The *bMBrakeReleased* status signal ("brake released") is set to TRUE.
 - In the "[Speed follower](#)" operating mode, the drive synchronises to the already accelerated speed setpoint.
 - In the operating modes with setpoint request via control signal (operating modes "[Homing](#)", "[Manual jog](#)" and "[Positioning](#)"), the ramping process starts after the brake release at 0.
5. After the waiting time set in [C02589/3](#) has additionally expired, the status monitoring starts again (if activated via bit 5 in [C02582](#)).

Time diagram



[9-39] Release holding brake in automatic mode via speed threshold

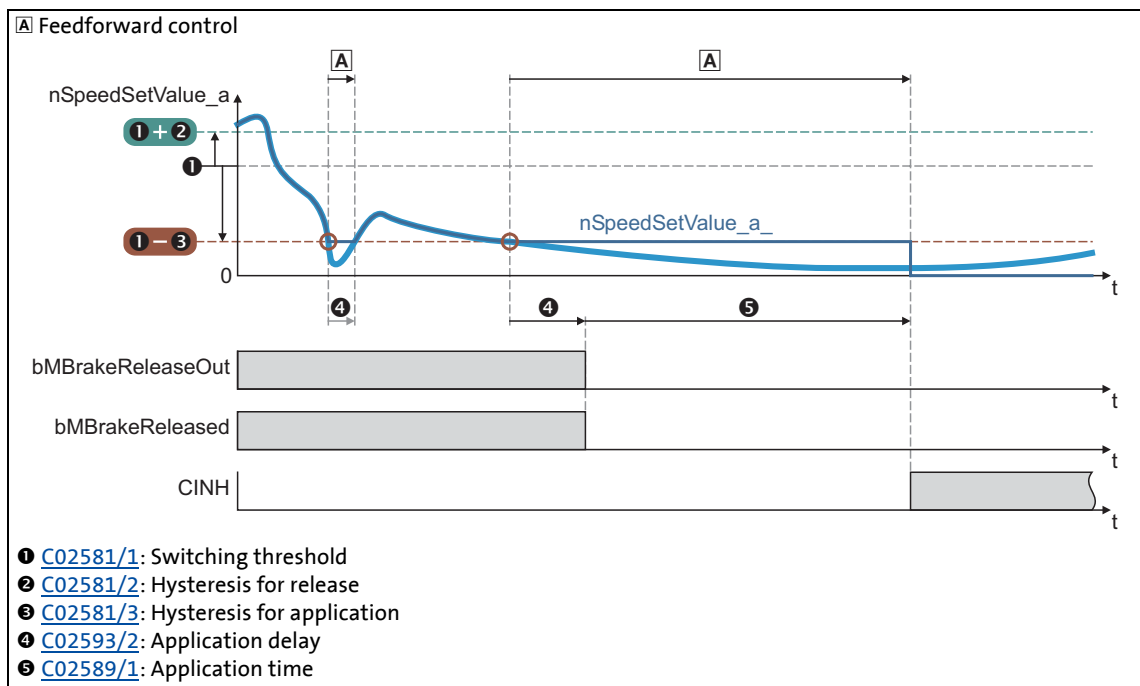
Related topics:

- ▶ [Feedforward control of the motor before release](#) (671)

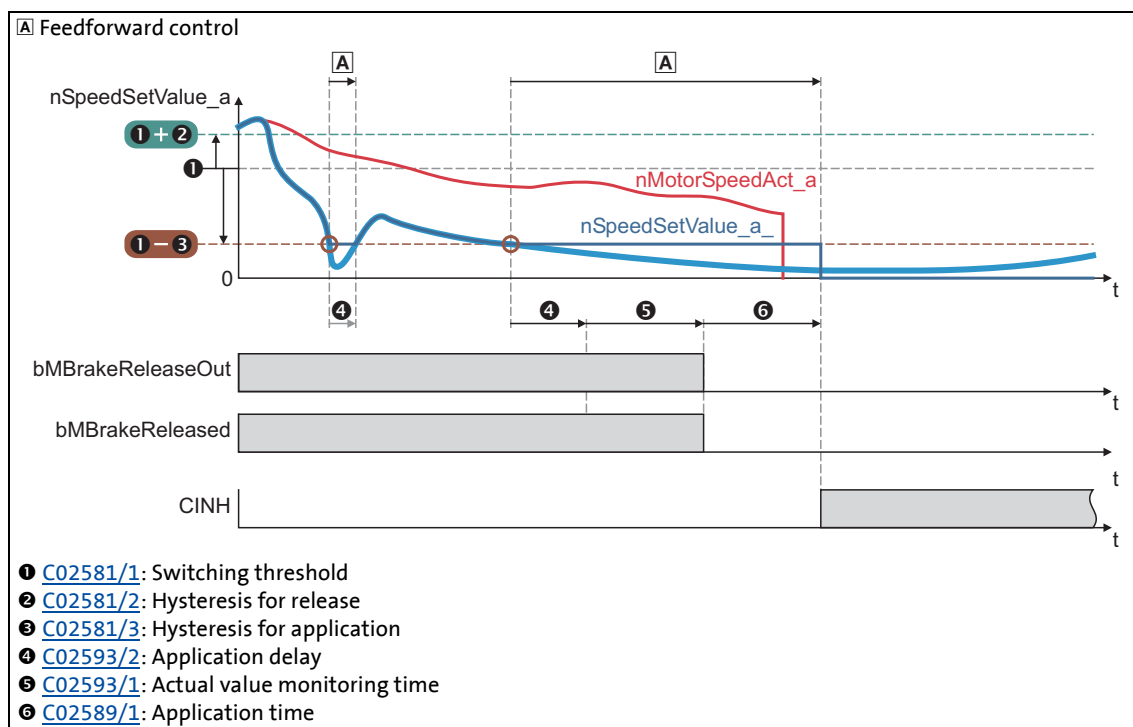
9.12.4 Process when brake is closed

- The motor is decelerated when the setpoint is reduced by the user (e.g. turn down the potentiometer, setpoint selection via CAN).
 - The motor can also be decelerated by the "Quick stop" function or by "DC-injection braking", either directly requested by the user or as response to an error.
- If the speed setpoint and the actual speed have fallen below the lower speed threshold or only the speed setpoint has fallen below the lower speed threshold and the actual value monitoring time has expired:
 - The *bMBrakeReleaseOut* trigger signal for the holding brake switching element is set to FALSE for closing the brake.
 - The *bMBrakeReleased* status signal is reset to FALSE.
 - In the operating modes with setpoint request via control signal (operating modes "[Homing](#)", "[Manual jog](#)" and "[Positioning](#)"), the brake closes depending on the internal state *bBusy* (setpoint generation through active profile generator) of the **Motion Control Kernel**.
 - The brake application time starts to expire.
- After the brake application time has expired, the controller is inhibited.
- After the waiting time set in [C02589/3](#) has additionally expired, the status monitoring starts again (if activated via bit 5 in [C02582](#)).
- In order to prevent the drive from further rotating/accelerating in the event of an error of the feedback contact, controller inhibit is cancelled again and the drive is held at standstill in a speed-controlled manner.

Time diagrams



[9-40] Close holding brake in automatic mode via speed threshold (actual value = setpoint)



[9-41] Close holding brake in automatic mode with actual value monitoring time ([C02593/1](#) > 0 s)

9.12.5 Behaviour in case of pulse inhibit

Setting the pulse inhibit causes a load-controlled coasting of the motor until the pulse is enabled again. In the enabled controller, the pulse can be inhibited e.g. due to a DC overvoltage, DC undervoltage or the "Safe torque off" request.

The brake response to pulse inhibit can be parameterised under [C02582](#).



Stop!

For parameterising the response to pulse inhibit in [C02582](#), the energy conditions of the machine should be evaluated first.

The energy stored in the machine can be considerably higher than the permissible switching energy and thus lead to the destruction of the brake if applied directly!

Activate brake immediately when pulse is inhibited

If bit 1 is set to "0" in [C02582](#) (Lenze setting), the brake will be immediately applied when the pulse is inhibited to avoid damage to the mechanical components.

Especially in the case of hoist drives, immediate engagement of the brake is absolutely necessary for safety reasons if the pulse inhibit function of the drive controller has been activated!



Danger!

This behaviour is valid in (semi) automatic operation when the *bMBrakeRelease* input is set to FALSE.

When the *bMBrakeRelease* input is set to TRUE (supervisor operation) in automatic mode, the brake is not applied at pulse inhibit!

Only activate brake below threshold for brake activation

If bit 1 and bit 3 are set to "1" in [C02582](#), the brake remains released until the lower speed threshold is reached to avoid an excessive wear of the brake.

- The braking action only takes places due to the friction in the load mechanics.
- The brake will not be applied until the motor speed has reached the threshold for brake activation. Hence, the function depends on the signal of the speed encoder.

During uncritical operation (horizontal loading condition), delayed brake application may be required to protect the brake in case of high centrifugal masses.

In case of vertical motion (bit 3 = 0), this function is not active due to safety-related reasons.

Related topics:

- ▶ [Functional settings](#) (📖 661)
- ▶ [Switching thresholds](#) (📖 662)

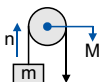
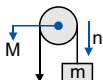
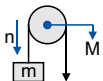
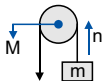
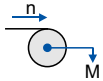
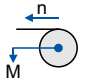
9.12.6 Feedforward control of the motor before release

The motor is precontrolled by selecting the lower speed threshold for applying the brake (control modes without feedback). When the upper speed threshold for brake release is reached, the motor is precontrolled with the for the release time set in [C02589](#) with the lower threshold value before the brake switches to the release mode.

Here, the direction of the feedforward control depends on two conditions:

1. On the settings selected under [C02582](#):
 - Bit 2 = feedforward control inverted (for vertical drives/hoists)
 - Bit 3 = direction of the axis
2. On the sign of the setpoint.

Truth table for the direction of the feedforward control

Setpoint	Direction	Feedforward control	Scheme	Direction	
				Feedforward control value	Start value
$n \geq 0$	vertical/hoist (C02582: Bit 3 = 0)	not inverted (C02582: Bit 2 = 0)		+	+
		inverted (C02582: Bit 2 = 1)		-	+
$n < 0$		not inverted (C02582: Bit 2 = 0)		+	-
		inverted (C02582: Bit 2 = 1)		-	-
$n \geq 0$	horizontal/winding drive (C02582: Bit 3 = 1)	Inversion via bit 2 with horizontal direction not effective		+	+
$n < 0$				-	-

Selection of the feedforward control value

The feedforward control value can be selected via bit 4 in [C02582](#):

- Bit 4 = 0: Automatic selection
 - The torque saved at the last stop is used.
- Bit 4 = 1: Manual selection
 - *bMBrakeStartValue2* = FALSE: The feedforward control value 1 set in [C02581/4](#) is used.
 - *bMBrakeStartValue2* = TRUE: The feedforward control value set in [C02581/5](#) is used.

Additive torque

If the servo control (SC) operating mode has been selected, an additive torque value in [%] can be selected via the *nBrkTorqueAdd_a* input.

Related topics:

- ▶ [Functional settings](#) (📖 661)
- ▶ [Switching thresholds](#) (📖 662)

10 Diagnostics & error management

This chapter provides information on error handling, drive diagnostics, and fault analysis.

10.1 Basics on error handling in the controller

Many of the functions integrated into the controller can

- detect errors and thus protect the device from damage or overload, e.g. short-circuit detection, Ixt overload detection, overtemperature detection, etc.
- detect an operating error by the user, e.g. a missing memory module, a required or missing communication module, etc.
- output a warning signal if desired, e.g. if the speed is too high or too low, etc.

Depending on the importance, the error detection in the device responds very fast (e.g. short-circuit detection < 1 ms) or in a slower cycle (e.g. temperature monitoring approx. 100 ms).

All functions provided with an error detection (e.g. the motor control) supply information to a so-called error handler. The error handler is processed every 1 ms and evaluates all information.

In this evaluation, the so-called status determining error (display in [C00168](#)) and the current error (display in [C00170](#)) are generated, and the controller is caused to take the respective error status (e.g. TroubleQSP).

These two types of error information serve to diagnose errors systematically and contain the following information:

1. The error type (e.g. "Warning")
2. The error subject area (e.g. "CAN generally integrated")
3. The error ID within the error subject area

Together all types of information form the real error number which is unique in the whole device system. ▶ [Structure of the 32-bit error number \(bit coding\)](#) (📘 696)

In addition to the control of the device status by the error handler, a logbook function records the errors and their histories. ▶ [Logbook](#) (📘 682)











Tip!

For many device errors, the error type and hence the response of the controller to the error can be parameterised. ▶ [Setting the error response](#) (📘 691)

10.2

LED status displays

	CAN-RUN
	CAN-ERR
	DRV-RDY
	DRV-ERR
	AB-STATE
	
	
	USER

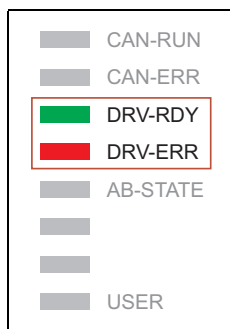
Information on some of the operating states can be quickly obtained via the LED display on the front of the controller.

Labelling	Colour	Description
CAN-RUN	green	CAN bus ok
CAN-ERR	red	CAN bus error
DRV-RDY	green	Standard device ready for operation
DRV-ERR	red	Warning/trouble/fault
AB-STATE	green	Axis bus status
-	-	These LEDs are currently not provided with a function!
-	-	
USER	orange	Starting from version 12.00.00, this LED can be triggered with any digital process signal via the LS_DigitalOutput system block. (400)

Related topics:

- ▶ [Device control \(DCTRL\)](#) (99)
- ▶ [Device state machine and device states](#) (113)
- ▶ [System bus "CAN on board"](#) (749)

10.2.1 LED status displays of the device status



The two LEDs "DRV-RDY" and "DRV-ERR" on the front of the controller are triggered depending on the device status.

The meaning can be seen from the table below.

DRV-RDY	DRV-ERR	Description	Device status (Display in C00137)
OFF	OFF	OFF or initialisation active	Init
	OFF	Safe torque off is active	SafeTorqueOff
	OFF	Device is ready to start	ReadyToSwitchOn
	OFF	Device is switched on	SwitchedOn
	OFF	Motor data identification/operation	OperationEnabled
		The controller is ready to switch on, switched on or the operation is enabled and a warning is indicated.	
		Fault active, quick stop	TroubleQSP
OFF		Fault active	Trouble
OFF		Fault active	Fault
OFF		System fault active	SystemFault
Legend Meaning of the symbols used to describe the LED states:			
	LED is flashing once approx. every 3 seconds (<i>slow flash</i>)		
	LED is flashing once approx. every 1.25 seconds (<i>flash</i>)		
	LED is flashing twice approx. every 1.25 seconds (<i>double flash</i>)		
	LED is blinking every second		
	LED is permanently on		

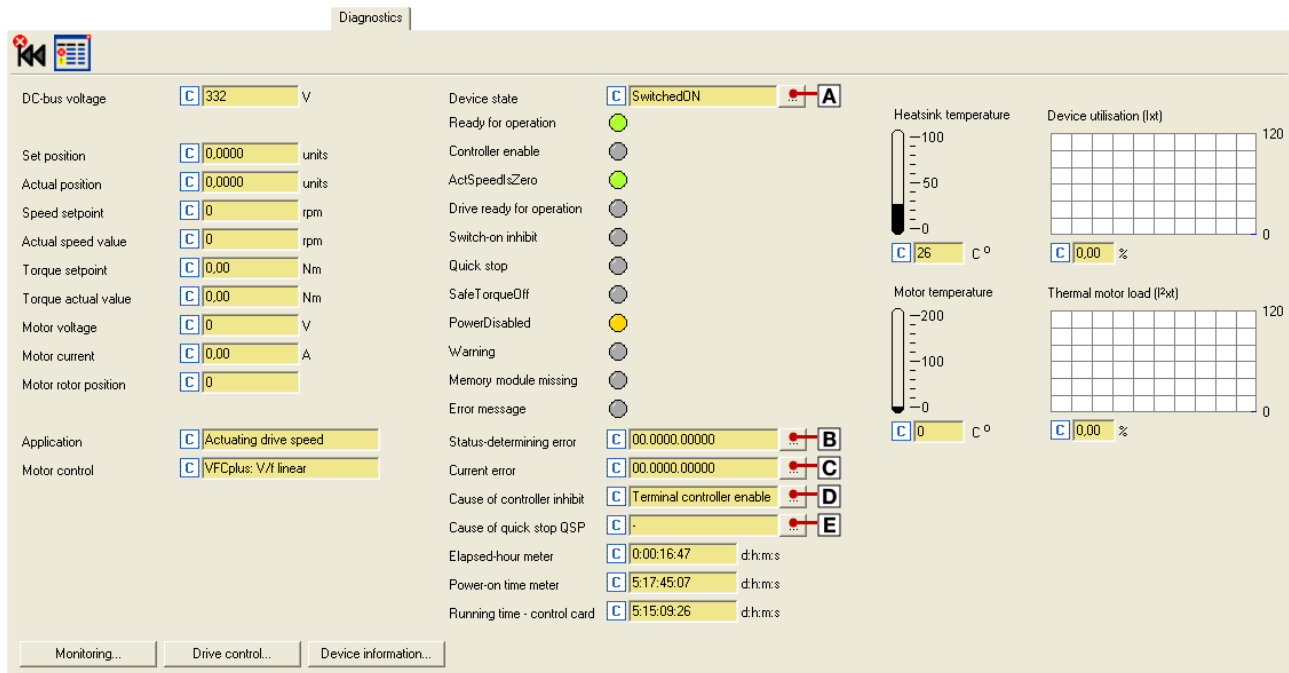
Related topics:

► [Device state machine and device states](#) (113)

10.3 Drive diagnostics with the »Engineer«


When an online connection to the controller has been established, the connected controller can be diagnosed and relevant actual controller states can be displayed in a clearly arranged visualisation using the »Engineer«.

Example: Representation of the diagnostic information in the »Engineer« V2.19



Button	Function
	Acknowledge error message (if the error cause has been eliminated).
	Display the Logbook of the controller. (682)
	[A] Display the internal state machine including the current device status.
	[B] Display details of the status determining error.
	[C] Display details of the current error.
	[D] Display all active sources of a controller inhibit.
	[E] Display all active sources of a quick stop.
Monitoring...	Configure the Monitoring. (689)
Drive control...	Display the bit assignment of the following control-related words: <ul style="list-style-type: none"> • MCI control word (C00136/1) • CAN control word (C00136/2) • Cause of controller inhibit (C00158) • Cause of quick stop (C00159) • Status word (C00150) • Status word 2 (C00155)
Device information...	Display identification data, e.g. firmware information or serial number of individual controller components.

**How to diagnose a drive with the »Engineer«:**

1. In the *Project view*, select the 8400 TopLine controller.
2. Click the  icon or select the **Online→Go online** command to build up an online connection with the controller.
3. Select the **Diagnostics** tab.
 - With an online connection, the **Diagnostics** tab displays current status information about the controller.

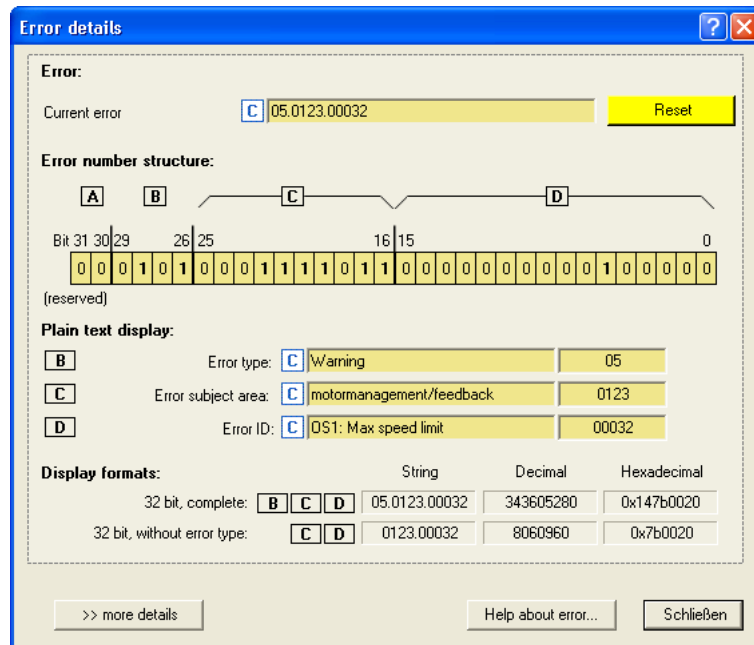
**Tip!**

The online connection to the controller can be established via the following device interfaces:

- CAN interface X1
Diagnostics via the [System bus "CAN on board"](#) (📖 749)
- X6 diagnostic interface
We recommend this diagnostic connection when the X1 CAN interface is used for process communication.

10.3.1 Display details of the error

If you go to the **Diagnostics** tab and click the  button for the status determining or current error, the *Error details* dialog box displays further information on the error:



Error details

Error:

Current error: **C** 05.0123.00032 Reset

Error number structure:

Diagram showing bit fields A, B, C, and D. Bit 31 is reserved. Bit 30 is 0, Bit 29 is 0, Bit 28 is 1, Bit 27 is 0, Bit 26 is 1, Bit 25 is 0, Bit 24 is 0, Bit 23 is 0, Bit 22 is 1, Bit 21 is 1, Bit 20 is 1, Bit 19 is 1, Bit 18 is 0, Bit 17 is 0, Bit 16 is 0, Bit 15 is 0, Bit 14 is 0, Bit 13 is 0, Bit 12 is 0, Bit 11 is 0, Bit 10 is 0, Bit 9 is 0, Bit 8 is 0, Bit 7 is 0, Bit 6 is 0, Bit 5 is 0, Bit 4 is 0, Bit 3 is 0, Bit 2 is 0, Bit 1 is 0, Bit 0 is 0.

Plain text display:

B Error type: **C** Warning 05

C Error subject area: **C** motormanagement/feedback 0123

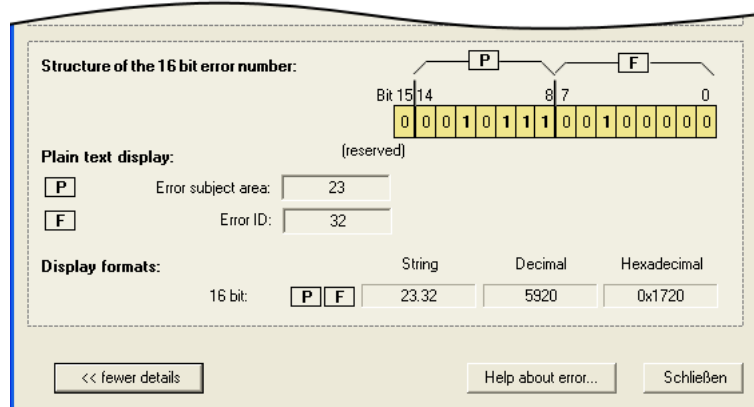
D Error ID: **C** OS1: Max speed limit 00032

Display formats:

	String	Decimal	Hexadecimal
32 bit, complete: B C D	05.0123.00032	343605280	0x147b0020
32 bit, without error type: C D	0123.00032	8060960	0x7b0020

>> more details Help about error... Schließen

- Click the **Help about error...** button to open the online help with information on the error cause and possible remedies.
- The **>> more details** button serves to provide more information about the structure of the 16-bit error number:



Structure of the 16 bit error number:

Diagram showing bit fields P and F. Bit 15 is reserved. Bit 14 is 0, Bit 13 is 0, Bit 12 is 0, Bit 11 is 1, Bit 10 is 1, Bit 9 is 1, Bit 8 is 0, Bit 7 is 0, Bit 6 is 1, Bit 5 is 0, Bit 4 is 0, Bit 3 is 0, Bit 2 is 0, Bit 1 is 0, Bit 0 is 0.

Plain text display:

P Error subject area: 23

F Error ID: 32

Display formats:

	String	Decimal	Hexadecimal
16 bit: P F	23.32	5920	0x1720

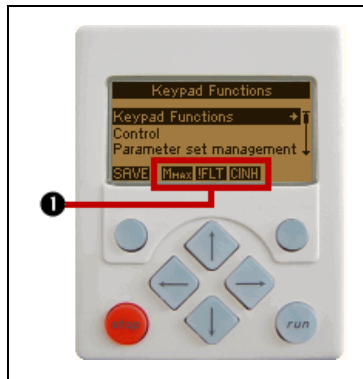
<< fewer details Help about error... Schließen

Related topics:

- ▶ [Structure of the 32-bit error number \(bit coding\)](#) (📖 696)
- ▶ [Structure of the 16 bit error number \(bit coding\)](#) (📖 699)

10.4 Drive diagnostics via keypad/bus system

Keypad display of the controller status



- If the keypad on the front of the controller is connected to the diagnostic interface X6, the status of the controller is shown via different icons on the LCD display in the area ❶.

Icon	Meaning	Note
RDY	Controller is switched on.	► SwitchedOn (📘 119)
RUN	Controller is enabled.	
QSP	Quick stop active	
CINH	Controller is inhibited.	The power outputs are inhibited.
Mmax	Speed controller 1 at the limit.	The drive is torque-controlled.
Imax	Set current limit has been exceeded in motor or generator mode.	
IMP	Pulse inhibit active	The power outputs are inhibited.
!SFLT	System fault active	
IFLT	Fault	► Fault (📘 123)
ITRB	Trouble	► Trouble (📘 122)
!TQSP	TroubleQSP	► TroubleQSP (📘 121)
WRN	Warning is active	

Display parameters

The parameters listed in the following tables serve to query current states and actual values of the controller for diagnostic purposes, e.g. by using the keypad, a bus system or the »Engineer« (with an online connection to the controller).

- These parameters are listed in the »Engineer« parameter list and the keypad in the **Diagnostics** category.
- A detailed description of these parameters can be found in the chapter "[Parameter reference](#)" ([□ 872](#)).

Parameter	Display
C00051	MCTRL: Actual speed value
C00052	Motor voltage
C00053	DC-bus voltage
C00054	Motor current
C00056/1	Torque demand
C00056/2	Actual torque value
C00058	Output frequency
C00061	Heatsink temperature
C00064/1	Device utilisation (lxt)
C00064/2	Device utilisation (lxt) 15s
C00064/3	Device utilisation (lxt) 3 min
C00133	Brake resistor utilisation
C00136/1	MCI control word
C00136/2	CAN control word
C00137	Device status
C00138/1	SYS control signals
C00138/2	MCK control signals
C00138/3	FWM control signals
C00150	Status word
C00158	Cause of controller inhibit
C00159	Cause of quick stop QSP
C00165/1	Status determining error (displayed as a numeric text)
C00165/2	Current error (displayed as a numeric text)
C00168	Status determining error (display of 32-bit number)
C00170	Current error
C00166/1	Error type, status determining
C00166/2	Error subject area, status determining
C00166/3	Error ID, status determining
C00166/4	Error type, current
C00166/5	Error subject area, current
C00166/6	Error ID, current
C00177/1	Switching cycles mains switching
C00177/2	Switching cycles output relay
C00177/3	Stress counter - short circuit
C00177/4	Stress counter - earth fault
C00177/5	Stress meter clamp

Parameter	Display
C00177/6	STO counter after power-on
C00177/7	DigIn CINH counter after power-on
C00177/8	IMP counter after power-on
C00178	Time the controller was enabled (elapsed-hour meter)
C00179	Power-up time (power-on time meter)
C00180/1	Running time - control card
C00180/2	Running time - heatsink fan
C00180/3	Running time - internal fan

Identification data

The parameters listed in the following table belong to the **Identification** category of the »Engineer« parameter list and the keypad and serve to display the identification data of the controller:

Parameter	Display
C00099	Firmware version (as a string)
C00199/1	Device name ► Automatic acceptance of the device name in the »Engineer«
C00200	Firmware product type
C00201/1...6	Firmware of the control card and the power section
C00203/1...9	Product type code of the individual device components
C00204/1...9	Serial numbers of the individual device components

10.5 Logbook

The integrated logbook function of the controller chronologically logs important events within the system and plays an important role for troubleshooting and controller diagnostics.

Events that can be logged

The following events can be logged in the logbook:

- [Error messages of the operating system](#) (📖 696)
- Error messages generated by the application (via [LS_SetError](#))
- Loading/saving of parameter sets, loading of the Lenze setting (*in preparation*)
- Transmitting the firmware to the controller (*in preparation*)
- Switching the controller on/off

Information saved

For each event, the following information is saved in the logbook:

- Type of response to the event (e.g. fault, warning or information)
- Subject area that activated the event (e.g. CAN or USER).
- Event
- Value of power-on time meter
- Selected process values (analog % signals, binary signals)

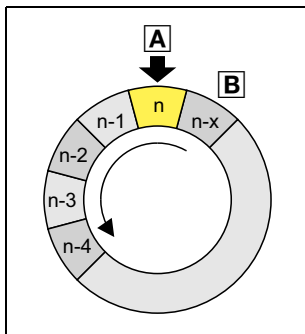
Memory depth

Maximum number of logbook entries:

- 8400 Stateline: 15 logbook entries
- 8400 HighLine/TopLine: 50 logbook entries

10.5.1 Functional description

The structure of the logbook corresponds to a ring buffer:



- As long as free logbook memory is available, the entry is placed in the next free position within the memory (A).
- If all memory units are assigned, the oldest entry (B) is deleted for a new entry.
- The newest entries will always remain available.



Note!

In the event of a supply voltage failure, the logbook is saved and reloaded automatically when the controller is switched on. This ensures that the error history of the device does not get lost. For this reason it is very important to act with caution when deleting the logbook entries.

10.5.2 Filtering logbook entries

The logbook adds new entries to the ring buffer after they have been passed through a parameterisable filter. This filter helps you to exclude certain events from being entered into the logbook which would trigger a certain error response (fault, trouble, warning, information, etc.).

[C00169](#) (bit 1 ... bit 6) includes a bit coded specification of the events which are to be entered into the logbook. In the Lenze setting, all events are entered into the logbook.



Note!

Events with the "No response" setting are not entered into the logbook.

Counter for multiple entries

In order to prevent the ring buffer from overflowing with identical errors with frequent occurrence e.g. during commissioning, identical errors will not lead to new line entries in the configuration of the logbook in the Lenze setting. Instead, one counter will be counted up for this error.

- The time of the error is always the time of its first occurrence. Hence, a new logbook line will only be generated if a new error occurs.
- The error counter can be deactivated by resetting bit 9 in [C00169](#).

10.5.3 Automatic recording of device-internal signals at the time the error occurs

For purposes of error analysis, two optional device-internal digital signals and an analog signal (16 bit) can be recorded at the time the error occurs.

- The digital signals to be recorded are selected in [C00163/1](#) and [C00163/2](#).
 - Scaling of the value recorded: 0 \equiv FALSE; 1 \equiv TRUE
- The analog signal to be recorded is selected in [C00164/1](#).
 - Scaling of the value recorded: 16384 \equiv 100 %

10.5.4 Reading out logbook entries

With an online connection, the existing logbook entries can easily be displayed in the »Engineer«. Alternatively, the logbook entries can also be read out via the corresponding parameters (e.g. using the keypad).



Note!

Reading out the logbook entries is only permissible by one engineering tool at a time!

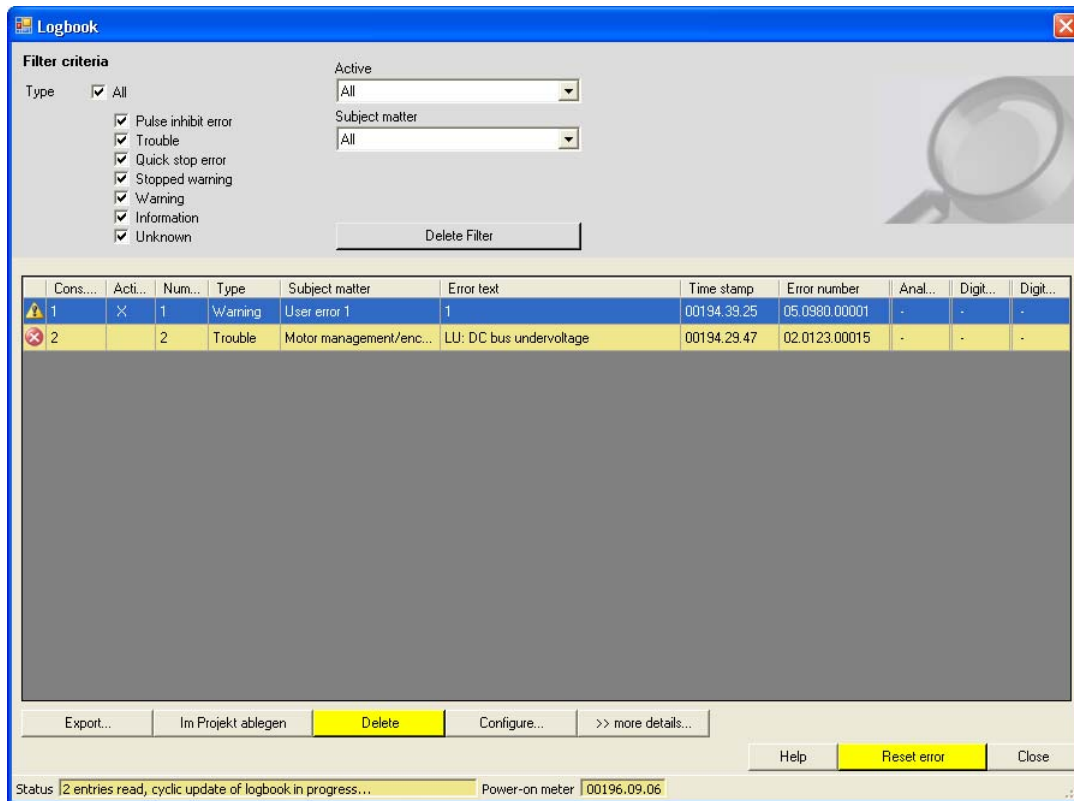
- If the logbook entries are tried to be read out via two engineering tools at the same time, missing lines or a permanent refresh may be caused.
- The parameter interface for reading out the logbook by an external control/visualisation, is available as well. ▶ [Reading out the logbook from an external control/visualisation](#) (p. 687)



How to display logbook entries in the »Engineer«:

1. In the *Project view*, select the 8400 TopLine controller.
2. Click the icon or select the **Online→Go online** command to build up an online connection with the controller.
3. Select the **Diagnostics** tab from the *Workspace*.
4. Click **Logbook**.

Example: Representation of the logbook in the »Engineer« V2.13



Button	Function
Reset filters	Reset set filter criteria to display all available logbook entries.
Export...	Export the entries available in the logbook into a *.log file. ▶ Exporting logbook entries to a file (□ 685)
File in project	File the current logbook in the Engineer project to be able to access it offline, too. ▶ Storing the logbook in the project (□ 686)
Delete	Delete all entries available in the logbook.
Configure...	Open parameterisation dialog for configuring the logbook.
>> more details	Show more details: <ul style="list-style-type: none"> • Analog value 1, digital values 1 & 2 • More output types of the error numbers (32-bit, internal 32-bit and internal 16-bit). • Instead of the >> more details button, the << less details is now displayed via which the details can be hidden again.
Help	Open online help for the logbook.
Reset error	Acknowledge existing error message if the error cause has been eliminated and thus the error is not pending anymore. <ul style="list-style-type: none"> • After the reset (acknowledgement) of the current error, further errors may be pending which must also be reset.
Close	Close the <i>Logbook</i> dialog box again.

10.5.5 Exporting logbook entries to a file



How to export the logbook entries to a file:

1. Click **Export...** in the *Logbook* dialog box.
 - The *Export logbook* dialog box is displayed.
2. Specify the folder, file name, and file type for the file.
3. Click the **Save** button to export the logbook entries into the given file.
 - Hidden logbook entries are not exported, i.e. the filter criteria specified are accounted for during the export.
 - The logbook entries are written to the file in the form of a semicolon separated list.

Structure of the semicolon separated list

The list includes the following information:

- | | |
|------------------|------------------------------|
| 1. Cons. no. | 9. Error number |
| 2. Active | 10. Source - analog value 1 |
| 3. Counter | 11. Analog value 1 |
| 4. Type | 12. Source - digital value 1 |
| 5. Subject area | 13. Digital value 1 |
| 6. Error text | 14. Source - digital value 2 |
| 7. Time stamp | 15. Digital value 2 |
| 8. Relative time | |

10.5.6 Storing the logbook in the project

If you want to display the currently available logbook entries at a later date in offline mode, i.e. without a connection to the controller, you can store the current logbook in the project.



How to store the logbook in the project:

Go to the *Logbook* dialog box and click the **File in project** button.

- The logbook with all the entries uploaded up to now is stored in the Engineer project independent of the set filter criteria.
- A logbook of the same device already stored before will be overwritten without querying the user.
- The filter settings are not stored in the project.
- When a logbook is filed in the project, the logbook can also be opened in offline mode via the **Logbook** button on the **Diagnostics** tab.



Note!

Storing the logbook changes the project.

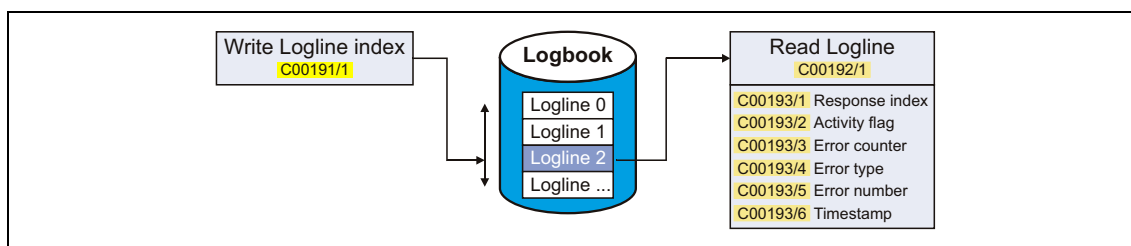
- When the project is closed, you are asked to save the changed project.
- Only if the changed project is saved, the new logbook entries stored in the project remain stored.

10.5.7 Reading out the logbook from an external control/visualisation

This function extension is available from version 12.00.00!

The parameters described in the following provide a second interface via which an external control or visualisation can exclusively access the logbook and read out logbook contents. Logbook contents can even be read out via this additional interface if the logbook is read out by the »Engineer« or »EASY Starter« at the same time.

Structure of the interface



- The line index of the logbook entry to be read out has to be set in [C00191/1](#).
- Then the logbook entry addressed is stored as "OCTET STRING" in [C00192/1](#).
 - Via this display parameter, the logbook entry can be read out by the control.
 - The "OCTET STRING" has a length of 8 double words of 4 successive bytes (= 32 bytes), starting with byte 0 in each case:

OCTET STRING	Byte 0	Byte 1	Byte 2	Byte 3
DWORD 0	Reserved	Reserved	Response index	Reserved
DWORD 1	Error activity flag	Error counter	Reserved	Reserved
DWORD 2	32-bit error number A Reserved B Error type C Error subject area D Error ID			
DWORD 3	Time in [s] during which the power was switched on (power-on time meter).			
DWORD 4	Reserved	Reserved	Reserved	Reserved
DWORD 5	Source - analog value 1	Reserved	Analog value 1 (scaling: 16384 ≙ 100 %)	
DWORD 6	Source - digital value 1	Reserved	Digital value 1	Reserved
DWORD 7	Source - digital value 2	Reserved	Digital value 2	Reserved

- Additionally, a read access to different individual elements of the logbook entry addressed can be executed via the subcodes of [C00193](#). These parameters have a uniform data format (32 bits) and represent the most important part of the logbook data:

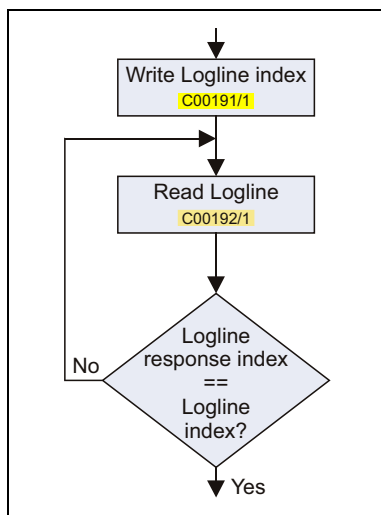
Parameter	Display
C00193/1	Response index, reference to the index requested (C00191/1)
C00193/2	Error activity flag (0 = error not active; 1 = error active)
C00193/3	Error counter (0 ... 255) <ul style="list-style-type: none"> • This information depends on the logbook configuration. In the Lenze setting the logbook configured so that identical errors do not produce a new line entry, but a counter is incremented for this error.
C00193/4	Error type (bits 26 ... 29 of the 32-bit error number)
C00193/5	Error subject area + error ID (bits 0 ... 25 of the 32-bit error number)
C00193/6	Time in [s] during which the power was switched on (power-on time meter).



Note!

- In the case of a simultaneous read access to the logbook entry ([C00192/1](#)) and its individual elements ([C00193/x](#)), the line index in [C00191/1](#) must only be reset by the control after the read process is fully completed. Otherwise the data read are inconsistent.
- Depending on the device version, the maximum number of logbook entries can vary:
 - 8400 StateLine: 15 logbook entries
 - 8400 HighLine/TopLine: 50 logbook entries

Basic workflow



- The logbook can be read out by an external control or visualisation via the procedure shown on the left.
- The "Response index" query ensures that the logbook entry read really corresponds to the logbook entry requested.






Related topics:

- ▶ [Structure of the 32-bit error number \(bit coding\)](#)

10.6 Monitoring

The controller is provided with various monitoring functions which protect the drive against impermissible operating conditions.

- If a monitoring function responds,
 - an entry will be made into the [Logbook](#) of the controller,
 - the response (TroubleQSP, Warning, Fault, etc.) set for this monitoring function will be triggered,
 - the status of the internal device control changes according to the selected response, controller inhibit is set, and the "DRV- ERR" LED on the front of the controller goes on:

Response	Entry in the logbook	Display in C00168	Disable voltage	Controller inhibit	Acknowledgement required	"DRV-ERR" LED
None						OFF
Fault	☑	☑	☑	☑	☑	
Trouble	☑	☑	☑	☑		
TroubleQSP	☑	☑			☑	
WarningLocked	☑	☑			☑	
Warning	☑	☑				
Information	☑	☑				OFF
System fault	☑	☑	☑	☑	Mains switching is required!	

Related topics:

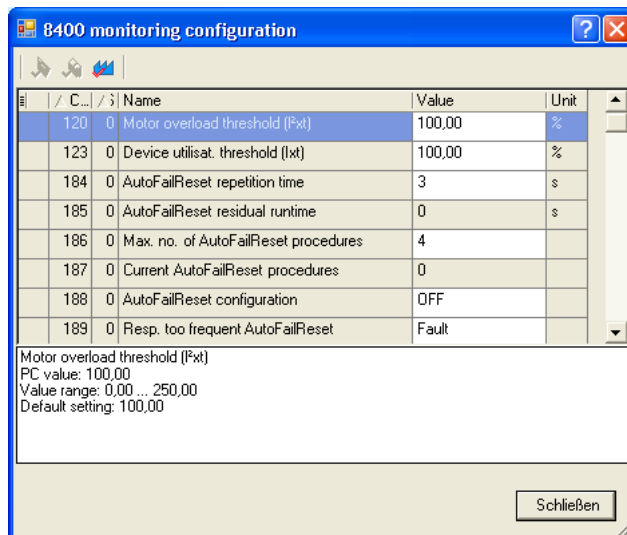
- ▶ [LED status displays of the device status](#) (📖 675)
- ▶ [Device state machine and device states](#) (📖 113)
- ▶ [Device overload monitoring \(Ixt\)](#) (📖 293)
- ▶ [Motor load monitoring \(I2xt\)](#) (📖 294)
- ▶ [Motor temperature monitoring \(PTC\)](#) (📖 297)
- ▶ [Brake resistor monitoring \(I2xt\)](#) (📖 298)
- ▶ [Motor phase failure monitoring](#) (📖 300)
- ▶ [Mains phase failure monitoring](#) (📖 303)
- ▶ [Maximum current monitoring](#) (📖 303)
- ▶ [Maximum torque monitoring](#) (📖 304)
- ▶ [Resolver/multi-encoder open-circuit monitoring](#) (📖 369)
- ▶ [Open-circuit monitoring HTL encoder](#) (📖 370)
- ▶ [Motor temperature monitoring \(KTY\)](#) (📖 373)

10.6.1 Monitoring configuration



How to configure the monitoring functions using the »Engineer«:

1. In the *Project view*, select the 8400 TopLine controller.
2. Select the **Diagnostics** tab from the *Workspace*.
3. Click the **Monitoring...** button.
 - The *8400 monitoring configuration* dialog box is displayed via which the desired settings can be made:



Related topics:

- [Setting the error response](#) (691)

10.6.2 Setting the error response

When a monitoring function responds, the response set for this monitoring function (TroubleQSP, Warning, Fault, etc.) will be triggered.

- For many monitoring functions the response can be individually parameterised via parameters.



Tip!

The table in the chapter "[Short overview \(A-Z\)](#)" contains the error messages for which the response can be set. ([702](#))

Warning thresholds

Some of the monitoring functions are activated if a defined warning threshold (e.g. temperature) has been exceeded.

- The corresponding preset threshold values can be changed via the following parameters:

Parameter	Info
C00120	Setting of motor overload (I ² xt)
C00123	Device utilisat. threshold (Ixt)
C00572	Brake resistor overload threshold
C00599	Motor phase failure threshold

10.6.3 AutoFailReset function

The AutoFailReset function serves to automatically reset the latching "Fault" and "TroubleQSP" errors as well as the latching "WarningLocked" warning.

The "latching" term means that the effect on the controller remains active even after the error cause has been removed.

To reset latching errors and warnings, the following options are available:

- Manual reset
 - with device command [C00002/19](#) (activated by Low-High edge)
 - by a Low-High edge at the *bResetFail* input of the [LS DriveInterface](#) (the "FailReset" control bit in the control word must be parameterised with a value of "1").
- Automatic reset
 - using the AutoFailReset function.

Overview of the relevant parameters

Parameter	Info
C00184	Repetition time of the error reset processes
C00185	Time left until the next error reset process
C00186	Max. number of permissible <u>unsuccessful</u> error reset processes <ul style="list-style-type: none"> • When the number set is reached, the response parameterised in C00189 is executed.
C00187	Current number of <u>unsuccessful</u> error reset processes carried out
C00188	Configuration of the AutoFailReset function <ul style="list-style-type: none"> • 0: Off • 1: Fault + TroubleQSP • 2: WarningLocked • 3: All locking
C00189	Response after max. number of <u>unsuccessful</u> error reset processes has been reached
Highlighted in grey = display parameter	

10.7 Maloperation of the drive

Maloperation	Cause	Remedy
Motor does not rotate	DC-bus voltage is too low <ul style="list-style-type: none"> Red LED is blinking every 1 s Display in the keypad: LU 	Check mains voltage
	Controller is inhibited <ul style="list-style-type: none"> Green LED is blinking Display in the keypad: CINH 	Deactivate controller inhibit <ul style="list-style-type: none"> Note: Controller inhibit can be set via several sources ! C00158 displays all active sources for controller inhibit.
	Automatic start is inhibited (Bit 0 in C00142 = 1)	LOW/HIGH edge at RFR If required, correct starting condition with C00142
	DC-injection braking (DCB) is active	Deactivate DC injection brake
	Mechanical motor brake is not released	Release mechanical motor brake manually or electrically
	Quick stop (QSP) is active <ul style="list-style-type: none"> Display in the keypad: IMP 	Deactivate quick stop <ul style="list-style-type: none"> Note: Quick stop can be set via several sources! C00159 displays all active sources for quick stop.
	Setpoint = 0	Select setpoint
	JOG frequency = 0 at activated JOG setpoint	Set JOG setpoint in C00039/1...15
	Fault active	Clear fault
	With C00006 = 4, "SLVC: Vector control" has been set, but no motor parameter identification has been carried out.	Execute automatic motor parameter identification with the C00002/23 device command
	Assignment of several mutually exclusive functions with a signal source in C00701	Correct configuration in C00701
Motor rotates irregularly	Motor cable is defective	Check motor cable
	Maximum motor current in motor or generator mode is set too low	Adjust settings to the application: C00022 : I _{max} in motor mode C00023 : I _{max} in generator mode
	Motor is underexcited or overexcited	Check parameterisation: C00006 : Motor control C00015 : VFC: V/f base frequency C00016 : VFC: V _{min} boost
	Rated motor data (stator resistance, speed, current, frequency, voltage) and cos φ and/or magnetising inductance is not adapted to the motor data	Execute automatic motor parameter identification with the C00002/23 device command - or - Adjust motor parameters manually: C00084 : Motor stator resistance C00087 : Rated motor speed C00088 : Rated motor current C00089 : Rated motor frequency C00090 : Rated motor voltage C00091 : Motor cosine phi C00092 : Motor magnetising inductance
	Motor windings are wired incorrectly	Reverse from star connection to delta connection

Maloperation	Cause	Remedy
Motor consumes too much current	V_{\min} boost has been selected too high	Correct setting with C00016
	V/f base frequency has been selected too low	Correct setting with C00015
	Rated motor data (stator resistance, speed, current, frequency, voltage) and $\cos \varphi$ and/or magnetising inductance is not adapted to the motor data	Execute automatic motor parameter identification with the C00002/23 device command - or - Adjust motor parameters manually: C00084 : Motor stator resistance C00087 : Rated motor speed C00088 : Rated motor current C00089 : Rated motor frequency C00090 : Rated motor voltage C00091 : Motor cosine phi C00092 : Motor magnetising inductance
Motor parameter identification is aborted with error LP1	Motor is too small compared to the rated device power ($>1 : 3$)	Use device with lower rated power
	DC injection brake (DCB) is active via terminal	Deactivate DC injection brake
Drive behaviour with vector control is not satisfactory	different	Optimise or manually adapt vector control
		Execute automatic motor parameter identification with the C00002/23 device command
Torque dip in field weakening range or motor stalling when being operated in the field weakening range	Motor is overloaded	Check motor load
	Motor windings are wired incorrectly	Reverse from star connection to delta connection
	V/f reference point is set too high	Correct setting with C00015
	Override point of field weakening is set too low	Correct setting with C00080
An asynchronous motor with feedback rotates without control and with too low speed	<p>Motor phases have been interchanged</p> <ul style="list-style-type: none"> • Thus the rotating field of the motor is not identical anymore with the rotating field of the feedback system. • Therefore, the drive shows the following behaviour if V/f characteristic control (C00006 = 7) is performed: <ul style="list-style-type: none"> • The motor rotates faster than the speed setpoint by the value set in C00074. • After the controller has been enabled, the controller will not stop if the speed setpoint = 0 or a quick stop (QSP) occurs. • Among other things, the final motor current depends on the value set for the V_{\min} boost and may rise up to I_{\max} which can trigger the "oC5: Ixt overload" fault message. 	<p>Check the phase position of the motor cable</p> <p>If possible: Actuate the motor with deactivated feedback (C00006 = 6) and check direction of rotation of the motor</p>
Motor phase (LP1) monitoring does not respond if the motor phases are interrupted	Monitoring is not active (C00597 = 0)	Activate monitoring (C00597 = 1)

10.8

Operation without mains supply

**Note!**

Observe the following restrictions for operation without mains supply:

Safety state

Controllers of the 8400 series can be optionally equipped with the integrated "Safe torque off (STO)" safety system.

- **Up to and including version 13.xx.xx, the following applies:**

If merely the external 24-V supply of the controller is switched on, the "Safe torque off" status in [C00137](#) (bit 10) will not be updated.

- **From version 14.00.00 the following applies:**

If merely the external 24-V supply of the controller is switched on, the "Safe torque off" status in [C00137](#) (bit 10) will be updated.

Fan monitoring functions

The fan monitoring functions are only active if the mains supply is switched on.

The following display parameters have a value of "0" if the mains supply is switched off and the external 24 V supply of the controller is switched on:

Parameter	Info
C00050	MCTRL: Speed setpoint
C00051	MCTRL: Actual speed value
C00052	Motor voltage
C00053	DC-bus voltage
C00054	Motor current
C00058	Output frequency
C00061	Heatsink temperature
C00064/1...3	Device utilisation (I _{xt})
C00066	Thermal motor load (I ² _{xt})
C00177	Switching cycles
C00725	Current switching frequency

10.9 Error messages of the operating system

This chapter describes all error messages of the controller operating system and possible causes & remedies.

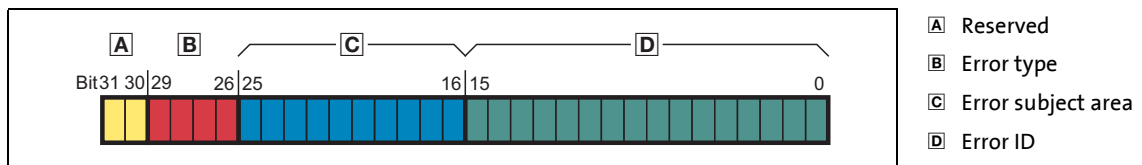


Tip!

Each error message is also saved to the logbook in chronological order. ▶ [Logbook](#) (📖 682)

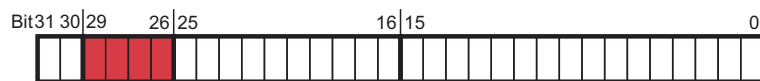
10.9.1 Structure of the 32-bit error number (bit coding)

If an error occurs in the controller, the internal fault memory saves a 32-bit value which contains the following information:



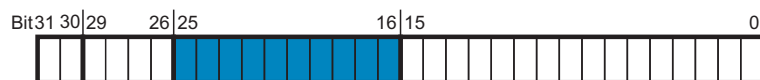
[10-1] Structure of the error number

- Display parameter: [C00168](#)
 - From version 13.00.00: [C00162/1](#) additionally displays the 32-bit error number without error type, i.e. this error number only contains the error subject area and the error ID (bit 0 ... bit 25).
- The [LS DriveInterface](#) system block shows the 32-bit error number at the outputs *wStateDetermFailNoLow* (Low Word) and *wStateDetermFailNoHigh* (High Word).
 - If the "Use 16BitFailNo." option is activated in [C00148](#) (bit 15 = "1"), the [LS DriveInterface](#) system block shows the short 16-bit error number at the output *wStateDetermFailNoLow*, and the value "0" at the output *wStateDetermFailNoHigh* (see the following chapter).
- For the sake of legibility, the error number in the logbook and in [C00165](#) is displayed with the following syntax:
[Error type].[Error subject area no.].[Error ID]

Error type

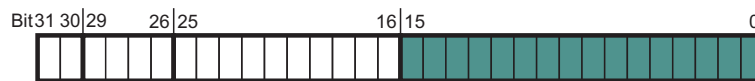
The error type gives information about the behaviour/response of the controller to the error. The error type for some device errors can also be parameterised.

Bit 29	Bit 28	Bit 27	Bit 26	Meaning
0	0	0	0	0: No response
0	0	0	1	1: Fault
0	0	1	0	2: Trouble
0	0	1	1	3: TroubleQSP
0	1	0	0	4: WarningLocked
0	1	0	1	5: Warning
0	1	1	0	6: Information

Error subject area

The error subject area indicates the internal "function unit" of the controller in which the error has occurred:

Error subject area		Assigned errors	Remedy possible by user?
No.	Name		
111	Supply voltage	Errors that occur in connection with the supply voltage of the device.	Yes
119	Temperature	Errors that occur for temperature reasons.	Yes
123	Motor management / encoder	Errors that occur within the motor control or encoder evaluation.	Yes
125	Analog I/O integrated	Errors that occur in connection with the analog inputs and outputs.	Yes
126	Axis bus	Errors that occur in connection with the axis bus.	Yes
127	Extension module slot 1	Errors that are reported by the extension module, and communication errors to the plugged-in extension module.	Yes if it is a fieldbus error.
131	CAN integrated (general)	Errors related to general CAN functions.	Yes
135	CAN process data object (PDO)	Errors that are explicitly only related to the CAN-PDO (process data objects).	Yes
140	Device configuration	Errors that occur due to incompatibilities of the plugged-in individual components (fieldbus module, safety module, et al.).	Yes if the error relates to a module plugged-in by the user.
144	Parameter set	Errors that occur in connection with the parameter set or the parameter set memory (memory module).	Yes if the error relates to a missing or incompatible memory module.
145	Device firmware (internal error)	Internal error of the device firmware.	No
184	MotionControlKernel	Errors that occur within the MotionControl basic functions (e.g. profile generation, brake control, positioning).	Yes
400	Defective device hardware	Errors that occur due to defective device hardware.	No
444	Fieldbus	Errors that occur in connection with fieldbus communication.	Yes
980 ... 983	User error 1 ... User error 4	Errors generated by the user (by the application) via the LS_SetError_1 system block.	Yes
984 ... 987	User error 5 ... User error 8	Errors generated by the user (by the application) via the LS_SetError_2 system block.	Yes

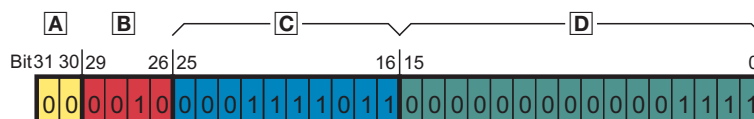
Error ID

16-bit value (0 ... 65535) for error identification within the error subject area.

Example for bit coding of the error number

[C00168](#) displays the internal error number "142278671".

- This decimal value corresponds to the following bit sequence:

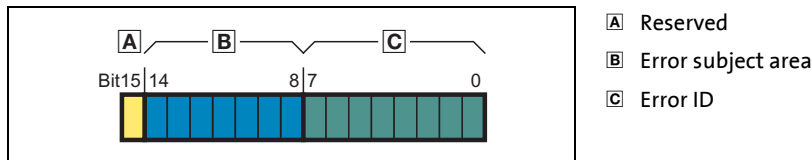


Assignment	Information	Meaning in the example
	Reserved	-
	Error type	2: Trouble
	Error subject area	123: Motor management / encoder
	Error ID	15: " LU: DC bus undervoltage "

- Thus, error number "142278671" means:
A DC bus undervoltage has been detected in the "Motor management / encoder" subject area.
The error response is a "Fault".

10.9.2 Structure of the 16 bit error number (bit coding)

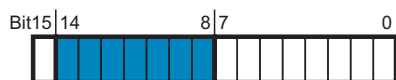
In addition to the 32-bit error number, a 16-bit error number is generated if an error occurs. It consists of the following information:



[10-2] Structure of the error number

- Display parameter: [C00160](#)
- The [LS_DriveInterface](#) system block shows the 16-bit error number at the output *wStateDetermFailNoShort*.
- If the "Use 16BitFailNo." option is activated in [C00148](#) (bit 15 = "1"), the [LS_DriveInterface](#) system block also shows the short 16-bit error number at the output *wStateDetermFailNoLow* (Low Word of the 32-bit error number).
 - The output *wStateDetermFailNoHigh* (High Word of the 32-bit error number) in this case is "0".
 - Advantage: The bus transfer of the error numbers is possible via a data word without changing the interconnection of the technology application.
- For the sake of legibility, the 16-bit error number in the logbook is displayed with the following syntax::
[Error subject area no.].[Error ID]

Error subject area



The error subject area indicates the internal "function unit" of the controller in which the error has occurred.



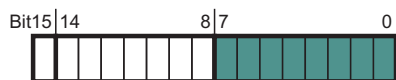
Note!

Due to the smaller value range (0 ...127), the number assignment to the error subject area differs from the 32-bit error number.

Error subject area		Assigned errors	Remedy possible by user?
No.	Name		
11	Supply voltage	Errors that occur in connection with the supply voltage of the device.	Yes
19	Temperature	Errors that occur for temperature reasons.	Yes
23	Motor management / encoder	Errors that occur within the motor control or encoder evaluation.	Yes
25	Analog I/O integrated	Errors that occur in connection with the analog inputs and outputs.	Yes
26	Defective device hardware	Errors that occur due to defective device hardware.	No
27	Extension module slot 1	Errors that are reported by the extension module, and communication errors to the plugged-in extension module.	Yes if it is a fieldbus error.
31	CAN integrated (general)	Errors related to general CAN functions.	Yes
35	CAN process data object (PDO)	Errors that are explicitly only related to the CAN-PDO (process data objects).	Yes

Error subject area		Assigned errors	Remedy possible by user?
No.	Name		
40	Device configuration	Errors that occur due to incompatibilities of the plugged-in individual components (fieldbus module, safety module, et al.).	Yes if the error relates to a module plugged-in by the user.
44	Parameter set	Errors that occur in connection with the parameter set or the parameter set memory (memory module).	Yes if the error relates to a missing or incompatible memory module.
45	Device firmware (internal error)	Internal error of the device firmware.	No
54	Fieldbus	Errors that occur in connection with fieldbus communication.	Yes
84	MotionControlKernel	Errors that occur within the MotionControl basic functions (e.g. profile generation, brake control, positioning).	Yes
100 ... 103	User error 1 ... User error 4	Errors generated by the user (by the application) via the LS_SetError_1 system block.	Yes
104 ... 107	User error 5 ... User error 8	Errors generated by the user (by the application) via the LS_SetError_2 system block.	Yes

Error ID



8-bit value (0 ... 255) for error identification within the error subject area.



Tip!

All possible 16-bit error numbers are listed in the table "[Short overview \(A-Z\)](#)" in the second column. ([book 702](#))

10.9.3

Reset error message

An error message with the response "Fault", "Trouble", "TroubleQSP" or "Warning locked" must be explicitly reset (acknowledged) after the cause of the error has been eliminated.



To reset (acknowledge) a pending error message, execute device command [C00002/19](#) = "1".



Tip!

When an online connection to the controller has been established, use the **Diagnostics** tab of »Engineer« and click **Reset error** to reset a pending error message.

10.9.4 Export error texts

All error texts of the controller can be exported into a text file (*.txt) for further processing.

- The error text is preceded with the corresponding 32-bit error number (no error type) and the 16-bit error number, both as decimal number.
- If there is no corresponding 16-bit error number for a 32-bit error number, the field remains empty.

Example

Output of the German and English error texts:

32-BitError	16-BitError	DE-de	EN-en
0	0	No error	No error
111	11	Versorgungsspannung	Supply voltage
119 / 19			
12323 : Motor management / encoder			
125	25	E/A integriert	I/O integrated
...			
26214416	6672	dH10: Lüfterausfall	dH10: Fan failure
26214505	6761	dH69: Abgleichdatenfehler	dH69: Adjustment fault



How to export the error texts into a text file:

1. Go to the *Project view* in the *Context menu* of the 8400 TopLine controller and execute the **Export error texts...** command.
2. Define the following options in the *Export error texts* dialog box:
 - Output file and memory location
 - Languages to be exported (German/English/French)
 - Device/module to be exported
 - Separator (tabulator or semicolon)
 - Font (UTF8, standard font or ASCII)
3. Click **OK** to start the export.
 - After the export, a message appears indicating whether the export was successful.



Tip!

From version 13.00.00, the 32-bit number of the state-determining error is displayed in [C00162/1](#) without error type.

If, for instance, the error texts are stored in a master control or on an operator panel, the error text to be displayed can be detected by reading the [C00162/1](#) code.

10.9.5 Short overview (A-Z)

The table below contains all error messages of the controller operating system in alphabetical order.

**Note!**

For the sake of legibility, the [Logbook](#) and [C00165](#) display the 32-bit error number with the following syntax:

[Error type].[Error subject area no.].[Error ID]

In this documentation, "xx", a wildcard, stands for the error type since it is configurable for many error messages.

**Tip!**

If you click the cross-reference in the first column, "Error number", you will reach the detailed description of the respective error message in the following chapter "[Cause & possible remedies](#)". (🔍 705)

Error number			Display in	Error message	Response (Lenze setting)	can be set in	CAN Emergency Error Code
32 bits	16 bits _{hex}	16 bits _{dec}	C00162/1				
▶ xx.0126.00001	0x1a01	6657	8257537	Ab01: Axis bus timeout	No Reaction	C00591/1	
▶ xx.0126.00002	0x1a02	6658	8257538	Ab02: Axis bus IO error	No Reaction	C00591/2	
▶ xx.0125.00001	0x1901	6401	8192001	An01: AIN1_I < 4 mA	TroubleQuickStop	C00598/1	0xF000
▶ xx.0125.00002	0x1902	6402	8192002	An02: AIN2_I < 4 mA	TroubleQuickStop	C00598/2	0xF000
▶ xx.0131.00006	0x1f06	7942	8585222	CA06: CAN CRC error	No Reaction	C00592/1	0x8000
▶ xx.0131.00007	0x1f07	7943	8585223	CA07: CAN bus warn	No Reaction	C00592/3	0x8000
▶ xx.0131.00008	0x1f08	7944	8585224	CA08: CAN Bus Stopped	No Reaction	C00592/4	0x8000
▶ xx.0131.00011	0x1f0b	7947	8585227	CA0b: CAN HeartBeatEvent	No Reaction	C00592/5	0x8130
▶ xx.0131.00015	0x1f0f	7951	8585231	CA0F: CAN control word	Fault	C00594/1	0xF000
▶ xx.0127.00002	0x1b02	6914	8323074	CE04: MCI communication error	No Reaction	C01501/1	0x7000
▶ xx.0127.00015	0x1b0f	6927	8323087	CE0F: MCI control word	Fault	C00594/2	0xF000
▶ xx.0135.00001	0x2301	8961	8847361	CE1: CAN RPDO1	No Reaction	C00593/1	0x8100
▶ xx.0135.00002	0x2302	8962	8847362	CE2: CAN RPDO2	No Reaction	C00593/2	0x8100
▶ xx.0135.00003	0x2303	8963	8847363	CE3: CAN RPDO3	No Reaction	C00593/3	0x8100
▶ xx.0131.00000	0x1f00	7936	8585216	CE4: CAN Bus Off	No Reaction	C00592/2	0x8000
▶ xx.0140.00013	0x280d	10253	9175053	CI01: Module missing/incompatible	No Reaction	C01501/2	0x7000
▶ xx.0184.00001	0x5401	21505	12058625	Ck01: Pos. HW limit switch	TroubleQuickStop	C00595/1	0x8600
▶ xx.0184.00002	0x5402	21506	12058626	Ck02: Neg. HW limit switch	TroubleQuickStop	C00595/2	0x8600
▶ xx.0184.00007	0x5407	21511	12058631	Ck03: Pos. SW limit position	TroubleQuickStop	C00595/3	0x8600
▶ xx.0184.00008	0x5408	21512	12058632	Ck04: Neg. SW limit position	TroubleQuickStop	C00595/4	0x8600
▶ xx.0184.00153	0x5499	21657	12058777	Ck05: Error following error 1	Warning	C00595/5	0x8611
▶ xx.0184.00154	0x549a	21658	12058778	Ck06: Contouring error 2	Warning	C00595/6	0x8611
▶ xx.0184.00155	0x549b	21659	12058779	Ck07: Travel range limit exceeded	TroubleQuickStop	C00595/7	0x8612
▶ xx.0184.00156	0x549c	21660	12058780	Ck08: Home position unknown	WarningLocked	C00595/8	0x8612
▶ xx.0184.08005	0x54cd	21709	12066629	Ck09: Invalid positioning mode	WarningLocked	C00595/9	0x8600
▶ xx.0184.08007	0x54cf	21711	12066631	Ck10: Implausible profile data	WarningLocked	C00595/10	0x8600
▶ xx.0184.08009	0x54d1	21713	12066633	Ck11: Invalid operating mode	Warning	C00595/11	0x8600
▶ xx.0184.08014	0x54d6	21718	12066638	Ck12: Invalid profile no.	WarningLocked	C00595/12	0x8600
▶ xx.0184.08015	0x54d7	21719	12066639	Ck13: Error FB MCKCtrlInterface	Warning	C00595/13	0x8600
▶ xx.0184.00015	0x540f	21519	12058639	Ck14: Target position beyond SW limit position	WarningLocked	C00595/14	0x8600
▶ xx.0184.00005	0x5405	21509	12058629	Ck15: Error status sign. brake	TroubleQuickStop	-	0x8600

Error number			Display in C00162/1	Error message	Response (Lenze setting)	can be set in	CAN Emergency Error Code
	32 bits	16 bits _{hex}	16 bits _{dec}				
▶ xx.0184.00064	0x5440	21568	12058688	Ck16: Time overflow manual control	Fault	-	
▶ xx.0135.00004	0x2304	8964	8847364	CP04: CAN RPDO4	No Reaction	C00593/4	0x8100
▶ xx.0145.00035	0x2d23	11555	9502755	dF10: AutoTrip Reset	Fault	C00189	0xF000
▶ xx.0145.00014	0x2d0e	11534	9502734	dF14: SW/HW invalid	Fault	-	
▶ xx.0145.00015	0x2d0f	11535	9502735	dF15: DCCOM CU2 error	Fault	-	
▶ xx.0145.00024	0x2d18	11544	9502744	dF18: BU RCOM error	Fault	-	0x6100
▶ xx.0145.00033	0x2d21	11553	9502753	dF21: BU Watchdog	Fault	-	0x6100
▶ xx.0145.00034	0x2d22	11554	9502754	dF22: CU watchdog	Fault	-	0x6100
▶ xx.0145.00025	0x2d19	11545	9502745	dF25: CU RCOM error	Fault	-	0x6100
▶ xx.0145.00026	0x2d1a	11546	9502746	dF26: Appl. watchdog	No Reaction	C00580/1	0x6200
▶ xx.0145.00050	0x2d32	11570	9502770	dF50: Retain error	Fault	-	0x6100
▶ xx.0145.00051	0x2d33	11571	9502771	dF51: CuCcr error	Fault	-	0x6100
▶ xx.0145.00052	0x2d34	11572	9502772	dF52: BuCcr error	Fault	-	0x6100
▶ xx.0400.00009	0x1a09	6665	26214409	dH09: EEPROM power section	Fault	-	0x5500
▶ xx.0400.00016	0x1a10	6672	26214416	dH10: Fan failure	Warning	C00566	0x5000
▶ xx.0400.00104	0x1a68	6760	26214504	dH68: Adjustment data error CU	Fault	-	0x5500
▶ xx.0400.00105	0x1a69	6761	26214505	dH69: Adjustment data error BU	Fault	-	0x5500
▶ xx.0400.00106	0x1a6a	6762	26214506	dH70: ControlUnit is unequal to BaseUnit	Fault	-	0x5500
▶ xx.0123.00094	0x175e	5982	8061022	FC01: Switching frequency reduction	No Reaction	C00590	0x2000
▶ xx.0123.00095	0x175f	5983	8061023	FC02: Maximum speed for Fchop	No Reaction	C00588	0xF000
▶ xx.0123.00099	0x1763	5987	8061027	FC03: Field controller limitation	No Reaction	C00570/4	0xF000
▶ xx.0123.00057	0x1739	5945	8060985	Id1: Motor data identification error	Fault	-	0xF000
▶ xx.0123.00056	0x1738	5944	8060984	Id2: Motor data identification error	Fault	-	0xF000
▶ xx.0123.00058	0x173a	5946	8060986	Id3: CINH identification	WarningLocked	-	0xF000
▶ xx.0123.00059	0x173b	5947	8060987	Id4: Resistance identification error	Warning	-	0xF000
▶ xx.0123.00074	0x174a	5962	8061002	Id5: Pole position identification error	Fault	C00643/1	
▶ xx.0123.00075	0x174b	5963	8061003	Id6: Resolver ident error	Fault	-	
▶ xx.0123.00060	0x173c	5948	8060988	Id7: Motor control does not match motor data	Information	C00571/1	0xF000
▶ xx.0123.00061	0x173d	5949	8060989	Id8: Speed sensor has not been set	Fault	C00571/2	0x7120
▶ xx.0123.00145	0x1791	6033	8061073	LP1: Motor phase failure	No Reaction	C00597	0x3000
▶ xx.0123.00015	0x170f	5903	8060943	LU: DC bus undervoltage	Trouble	C00600/1	0x3100
▶ xx.0123.00016	0x1710	5904	8060944	oC1: Power section - short circuit	Fault	-	0x2000
▶ xx.0123.00017	0x1711	5905	8060945	oC2: Power section - earth fault	Fault	-	0x2000
▶ xx.0119.00050	0x1332	4914	7798834	oC5: Ixt overload	Warning	C00604	0x2000
▶ xx.0123.00105	0x1769	5993	8061033	oC6: I2xt motor overload	Warning	C00606	0x2000
▶ xx.0123.00007	0x1707	5895	8060935	oC7: Motor overcurrent	Fault	-	0x2000
▶ xx.0123.00030	0x171e	5918	8060958	oC10: Maximum current reached	No Reaction	C00609	0x2000
▶ xx.0123.00071	0x1747	5959	8060999	oC11: Clamp operation active	Fault	-	0xF000
▶ xx.0123.00065	0x1741	5953	8060993	oC12: I2xt brake resistor overload	Fault	-	0xF000
▶ xx.0123.00090	0x175a	5978	8061018	oC13: Maximum current for Fch exceeded	Fault	-	0xF000
▶ xx.0123.00096	0x1760	5984	8061024	oC14: Direct-axis current controller limitation	No Reaction	C00570/1	0xF000
▶ xx.0123.00097	0x1761	5985	8061025	oC15: Cross current controller limitation	No Reaction	C00570/2	0xF000
▶ xx.0123.00098	0x1762	5986	8061026	oC16: Torque controller limitation	No Reaction	C00570/3	0xF000
▶ xx.0123.00031	0x171f	5919	8060959	oC17: Clamp sets pulse inhibit	No Reaction	C00569/1	0xF000
▶ xx.0119.00001	0x1301	4865	7798785	oH1: Heatsink overtemperature	Fault	-	0x4000
▶ xx.0119.00015	0x130f	4879	7798799	oH3: Motor temperature (X106) triggered	Fault	C00585	0x4000
▶ xx.0119.00000	0x1300	4864	7798784	oH4: Heatsink temp. > shutdown temp. -5°C	No Reaction	C00582	0x4000
▶ xx.0119.00020	0x1314	4884	7798804	oH6: Motor temperature MultiEncoder >= C121	Warning	C00583/4	
▶ xx.0119.00002	0x1302	4866	7798786	oH7: Motor temperature resolver >= C121	Warning	C00583/3	
▶ xx.0119.00003	0x1303	4867	7798787	oH9: Motor overtemperature resolver	Fault	C00583/1	
▶ xx.0119.00021	0x1315	4885	7798805	oH12: Motor overtemperature MultiEncoder	Fault	C00583/2	

Error number 32 bits	16 bits _{hex}	16 bits _{dec}	Display in C00162/1	Error message	Response (Lenze setting)	can be set in	CAN Emergency Error Code
▸ xx.0123.00032	0x1720	5920	8060960	oS1: Maximum speed limit reached	No Reaction	C00579	0x8400
▸ xx.0123.00033	0x1721	5921	8060961	oS2: Max. motor speed	Fault	-	0x8400
▸ xx.0123.00001	0x1701	5889	8060929	ot1: Max. torque reached	No Reaction	C00608	0x8300
▸ xx.0123.00093	0x175d	5981	8061021	ot2: Speed controller output limited	No Reaction	C00567	0xF000
▸ xx.0123.00014	0x170e	5902	8060942	OU: DC bus overvoltage	Trouble	-	0x3100
▸ xx.0144.00001	0x2c01	11265	9437185	PS01: No memory module	Warning	-	0x6300
▸ xx.0144.00002	0x2c02	11266	9437186	PS02: Invalid par. set	Fault	-	0x6300
▸ xx.0144.00003	0x2c03	11267	9437187	PS03: Invalid device par. set	Fault	-	0x6300
▸ xx.0144.00004	0x2c04	11268	9437188	PS04: Invalid MCI par. set	Fault	-	0x6300
▸ xx.0144.00007	0x2c07	11271	9437191	PS07: Invalid memory module par. set	Fault	-	0x6300
▸ xx.0144.00008	0x2c08	11272	9437192	PS08: Invalid device par.	Fault	-	0x6300
▸ xx.0144.00009	0x2c09	11273	9437193	PS09: Invalid par. format	Fault	-	0x6300
▸ xx.0144.00010	0x2c0a	11274	9437194	PS10: Memory module binding invalid	Fault	-	
▸ xx.0123.00024	0x1718	5912	8060952	Sd2: Resolver open circuit	Fault	C00603/2	
▸ xx.0123.00205	0x17cd	6093	8061133	Sd3: Feedback system open circuit	Fault	C00586	0x7300
▸ xx.0123.00027	0x171b	5915	8060955	Sd4: MultiEncoder open circuit	Fault	C00603/1	
▸ xx.0119.00012	0x130c	4876	7798796	Sd6: Error thermal detector resolver	Fault	C00583/5	
▸ xx.0123.00026	0x171a	5914	8060954	Sd7: Error encoder communication	Fault	C00603/4	
▸ xx.0123.00062	0x173e	5950	8060990	Sd8: Encoder angular drift monit.	No Reaction	C00603/3	
▸ xx.0123.00028	0x171c	5916	8060956	Sd9: Status message Hiperface	Information	C00603/5	0x7300
▸ xx.0123.00200	0x17c8	6088	8061128	Sd10: Speed limit for feedback system 12	Fault	C00607	0x7300
▸ xx.0123.00201	0x17c9	6089	8061129	Sd11: Speed limit for feedback system 67	Fault	C00607	0x7300
▸ xx.0119.00022	0x1316	4886	7798806	Sd12: Error thermal detector MultiEncoder	Fault	C00583/6	
▸ xx.0123.00206	0x17ce	6094	8061134	Sd13: Inaccuracy SinCos	Information	-	0x7300
▸ xx.0123.00029	0x171d	5917	8060957	Sd14: Position invalid Hiperface	Information	C00603/6	0x7300
▸ xx.0111.00002	0x0b02	2818	7274498	Su02: One mains phase is missing	Warning	C00565	0x3000
▸ xx.0111.00003	0x0b03	2819	7274499	Su03: Too frequent mains switching	Fault	-	0x3000
▸ xx.0111.00004	0x0b04	2820	7274500	Su04: CU Insufficiently Supplied	Warning	-	0x3000
▸ xx.0111.00006	0x0b06	2822	7274502	Su06: Mains input overload	Fault	-	0x3000
Freely configurable user error messages (see LS_SetError_1 and LS_SetError_2)							
▸ xx.0980.00001	25600 _{dec} + C161/1 *			User error 1	No Reaction	C00581/1	0x6200
▸ xx.0981.00002	25856 _{dec} + C161/2 *			User error 2	No Reaction	C00581/2	0x6200
▸ xx.0982.00003	26112 _{dec} + C161/3 *			User error 3	No Reaction	C00581/3	0x6200
▸ xx.0983.00004	26368 _{dec} + C161/4 *			User error 4	No Reaction	C00581/4	0x6200
▸ xx.0984.00001	26624 _{dec} + C161/5 *			User error 5	No Reaction	C00581/5	0x6200
▸ xx.0985.00002	26880 _{dec} + C161/6 *			User error 6	No Reaction	C00581/6	0x6200
▸ xx.0986.00003	27136 _{dec} + C161/7 *			User error 7	No Reaction	C00581/7	0x6200
▸ xx.0987.00004	27392 _{dec} + C161/8 *			User error 8	No Reaction	C00581/8	0x6200
* Only the lower 8 bits of the adjustable error ID (C161/x) can be used.							

10.9.6 Cause & possible remedies

This chapter contains all error messages of the controller operating system in numerical order of the error numbers. The list provides detailed information on the response to the error message as well as information on the cause & possible remedies.



Note!

For the sake of legibility, the [Logbook](#) and [C00165](#) display the error number with the following syntax:

[Error type].[Error subject area no.].[Error ID]

In this documentation, "xx", a wildcard, stands for the error type since it is configurable for many error messages.



Tip!

A list of all error messages of the controller operating system in alphabetical order can be found in the previous chapter "[Short overview \(A-Z\)](#)" ([□ 702](#)).

Su02: One mains phase is missing [xx.0111.00002]

Response (Lenze setting printed in bold)	Setting: C00565 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
One mains phase of a three-phase supply has failed.	Check mains connection (terminal X100).

Su03: Too frequent mains switching [xx.0111.00003]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
<p>Too frequent mains switching of the power section.</p> <ul style="list-style-type: none"> • The device recognises if the power section is switched on and off too frequently. • To protect internal charging connections from destruction, the device reports this error and prevents the controller inhibit. All other functions are active. <p>Use of a power supply module in the DC-bus connection, the DC terminals of which are connected downstream to the charging connection for the voltage DC bus (e.g. 9400 from 45 kW).</p>	<p>The error must be acknowledged by mains switching. The charging circuit can only cool down when the mains is switched off.</p> <ul style="list-style-type: none"> • After switching the mains 3 times in one minute, there must be a switching pause of 9 minutes. • Cyclic mains switching every 3 minutes is permissible. <p>From version 12.00.00 onwards, this power supply module can be used in the DC-bus connection by enabling it via C02865 (bit 8).</p> <p>Note: For further configuration of devices in the DC-bus connection with 8400, the DC terminals of which are connected downstream to the charging connection for the voltage DC bus (e.g. 9400 from 45 kW with 8400) contact Lenze.</p>

Su04: CU insufficiently supplied [xx.0111.00004]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
After switching on the device, the 24V supply voltage for the control electronics is too low (100 ms after switch-on U is < 19V). <ul style="list-style-type: none"> The current supply voltage is displayed in C00065. 	With internal supply voltage via the power electronics, the controller must be replaced. With external supply voltage, check the correct connection and/or the stability of the supply voltage.

Su06: Mains input overload [xx.0111.00006]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
In order to protect the device from overload, the following device outputs have a hardware detection in the mains input: 7.5 kW, 11 kW, 15 kW, 30 kW, 37 kW, 45 kW. In case of the error message "Su06", this hardware detection has responded.	<ul style="list-style-type: none"> Check whether all mains phases are connected (a 2-phase supply may be existent). Provide for sufficient cooling of the device.

oH4: Heatsink temp. > shutdown temp. -5°C [xx.0119.00000]

Response (Lenze setting printed in bold)		Setting: C00582 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information		
Cause	Remedy	
The heatsink temperature now only differs by 5 °C from the shutdown temperature of the motor.	Prevent further heating, i.e. reduce motor load or set controller inhibit so that the heatsink can cool down again.	

oH1: Heatsink overtemperature [xx.0119.00001]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
The heatsink temperature is higher than the fixed limit temperature (90 °C). Maybe the ambient temperature of the controller is too high or the fan or its ventilation slots are dirty.	<ul style="list-style-type: none"> Check control cabinet temperature. Clean filter. Clean controller. If required, clean or replace the fan. Provide for sufficient cooling of the device.

oH7: Motor temperature resolver >= C121 [xx.0119.00002]

Response (Lenze setting printed in bold)		Setting: C00583/3 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
The motor temperature detected via the resolver interface has reached the warning threshold set in C00121/1 .	<ul style="list-style-type: none"> Check motor temperature monitoring. Provide for sufficient cooling of the motor. Check terminals for open circuit or loose contact. 	

oH9: Motor overtemperature resolver [xx.0119.00003]

Response (Lenze setting printed in bold)	Setting: C00583/1 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
The motor temperature detected via the resolver interface has reached the fixed limit temperature (150 °C).	<ul style="list-style-type: none"> • Check motor temperature monitoring. • Provide for sufficient cooling of the motor. • Check terminals for open circuit or loose contact.

Sd6: Error thermal detector resolver [xx.0119.00012]

Response (Lenze setting printed in bold)	Setting: C00583/5 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
The signals of the encoder connected to the resolver interface are outside the defined operating range of the motor temperature detection.	<ul style="list-style-type: none"> • Check contacts of the encoder cable at the motor and controller. • Check the selected motor temperature sensor in C01190/1 as to whether it complies with the assembly in the motor. • If required, switch off thermal sensor monitoring (C00583/5="0").

oH3: Motor temperature (X106) triggered [xx.0119.00015]

Response (Lenze setting printed in bold)	Setting: C00585 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☑ 5: Warning ☐ 6: Information	
Cause	Remedy
<p>The motor temperature monitoring function at the plug connector X106, terminal T1 /T2, has tripped.</p> <p>Possible causes:</p> <ul style="list-style-type: none"> • The motor is overheated so that the thermal contact integrated into the motor has been switched. • An open circuit or a loose contact at the connections mentioned above has occurred. 	<ul style="list-style-type: none"> • Check motor temperature monitoring. • Provide for sufficient cooling of the motor. • Check terminals for open circuit or loose contact.

oH6: Motor temperature MultiEncoder >= C121 [xx.0119.00020]

Response (Lenze setting printed in bold)	Setting: C00583/4 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
The motor temperature detected via the encoder interface has reached the warning threshold set in C00121/2 .	<ul style="list-style-type: none"> • Check motor temperature monitoring. • Provide for sufficient cooling of the motor. • Check terminals for open circuit or loose contact.

oH12: Motor overtemperature MultiEncoder [xx.0119.00021]

Response (Lenze setting printed in bold)	Setting: C00583/2 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
The motor temperature detected via the encoder interface has reached the fixed limit temperature (150 °C).	<ul style="list-style-type: none"> • Check motor temperature monitoring. • Provide for sufficient cooling of the motor. • Check terminals for open circuit or loose contact.

Sd12: Error thermal detector MultiEncoder [xx.0119.00022]

Response (Lenze setting printed in bold)		Setting: C00583/6 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
The signals of the encoder connected to the encoder interface are outside the defined operating range of the motor temperature detection.	<ul style="list-style-type: none"> • Check contacts of the encoder cable at the motor and controller. • Check the selected motor temperature sensor in C01190/2 as to whether it complies with the assembly in the motor. • If required, switch off thermal sensor monitoring (C00583/6="0"). 	

oC5: lxt overload [xx.0119.00050]

Response (Lenze setting printed in bold)		Setting: C00604 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information		
Cause	Remedy	
<p>The lxt overload check has tripped.</p> <ul style="list-style-type: none"> • Operating threshold = 100 % lxt (adjustable in C00123) <p>Possible causes:</p> <ul style="list-style-type: none"> • Wrong dimensioning of the device with regard to its motor load. • Load cycles are not complied with. 	<ul style="list-style-type: none"> • Check and, if required, correct dimensioning of the device and the motor load with regard to technical data. • Reduce motor load cycles (observe load cycles according to documentation). 	

ot1: Maximum torque reached [xx.0123.00001]

Response (Lenze setting printed in bold)		Setting: C00608 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information		
Cause	Remedy	
<p>The device indicates that the maximally possible torque at the motor shaft has been reached.</p> <ul style="list-style-type: none"> • C00057 displays the current torque. 	Reduce motor load.	

oC7: Motor overcurrent [xx.0123.00007]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
<p>Maximum current monitoring has tripped.</p> <ul style="list-style-type: none"> • The instantaneous value of the motor current has exceeded the limit value set in C00939. 	Check and, if required, correct dimensioning of the load with regard to the installed device power.

oU: DC bus overvoltage [xx.0123.00014]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input checked="" type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
<p>The device has detected an overvoltage in the DC bus. To protect the device hardware, the inverter control is switched off.</p> <ul style="list-style-type: none"> Depending on the configuration of the auto-start lock function, set C00142 so that, when this error is tripped, the controller only restarts after the controller inhibit has been switched. If this error message remains active longer than the time set in C00601, a "Fault" is tripped. Otherwise, the deactivation of the error message causes the inverter control to be enabled again <ul style="list-style-type: none"> In case of the control types VFCplus and SLVC, the motor voltage is approached to the voltage setpoint alongside a ramp. From version 15.00.00, this voltage ramp can be set in C00983/2. If the described remedies are not possible or do not have any effect, it may be required to increase this voltage ramp as otherwise an overcurrent interruption may be caused. This only happens in case of high motor power and mass inertia so that the Lenze setting of 1 s should be sufficient in the majority of cases. 	<ul style="list-style-type: none"> Reduce load in generator mode. Use a brake resistor. Use a regenerative power supply unit. Establish a DC-bus connection. Select a braking method in C00175 which stops the ramp function generator when reaching the brake chopper threshold ("HlgStop"). In case of servo control (SC), set the speed controller parameters correctly.

LU: DC bus undervoltage [xx.0123.00015]

Response (Lenze setting printed in bold)		Setting: C00600/1 (<input checked="" type="checkbox"/> Adjustable response)
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input checked="" type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information		
Cause	Remedy	
<p>The device has detected a DC bus undervoltage. The inverter control is switched off because the drive properties of the motor control cannot be provided anymore due to the DC bus undervoltage.</p> <ul style="list-style-type: none"> Depending on the configuration of the auto-start lock function, set C00142 so that, when this error is tripped, the controller only restarts after the controller inhibit has been switched. 	<ul style="list-style-type: none"> Switch on mains supply or ensure sufficient supply via DC bus. Adjust setting in C00142 if required. 	

oC1: Power section - short circuit [xx.0123.00016]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
<p>The device has recognised a short circuit of the motor phases. To protect the device electronics, the inverter control is switched off.</p> <ul style="list-style-type: none"> Mostly, incorrectly executed motor connections are the cause. If the device is inappropriately dimensioned with regard to the motor load and the current limitation in the controller (I_{max} controller) is set incorrectly, this error message may also occur. <p>► Motor control: Defining current limits</p>	<ul style="list-style-type: none"> Check motor connections and the corresponding plug connector on the device. Only use permissible combinations of device power and motor power. Do not set the dynamics of the current limitation controller too high.

oC2: Power section - earth fault [xx.0123.00017]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
<p>The device has recognised an earth fault at one of the motor phases. To protect the device electronics, the inverter control is switched off.</p> <ul style="list-style-type: none"> • Mostly, incorrectly executed motor connections are the cause. • If motor filter, motor cable length, and cable type (shielding capacity) are dimensioned incorrectly, this error message may occur due to leakage currents to PE. • If motor filters with additional terminals for +UG and –UG and devices greater or equal 3 kW are used, the earth fault detection may be triggered due to leakage currents to +UG and –UG. • A cause can also be the use of shielded motor cables longer than 50 m. 	<ul style="list-style-type: none"> • Check motor connections and the corresponding plug connector on the device. • Use motor filters, cable lengths, and cable types recommended by Lenze. • If motor filters with additional terminals for +UG and –UG and devices greater or equal 3 kW are used: <ul style="list-style-type: none"> • Deactivate earth-fault detection during operation by setting the filter time (C01770) to 250 ms. • If motor cables longer than 50 m are used: <ul style="list-style-type: none"> • Increase filter time for earth-fault detection during operation (C01770).

Sd2: Open circuit resolver [xx.0123.00024]

Response (Lenze setting printed in bold)		Setting: C00603/2 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input checked="" type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
<ul style="list-style-type: none"> • Encoder signal interferences (EMC). • Resolver cable interrupted. • Resolver defective. 	<ul style="list-style-type: none"> • Check resolver cable. • Check resolver. • Switch off monitoring (C00603/2 = "0: No reaction") when the resolver is not used. 	

Sd7: Encoder communication error [xx.0123.00026]

Response (Lenze setting printed in bold)		Setting: C00603/4 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input checked="" type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
<ul style="list-style-type: none"> • Encoder cable interrupted. • Encoder defective. 	<ul style="list-style-type: none"> • Check encoder cable • Check encoder. • Check parameter setting. 	

Sd4: Open circuit MultiEncoder [xx.0123.00027]

Response (Lenze setting printed in bold)		Setting: C00603/1 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input checked="" type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
<ul style="list-style-type: none"> • Encoder cable interrupted. • Encoder defective. • Supply voltage for the encoder not sufficient. 	<ul style="list-style-type: none"> • Check encoder cable. • Check encoder. • Check the set encoder supply voltage in C00421. Adapt setting to the max. permissible encoder supply voltage. If required, additional voltage drops of the encoder cable have to be taken into consideration. • Switch off monitoring (C00603/1 = "0: No reaction") when the encoder is not used. 	

Sd9: Status message Hiperface [xx.0123.00028]

Response (Lenze setting printed in bold)	Setting: C00603/5 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
<p>Sd9 is output when the controller has received a Hiperface encoder error code from the encoder during initialisation.</p> <ul style="list-style-type: none"> The received error codes are displayed in C00491/1...4. The error codes are explained in the data sheet of the respective encoder. 	<p>Eliminating the fault described in the error code. Afterwards, reinitialising the encoder by a renewed writing of the encoder type in C00422.</p>

Sd14: Position invalid Hiperface [xx.0123.00029]

Response (Lenze setting printed in bold)	Setting: C00603/6 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
<p>No standstill of the Hiperface encoder during initialisation. Hence, the absolute Hiperface track and the incremental SinCos track cannot be initiated exactly and the actual position cannot be detected correctly.</p>	<p>Stopping encoder movement. Afterwards reinitialising the encoder by a renewed writing of the encoder type in C00422.</p>

oC10: Maximum current reached [xx.0123.00030]

Response (Lenze setting printed in bold)	Setting: C00609 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☑ 5: Warning ☐ 6: Information	
Cause	Remedy
<p>The device displays that the maximum current has been reached.</p>	<ul style="list-style-type: none"> Check and, if required, correct dimensioning of the load with regard to the installed device power. Check the maximum current settings in C00022 (Imax in motor mode) and C00023 (Imax in generator mode).

oC17: Clamp sets pulse inhibit [xx.0123.00031]

Response (Lenze setting printed in bold)	Setting: C00569/1 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☑ 5: Warning ☐ 6: Information	
Cause	Remedy
<p>Due to a short overcurrent, the inverter was switched off for a short time (clamp disconnection).</p>	<ul style="list-style-type: none"> Check and, if required, correct dimensioning of the load with regard to the installed device power. Reduce the dynamics of the setpoint change or speed control.

oS1: Maximum speed limit reached [xx.0123.00032]

Response (Lenze setting printed in bold)	Setting: C00579 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☑ 5: Warning ☐ 6: Information	
Cause	Remedy
<p>The device has recognised that the maximum speed has been reached.</p>	<ul style="list-style-type: none"> Limit setpoint selection to maximum values. Adjust set speed limitation (C00909) and frequency limitation (C00910).

oS2: Max. motor speed [xx.0123.00033]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
The device has recognised that the maximally permissible motor speed has been reached.	<ul style="list-style-type: none"> • Limit setpoint selection to the maximally permissible motor speed. • If required, adapt set maximum motor speed (C00965).

Id2: Motor data identification error [xx.0123.00056]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
During the identification of the motor parameters, an error has occurred that caused an abortion of the identification process. Possible causes: <ul style="list-style-type: none"> • Interrupted motor cable. • Switched-off power section during the identification. • Implausible start parameter settings. 	<ul style="list-style-type: none"> • Check the motor connections and the corresponding plug connector on the device and, if necessary, the motor terminal box. • Correct start parameters for the motor parameter identification (motor nameplate data). • Stable power supply of the device.

Id1: Motor data identification error [xx.0123.00057]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
During the identification of motor parameters, an error has occurred. Possible causes: <ul style="list-style-type: none"> • Interrupted motor cable. • Switched-off power section during the identification. • Implausible start parameter settings. 	<ul style="list-style-type: none"> • Check the motor connections and the corresponding plug connector on the device and, if necessary, the motor terminal box. • Correct start parameters for the motor parameter identification (motor nameplate data). • Stable power supply of the device.

Id3: CINH identification [xx.0123.00058]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
The device has detected controller inhibit during the motor data identification. <ul style="list-style-type: none"> • This cancels the identification process. The Lenze setting of the motor data is used. 	<ul style="list-style-type: none"> • Do not set controller inhibit during the motor data identification. • Do not execute any device function which may activate controller inhibit.

Id4: Resistor identification error [xx.0123.00059]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
The device has recognised that an error has occurred in the calculation of the motor cable resistance. <ul style="list-style-type: none"> • The parameters for cable cross-section and cable length are implausible. 	Enter sensible values for cable cross-section and motor cable length.

Id7: Motor control does not match motor data [xx.0123.00060]

Response (Lenze setting printed in bold)		Setting: C00571/1 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input checked="" type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
<p>At controller enable, the device has detected that the motor control type set in C00006 cannot control the motor type set.</p> <ul style="list-style-type: none"> Example: Motor nameplate data for an asynchronous motor have been entered; however, a motor control type for a synchronous motor is set in C00006. <p>Note: Since the "VFCplus" control types are able to control every motor to a certain extent, this error message will never occur here.</p>	<p>Enter correct motor nameplate data and set a matching motor control type in C00006:</p> <ul style="list-style-type: none"> Motor nameplate data asynchronous motor → motor control type must be ASM, SLVC or VFCplus servo control. Motor nameplate data synchronous motor → motor control type must be PSM, SLPSM or VFCplus servo control. 	

Id8: Speed encoder has not been set [xx.0123.00061]

Response (Lenze setting printed in bold)		Setting: C00571/2 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input checked="" type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
<p>When being In controller enable status, the device has detected that a motor control type with feedback has been set in C00006, but no speed sensor has been set in C00495.</p>	<p>Set the speed sensor in C00495.</p> <p>Note: The error can only be reset if the settings in C00006 and C00495 match.</p>	

Sd8: Encoder angular drift monit. [xx.0123.00062]

Response (Lenze setting printed in bold)		Setting: C00603/3 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input checked="" type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
<ul style="list-style-type: none"> Encoder signal interferences (EMC). Encoder cable interrupted. Encoder defective. Faulty parameter setting of the encoder. 	<ul style="list-style-type: none"> Check encoder cable, use shorter encoder cable if required. Check encoder. Check parameter setting. If required, switch off monitoring (C00603/3). 	

oC12: I2xt overload - brake resistor [xx.0123.00065]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Too frequent and too long braking processes.	Check drive dimensioning.

oC11: Clamp operation active [xx.0123.00071]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
<p>The device indicates that the "CLAMP" overcurrent limitation has been activated.</p> <ul style="list-style-type: none"> A permanent clamp operation causes an overload disconnection. 	Reduce setpoint generation dynamics or motor load.

Id5: Pole position identification error [xx.0123.00074]

Response (Lenze setting printed in bold)		Setting: C00643/1 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information		
Cause	Remedy	
<p>With 360° pole position identification:</p> <ul style="list-style-type: none"> The rotor position detected via the encoder system does not comply with the controlled output position (plausibility check). <p>With pole position identification with minimum movement:</p> <ul style="list-style-type: none"> The encoder system has detected a movement that is greater than the permitted movement set in C00645/1. 	<p>With 360° pole position identification:</p> <ul style="list-style-type: none"> Check parameter setting of the pole position identification. If required, adapt error tolerance for plausibility check in C00645/2. <p>With pole position identification with minimum movement:</p> <ul style="list-style-type: none"> If required, adjust permitted movement in C00645/1. 	

Id6: Resolver ident. error [xx.0123.00075]

Response (Lenze setting printed in bold)	
☐ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☐ 5: Warning ☐ 6: Information	
Cause	Remedy
<ul style="list-style-type: none"> A controller inhibit was set during resolver error identification. A time-out occurred while the algorithm was being processed. This error may occur if more than 60 seconds pass by between the setting of the "Resolver error identification" device command and the enable of the controller. The setpoint speed was too small ($nset < 500$ rpm). The setpoint speed was not traversed for at least 1 second. 	<ul style="list-style-type: none"> Reduce the gain of the speed controller. Check the shielding of the motor and encoder. Check encoder/encoder connection. Controller is enabled after the "Resolver error identification" device command has been set. Ensure that the speed profile is traversed for at least 1 second at constant setpoint speed ($nset > 500$ rpm).

oC13: Maximum current for Fch exceeded [xx.0123.00090]

Response (Lenze setting printed in bold)	
☐ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☐ 5: Warning ☐ 6: Information	
Cause	Remedy
<p>The device has detected a motor current which exceeds the maximum current limit at permanent switching frequency of the inverter.</p> <ul style="list-style-type: none"> If a permanent switching frequency inverter is set, a certain limit arises for the maximum current, depending on the setting. If this current limit is exceeded due to a load impulse or overload, an error message is displayed. 	<ul style="list-style-type: none"> Observe the maximum current setting depending on the set switching frequency of the inverter. Reduce the required load or setting of the dynamic switching frequency if necessary.

ot2: Speed controller output limited [xx.0123.00093]

Response (Lenze setting printed in bold)		Setting: C00567 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☑ 5: Warning ☐ 6: Information		
Cause	Remedy	
<p>The output of the speed controller has reached the internal limit value. In this status, the speed controller is not able anymore to correct the system deviation.</p> <ul style="list-style-type: none"> Only during "Closed loop" operation or with vector control (SLVC). 	<ul style="list-style-type: none"> Observe load requirements. Correct dimensioning or reduce setpoint generation dynamics if necessary. <p>► Motor control</p>	

FC01: Switching frequency reduction [xx.0123.00094]

Response (Lenze setting printed in bold)	Setting: C00590 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☑ 5: Warning ☐ 6: Information	
Cause	Remedy
Load-dependent switching frequency reduction	<ul style="list-style-type: none"> • Observe load requirements. • Correct dimensioning or reduce setpoint generation dynamics if necessary. <p>► Motor control</p>

FC02: Maximum speed for Fchop [xx.0123.00095]

Response (Lenze setting printed in bold)	Setting: C00588 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☑ 5: Warning ☐ 6: Information	
Cause	Remedy
Maximum speed for chopper frequency has been reached. <ul style="list-style-type: none"> • The maximum speed has been exceeded depending on the switching frequency. 	Select the correct maximum speed as a function of the switching frequency. <p>► Motor control: Determine speed limits</p>

oC14: Direct-axis current controller limitation [xx.0123.00096]

Response (Lenze setting printed in bold)	Setting: C00570/1 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☑ 5: Warning ☐ 6: Information	
Cause	Remedy
Direct-axis current controller limitation is active.	<ul style="list-style-type: none"> • Observe load requirements. • Correct dimensioning or reduce setpoint generation dynamics if necessary. <p>► Motor control</p>

oC15: Cross current controller limitation [xx.0123.00097]

Response (Lenze setting printed in bold)	Setting: C00570/2 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☑ 5: Warning ☐ 6: Information	
Cause	Remedy
Cross current controller limitation is active.	<ul style="list-style-type: none"> • Observe load requirements. • Correct dimensioning or reduce setpoint generation dynamics if necessary. • Check parameter setting of the current controller with regard to the motor controllers (e.g. reduce Vp). <p>► Motor control</p>

oC16: Torque controller limitation [xx.0123.00098]

Response (Lenze setting printed in bold)	Setting: C00570/3 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☑ 5: Warning ☐ 6: Information	
Cause	Remedy
Actuator limitation according to speed controller.	<ul style="list-style-type: none"> • Observe load requirements. • Correct dimensioning or reduce setpoint generation dynamics if necessary. <p>► Motor control</p>

FC03: Field controller limitation [xx.0123.00099]

Response (Lenze setting printed in bold)	Setting: C00570/4 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
The output of the field controller has reached its maximum limit value. The drive is at the torque limit in the field weakening range.	<ul style="list-style-type: none"> • Observe load requirements. • Correct dimensioning or reduce setpoint from the field weakening range if necessary. <p>► Motor control</p>

oC6: I2xt overload - motor [xx.0123.00105]

Response (Lenze setting printed in bold)	Setting: C00606 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Thermal overload of the motor.	<p>Only self-ventilated motors can be monitored using the I2xt function.</p> <ul style="list-style-type: none"> • Check whether it is a self-ventilated motor. If not, set C00606 to "0: No Reaction". • Observe load requirements. • Correct dimensioning if necessary. • For VFCplus control type: Check Vmin boost (C00016). <p>► Set Vmin boost</p>

LP1: Motor phase failure [xx.0123.00145]

Response (Lenze setting printed in bold)	Setting: C00597 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
<p>Motor phase failure - power section</p> <ul style="list-style-type: none"> • This error message is displayed if a motor phase carries less current of one half-wave than set in C00599. 	<ul style="list-style-type: none"> • Check the motor connections and the corresponding plug connector on the device and, if necessary, the motor terminal box. • Check the trigger threshold (C00599).

Sd10: Speed limit - feedback system 12 [xx.0123.00200]

Response (Lenze setting printed in bold)	Setting: C00607 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Maximally permissible speed of the feedback system connected to DI1/DI2 reached.	<p>Reduce speed of the rotation shaft/feedback system.</p> $n_{\text{encoder}} \leq (f_{\text{max}} \times 60) / \text{encoder increments}$ <p>(for $f_{\text{max}} = 10 \text{ kHz}$)</p>

Sd11: Speed limit for feedback system 67 [xx.0123.00201]

Response (Lenze setting printed in bold)	Setting: C00607 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Maximally permissible speed of the feedback system connected to DI6/DI7 reached.	<p>Reduce speed of the rotation shaft/feedback system.</p> $n_{\text{encoder}} \leq (f_{\text{max}} \times 60) / \text{encoder increments}$ <p>(for $f_{\text{max}} = 10 \text{ kHz}$)</p>

Sd3: Open circuit - feedback system [xx.0123.00205]

Response (Lenze setting printed in bold)		Setting: C00586 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☑ 5: Warning ☐ 6: Information		
Cause	Remedy	
<ul style="list-style-type: none"> HTL encoder cable interrupted. HTL encoder is defective. <p>Note: The reason can also be a very dynamic acceleration or an approach against a blocked motor shaft, e.g. with a closed holding brake or when referencing to positive stop (mode 14/15) and a waiting time (C01223) >100 ms.</p>	<ul style="list-style-type: none"> Check HTL encoder cable. Check HTL encoder. Check related terminals. Switch off monitoring (C00586 = "0: No reaction") when the HTL encoder is not used. 	

Sd13: Inaccuracy SinCos [xx.0123.00206]

Response (Lenze setting printed in bold)		Setting: C00495 (☐ Adjustable response)
☐ 0: No Reaction ☐ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☐ 5: Warning ☑ 6: Information		
Cause	Remedy	
<p>Only in case of "Multi-Encoder" speed encoder selection (C00495 = 3):</p> <p>A plausibility check for the digital and analog signals of the absolute value encoder (Hiperface) or sin/cos encoder has responded.</p> <ul style="list-style-type: none"> The reason for this are EMC interferences. This information is given since angle errors (position error) can occur in such a case. 	Eliminate EMC interference.	

An01: AIN1_I < 4 mA [xx.0125.00001]

Response (Lenze setting printed in bold)		Setting: C00598/1 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☐ 4: WarningLocked ☑ 5: Warning ☐ 6: Information		
Cause	Remedy	
<p>Open-circuit monitoring for analog input 1 has tripped.</p> <ul style="list-style-type: none"> Only if the analog input has been configured as a current loop of 4 ... 20 mA (C00034/1 = 2). 	<ul style="list-style-type: none"> Check wiring of the analog X3/A1I input terminal for open circuit. Check minimum current values of the signal sources. 	

An02: AIN2_I < 4 mA [xx.0125.00002]

Response (Lenze setting printed in bold)		Setting: C00598/2 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☐ 4: WarningLocked ☑ 5: Warning ☐ 6: Information		
Cause	Remedy	
<p>Open-circuit monitoring for analog input 2 has tripped.</p> <ul style="list-style-type: none"> Only if the analog input has been configured as a current loop of 4 ... 20 mA (C00034/2 = 2). 	<ul style="list-style-type: none"> Check wiring of the analog X3/A2I input terminal for open circuit. Check minimum current values of the signal sources. 	

Ab01: Axis bus timeout [xx.0126.00001]

Response (Lenze setting printed in bold)	Setting: C00591/1 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input checked="" type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information	
Cause	Remedy
<p>The axis bus data error monitoring has been triggered as the monitoring time for data errors set in C02431/3 has been exceeded.</p> <ul style="list-style-type: none"> • The current number of incorrectly transmitted telegrams is displayed in C02438/1. • The current number of incorrectly received telegrams is displayed in C02438/2. • The current axis bus error status is displayed in C02436. 	<ul style="list-style-type: none"> • Check wiring and bus terminating resistor. • Assign different IDs to nodes. • Eliminate electrical interference (e.g. EMC).

Ab02: Axis bus IO error [xx.0126.00002]

Response (Lenze setting printed in bold)	Setting: C00591/2 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input checked="" type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information	
Cause	Remedy
<p>An axis bus node has put the IO axis bus into the "error" status with parameterised "master/slave" function ("release cord" principle).</p> <ul style="list-style-type: none"> • In the "Error" status, all nodes start their adjustable response, e.g. a synchronised braking of the drive system or the master only brakes the network to standstill. 	<p>Remove the fault of the node which pulled the "release cord".</p> <p>Note: The "error" status can only be reset by the node defined as "master".</p>

CE04: MCI communication error [xx.0127.00002]

Response (Lenze setting printed in bold)	Setting: C01501/1 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input checked="" type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information	
Cause	Remedy
Communication error with extension module in slot 1.	<ul style="list-style-type: none"> • Eliminate EMC interference. • Switch off controller, correctly plug in the module, switch on the controller again. • Mains switching or restart of the controller, respectively. • Replace module/controller. • Please contact Lenze if the problem occurs again.

CE0F: MCI control word [xx.0127.00015]

Response (Lenze setting printed in bold)	Setting: C00594/2 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input checked="" type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Bit 14 ("SetFail") of the wMciCtrl control word of the LS DriveInterface system block has been set.	Trace back signal source on the bus (e.g. PROFIBUS) that sets bit 14 ("SetFail").

CE4: CAN bus off [xx.0131.00000]

Response (Lenze setting printed in bold)	Setting: C00592/2 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
CAN on board : "Bus off" status <ul style="list-style-type: none"> Received too many faulty telegrams. Damaged cable (e.g. loose contact). Two nodes with the same ID. 	<ul style="list-style-type: none"> Check wiring and bus terminating resistor. Set identical baud rate for each bus node. Assign different IDs to nodes. Eliminate electrical interference (e.g. EMC).

CA06: CAN CRC error [xx.0131.00006]

Response (Lenze setting printed in bold)	Setting: C00592/1 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
CAN on board : A faulty CAN telegram has been detected.	<ul style="list-style-type: none"> Check wiring and bus terminating resistor. Eliminate electrical interference (e.g. EMC).

CA07: CAN bus warning [xx.0131.00007]

Response (Lenze setting printed in bold)	Setting: C00592/3 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
CAN on board : Incorrect transmission or reception of more than 96 CAN telegrams. <ul style="list-style-type: none"> The current number of incorrectly transmitted CAN telegrams is displayed in C00372/1. The current number of incorrectly received CAN telegrams is displayed in C00372/2. The current CAN error status is displayed in C00345. 	<ul style="list-style-type: none"> Check wiring and bus terminating resistor. Set identical baud rate for each bus node. Assign different IDs to nodes. Eliminate electrical interference (e.g. EMC).

CA08: CAN bus stopped [xx.0131.00008]

Response (Lenze setting printed in bold)	Setting: C00592/4 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
CAN on board : The device has received the "Stop Remote Node" NMT telegram.	Check CAN master (NMT master).

CA0b: CAN HeartBeatEvent [xx.0131.00011]

Response (Lenze setting printed in bold)	Setting: C00592/5 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
CAN on board : Cyclic node monitoring <ul style="list-style-type: none"> Being a Heartbeat consumer, the device has not received a Heartbeat telegram from Heartbeat producer 1 ... 15 within the defined time. The current states of the Heartbeat producers are displayed in C00347/1...15. 	<ul style="list-style-type: none"> Reactivate Heartbeat producers by mains switching, restarting the controller, or a CAN Reset Node. Reparameterise CAN Heartbeat producer time or switch off consumer monitoring and reset error status if latched. <p>► Heartbeat protocol</p>

CA0F: CAN control word [xx.0131.00015]

Response (Lenze setting printed in bold)	Setting: C00594/1 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☐ 4: WarningLocked ☑ 5: Warning ☐ 6: Information	
Cause	Remedy
Bit 14 ("SetFail") in the wCANControl control word of the LS DriveInterface system block has been set.	Trace back signal source on the CAN bus that sets bit 14 ("SetFail").

CE1: CAN RPDO1 [xx.0135.00001]

Response (Lenze setting printed in bold)	Setting: C00593/1 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
CAN on board : Time monitoring for RPDO1 has been triggered. <ul style="list-style-type: none"> RPDO1 has not been received within the monitoring time set in C00357/1 or was faulty. 	<ul style="list-style-type: none"> Set correct telegram length for CAN master (transmitter). Eliminate electrical interference (e.g. EMC). Adjust monitoring time C00357/1 or switch off time monitoring.

CE2: CAN RPDO2 [xx.0135.00002]

Response (Lenze setting printed in bold)	Setting: C00593/2 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
CAN on board : Time monitoring for RPDO2 has been triggered. <ul style="list-style-type: none"> RPDO2 has not been received within the monitoring time set in C00357/2 or was faulty. 	<ul style="list-style-type: none"> Set correct telegram length for CAN master (transmitter). Eliminate electrical interference (e.g. EMC). Adjust monitoring time C00357/2 or switch off time monitoring.

CE3: CAN RPDO3 [xx.0135.00003]

Response (Lenze setting printed in bold)	Setting: C00593/3 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
CAN on board : Time monitoring for RPDO3 has been triggered. <ul style="list-style-type: none"> RPDO3 has not been received within the monitoring time set in C00357/3 or was faulty. 	<ul style="list-style-type: none"> Set correct telegram length for CAN master (transmitter). Eliminate electrical interference (e.g. EMC). Adjust monitoring time C00357/3 or switch off time monitoring.

CP04: CAN RPDO4 [xx.0135.00004]

Response (Lenze setting printed in bold)	Setting: C00593/4 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
CAN on board : Time monitoring for RPDO4 has been triggered. <ul style="list-style-type: none"> RPDO4 has not been received within the monitoring time set in C00357/4 or was faulty. 	<ul style="list-style-type: none"> Set correct telegram length for CAN master (transmitter). Eliminate electrical interference (e.g. EMC). Adjust monitoring time C00357/4 or switch off time monitoring.

CI01: Module missing/incompatible [xx.0140.00013]

Response (Lenze setting printed in bold)	
Setting: C01501/2 (☑ Adjustable response)	
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
The optional communication module has been removed or there is a connection problem or incompatibility with the standard device.	<ul style="list-style-type: none"> • Check connection between the communication module and standard device. • Check if the module is plugged in correctly. • In case of an incompatibility, either the module or the software of the standard device is out of date. In this case, please contact Lenze.

PS01: No memory module [xx.0144.00001]

Response (Lenze setting printed in bold)	
☐ 0: No Reaction ☐ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☑ 5: Warning ☐ 6: Information	
Cause	Remedy
Memory module is either not available or not snapped into place correctly.	<ul style="list-style-type: none"> • If a memory module has been provided: Plug the memory module into the slot of the standard device intended for this purpose. • If a memory module has been provided: Check if the memory module has been plugged-in correctly.

PS02: Par. set invalid [xx.0144.00002]

Response (Lenze setting printed in bold)	
☐ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☐ 5: Warning ☐ 6: Information	
Cause	Remedy
<p>The parameter set saved to the memory module is invalid because it has not been saved completely.</p> <ul style="list-style-type: none"> • This can be due to voltage failure or caused by removing the memory module while saving the parameter set. <p>The parameter set stored in the memory module is invalid. The reason for this can be as follows:</p> <ul style="list-style-type: none"> • Incomplete storage of the parameter set due to voltage failure. • The plugged-in module stems from a device with new firmware (compare C00099) or from a different device type (e.g. 8400 BaseLine). 	<p>Ensure voltage supply during the storage process and that the module remains plugged into the slot.</p> <p>Acknowledge errors via C00002/19 or control word via communication interface and then re-parameterise the controller.</p> <p>The error can only be removed by loading the Lenze setting with the C00002/1 = "1: On / start" device command.</p> <ul style="list-style-type: none"> • In order to prevent the error, do not switch off the voltage during the saving process. • If the parameter set is to be transferred from one device with a higher version to a device with a lower version, use the "copy parameter set" function of the keypad. Make sure that you do not use functions that are not available in the older device.

PS03: Par. set device invalid [xx.0144.00003]

Response (Lenze setting printed in bold)	
☐ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☐ 3: TroubleQuickStop ☐ 4: WarningLocked ☐ 5: Warning ☐ 6: Information	
Cause	Remedy
<p>The parameter set saved to the memory module is incompatible to the standard device.</p> <ul style="list-style-type: none"> • An incompatibility of the parameter set is caused e.g. when the memory module of an 8400 HighLine is plugged into an 8400 StateLine or the parameter set in the memory module has a higher version than expected by the standard device. 	<p>When the memory modules are exchanged, observe the downward compatibility:</p> <ul style="list-style-type: none"> • OK: StateLine V2.0 to StateLine V3.0 • OK: StateLine V2.0 to HighLine V2.0 • Not OK: HighLine Vx.x to StateLine Vx.x • Not OK: StateLine V3.0 to StateLine < V3.0

PS04: Par. set Mci invalid [xx.0144.00004]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
<p>The parameter set saved to the communication module is incompatible to the standard device.</p> <ul style="list-style-type: none"> An incompatibility of the parameter set is caused e.g. when the MCI module parameters in the memory module do not match the plugged communication module. 	<p>When the memory modules are exchanged, observe the downward compatibility:</p> <ul style="list-style-type: none"> OK: StateLine V2.0 to StateLine V3.0 OK: StateLine V2.0 to HighLine V2.0 Not OK: HighLine Vx.x to StateLine Vx.x Not OK: StateLine V3.0 to StateLine < V3.0

PS07: Par. memory module invalid [xx.0144.00007]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
<p>The parameter set saved to the memory module is invalid.</p> <ul style="list-style-type: none"> The error occurs while loading the parameter set. The memory module plugged in the device lacks a code or a code is incorrect. 	<p>Consultation with Lenze required.</p>

PS08: Par. device invalid [xx.0144.00008]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
<p>The parameter set in the device is invalid.</p> <ul style="list-style-type: none"> The error occurs while loading the parameter set. One code in the device is incorrect. 	<p>Consultation with Lenze required.</p>

PS09: Par. format invalid [xx.0144.00009]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
<p>The code format is invalid.</p> <ul style="list-style-type: none"> The error occurs while loading the parameter set. 	<p>Consultation with Lenze required.</p>

PS10: Memory module binding invalid [xx.0144.00010]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
<p>Device personalisation is active: The binding ID of the memory module does not comply with the binding ID of the controller.</p>	<ul style="list-style-type: none"> Use memory module/controller with matching binding IDs. Contact machine manufacturer. <p>Note: It is not possible for Lenze to modify a replacement device via special accesses in such a way that it cooperates with a personalised memory module.</p>

dF14: SW-HW invalid [xx.0145.00014]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Device error	Consultation with Lenze required.

dF15: DCCOM CU2 error [xx.0145.00015]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Device error	Consultation with Lenze required.

dF18: BU RCOM error [xx.0145.00024]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Device error	Consultation with Lenze required.

dF25: CU RCOM error [xx.0145.00025]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Device error	Consultation with Lenze required.

dF26: Appl. watchdog [xx.0145.00026]

Response (Lenze setting printed in bold)	
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Setting: C00580/1 (<input checked="" type="checkbox"/> Adjustable response)	
Cause	Remedy
Time-out of the application. The required computing time of the application exceeds the available computing time.	Reduction of the function block interconnection or the complexity of the application.

dF21: BU watchdog [xx.0145.00033]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Device error	Consultation with Lenze required.

dF22: CU watchdog [xx.0145.00034]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Device error	Consultation with Lenze required.

dF10: AutoTrip reset [xx.0145.00035]

Response (Lenze setting printed in bold)		Setting: C00189 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input checked="" type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
Too frequent auto-trip reset.	<ul style="list-style-type: none"> • Check the error cause that activates the auto-trip reset. • Eliminate error cause and reset (acknowledge) error manually afterwards. 	

dF50: Retain error [xx.0145.00050]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
An error has occurred when accessing retain data. <ul style="list-style-type: none"> • Either caused by an internal hardware error or by lack of mains switching after a firmware download. 	Mains switching <ul style="list-style-type: none"> • Please contact Lenze if the problem occurs again.

dF51: CuCcr error [xx.0145.00051]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Device error	Mains switching <ul style="list-style-type: none"> • Please contact Lenze if the problem occurs again.

dF52: BuCcr error [xx.0145.00052]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Device error	Mains switching <ul style="list-style-type: none"> • Please contact Lenze if the problem occurs again.

Ck01: Pos. HW limit switch [xx.0184.00001]

Response (Lenze setting printed in bold)		Setting: C00595/1 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
MCK: The hardware limit switch in positive traversing direction has tripped. <ul style="list-style-type: none"> • The <i>bLimitSwitchPos</i> input for travel range monitoring via positive hardware limit switch has been set to FALSE (fail-safe). 	Reset error message and retract limit switch.	

Ck02: Neg. HW limit switch [xx.0184.00002]

Response (Lenze setting printed in bold)	Setting: C00595/2 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☒ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
<p>MCK: The hardware limit switch in negative traversing direction has tripped.</p> <ul style="list-style-type: none"> The <i>bLimitSwitchNeg</i> input for travel range monitoring via negative hardware limit switch has been set to FALSE (fail-safe). 	Reset error message and retract limit switch.

Ck15: Error status sign. brake [xx.0184.00005]

Response (Lenze setting printed in bold)	Setting: C00595/2 (☑ Adjustable response)
☐ 0: No Reaction ☐ 1: Fault ☐ 2: Trouble ☒ 3: TroubleQuickStop ☐ 4: WarningLocked ☐ 5: Warning ☐ 6: Information	
Cause	Remedy
<p>MCK: The status monitoring of the holding brake control has tripped.</p>	<ul style="list-style-type: none"> Check configuration of the <i>bMBrakeApplied</i> input for status detection of the brake (via a switching contact at the brake). Check wiring/function of the switching contact. Adapt waiting time (C02589/3). Deactivate status monitoring (via bit 5 in C02582).

Ck03: Pos. SW limit position [xx.0184.00007]

Response (Lenze setting printed in bold)	Setting: C00595/3 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☒ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
<p>MCK: The device has detected that the position is outside the positive software limit position (C01229/1).</p>	<ul style="list-style-type: none"> Increase permissible traversing range (change setting of the software limit positions). Deactivate software limit position monitoring.

Ck04: Neg. SW limit position [xx.0184.00008]

Response (Lenze setting printed in bold)	Setting: C00595/4 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☒ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
<p>MCK: The device has detected that the position is outside the negative software limit position (C01229/2).</p>	<ul style="list-style-type: none"> Increase permissible traversing range (change setting of the software limit positions). Deactivate software limit position monitoring.

Ck14: Target position outside SW limit position [xx.0184.00015]

Response (Lenze setting printed in bold)	Setting: C00595/14 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☒ 3: TroubleQuickStop ☒ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
<p>MCK: It has been attempted to position a target outside the software limit positions (C01229/1 and C01229/2).</p>	<ul style="list-style-type: none"> Select a target within the software limit positions. Increase permissible traversing range (change setting of the software limit positions). Deactivate software limit position monitoring.

Ck16: Time overflow manual operation [xx.0184.00064]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
PC manual control: The connection monitoring has tripped. • The online connection between the PC and the controller has been interrupted for a longer period of time than the timeout set in C00464/1 .	<ul style="list-style-type: none"> • Check communication link between PC and controller. • Check voltage supply/function of the controller. • Adjust the timeout (C00464/1).

Ck05: Following error 1 [xx.0184.00153]

Response (Lenze setting printed in bold)		Setting: C00595/5 <input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
MCK: Following error limit 1 (C01215/1) has been exceeded.	<ul style="list-style-type: none"> • Optimise control mode. • Increase following error limit. • Deactivate following error monitoring. 	

Ck06: Following error 2 [xx.0184.00154]

Response (Lenze setting printed in bold)		Setting: C00595/6 <input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
MCK: Following error limit 2 (C01215/2) has been exceeded.	<ul style="list-style-type: none"> • Optimise control mode. • Increase following error limit. • Deactivate following error monitoring. 	

Ck07: Travel range limit exceeded [xx.0184.00155]

Response (Lenze setting printed in bold)		Setting: C00595/7 <input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
MCK: The maximum travel distance has been exceeded. • The maximum travel distance is displayed in C01213/1 .	<ul style="list-style-type: none"> • Check profile parameters. • Deactivate travel range limit monitoring. 	

Ck08: Home position unknown [xx.0184.00156]

Response (Lenze setting printed in bold)		Setting: C00595/8 <input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
MCK: Home position is unknown.	Perform homing.	

Ck09: Positioning mode invalid [xx.0184.08005]

Response (Lenze setting printed in bold)		Setting: C00595/9 <input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
MCK: The positioning mode defined via the <i>wPosProfileMode</i> input is not supported.	Define a valid positioning mode.	

Ck10: Implausible profile data [xx.0184.08007]

Response (Lenze setting printed in bold)	Setting: C00595/10 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
<p>Cause 1: The profile data result in a braking distance that is longer than the distance to be travelled.</p> <ul style="list-style-type: none"> Occurs if a small specified distance within a few increments is to be positioned with final speed and S rounding. It has been detected that the braking distance required for sizing the profile phases correctly regarding the S rounding and overchange is longer than the selected distance in the first cycle when <i>bExecute</i> = TRUE. <p>Cause 2: Reversing process in overchange profile linkage</p> <ul style="list-style-type: none"> If the linkage of two profiles with final speed causes a reversing process in the second profile and this is to smooth another sequence profile with final speed too, the error is set and ramped down to standstill. <p>Cause 3: Final speed at overchange is higher than maximum profile speed</p> <p>Cause 4: Traversing, accelerating or braking is not possible due to 0-parameters for speed, acceleration or deceleration.</p>	<p>On cause 1:</p> <ul style="list-style-type: none"> Set the S rounding to zero for the respective profile and go to the next profile with final speed zero. <p>On cause 2:</p> <ul style="list-style-type: none"> The continuous profile linkage with overchange must not provide any reversing process due to the profile selection. Here, the profile which causes a reversing must be defined with the final speed 0. <p>On cause 3:</p> <ul style="list-style-type: none"> Profiles in an overchange profile linkage with final speeds higher than their max. profile speeds are not supported. The final speed of a profile is limited internally to the max. profile speed in the profile data set. <p>On cause 4:</p> <ul style="list-style-type: none"> Ensure that the corresponding profile parameters for speed, acceleration and deceleration are set to non-zero when starting a traversing process.

Ck11: Invalid operating mode [xx.0184.08009]

Response (Lenze setting printed in bold)	Setting: C00595/11 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
MCK: The operating mode defined via the <i>wMckOperationMode</i> input is not supported.	Define a valid operating mode.

Ck12: Invalid profile number [xx.0184.08014]

Response (Lenze setting printed in bold)	Setting: C00595/12 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
MCK: The positioning profile number in the positioning operating mode specified via the <i>wPosProfileNo</i> input is invalid.	Define a valid profile number.

Ck13: Error - MCKCtrlInterface function block [xx.0184.08015]

Response (Lenze setting printed in bold)	Setting: C00595/13 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☐ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
MCK: An error in the L_MckCtrlInterface_1 function block has occurred.	Check wiring and parameterisation of the L_MckCtrlInterface_1 function block.

dH09: EEPROM power section [xx.0400.00009]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Device error	Consultation with Lenze required.

dH10: Fan failure [xx.0400.00016]

Response (Lenze setting printed in bold)		Setting: C00566 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information		
Cause	Remedy	
The device fan has failed. Possible causes: <ul style="list-style-type: none"> • The short-circuit check of the fan connection has tripped. • The speed monitoring of the fan has tripped. 	<ul style="list-style-type: none"> • Check the fan for short-circuit. • Clean the fan. 	

dH68: Adjustment data error CU [xx.0400.00104]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Device error	Consultation with Lenze required.

dH69: Adjustment data error BU [xx.0400.00105]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Device error	Consultation with Lenze required.

dH70: ControlUnit is unequal to BaseUnit [xx.0400.00106]

Response (Lenze setting printed in bold)	
<input type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input type="checkbox"/> 2: Trouble <input type="checkbox"/> 3: TroubleQuickStop <input type="checkbox"/> 4: WarningLocked <input type="checkbox"/> 5: Warning <input type="checkbox"/> 6: Information	
Cause	Remedy
Device error	Consultation with Lenze required.

User error 1 [xx.0980.00000 ... xx.0980.65535]

Response (Lenze setting printed in bold)		Setting: C00581/1 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input checked="" type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information		
Cause	Remedy	
User error 1 has been tripped via the <i>bSetError1</i> input of the LS_SetError_1 system block.	User-defined.	

User error 2 [xx.0981.00000 ... xx.0981.65535]

Response (Lenze setting printed in bold)	Setting: C00581/2 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
User error 2 has been tripped via the <i>bSetError2</i> input of the LS_SetError_1 system block.	User-defined.

User error 3 [xx.0982.00000 ... xx.0982.65535]

Response (Lenze setting printed in bold)	Setting: C00581/3 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
User error 3 has been tripped via the <i>bSetError3</i> input of the LS_SetError_1 system block.	User-defined.

User error 4 [xx.0983.00000 ... xx.0983.65535]

Response (Lenze setting printed in bold)	Setting: C00581/4 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
User error 4 has been tripped via the <i>bSetError4</i> input of the LS_SetError_1 system block.	User-defined.

User error 5 [xx.0984.00000 ... xx.0984.65535]

Response (Lenze setting printed in bold)	Setting: C00581/5 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
User error 5 has been tripped via the <i>bSetError1</i> input of the LS_SetError_2 system block.	User-defined.

User error 6 [xx.0985.00000 ... xx.0985.65535]

Response (Lenze setting printed in bold)	Setting: C00581/6 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
User error 6 has been tripped via the <i>bSetError2</i> input of the LS_SetError_2 system block.	User-defined.

User error 7 [xx.0986.00000 ... xx.0986.65535]

Response (Lenze setting printed in bold)	Setting: C00581/7 (☑ Adjustable response)
☑ 0: No Reaction ☑ 1: Fault ☑ 2: Trouble ☑ 3: TroubleQuickStop ☑ 4: WarningLocked ☑ 5: Warning ☑ 6: Information	
Cause	Remedy
User error 7 has been tripped via the <i>bSetError3</i> input of the LS_SetError_2 system block.	User-defined.

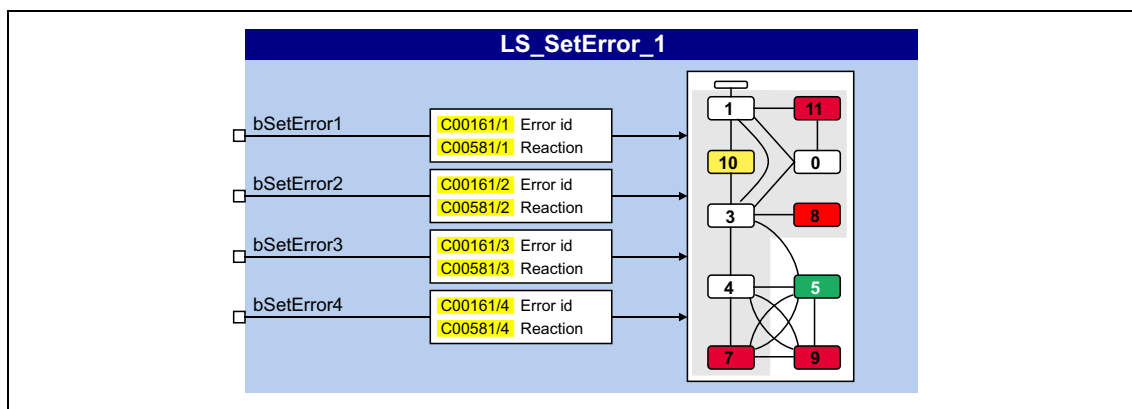
User error 8 [xx.0987.00000 ... xx.0987.65535]

Response (Lenze setting printed in bold)	Setting: C00581/8 (<input checked="" type="checkbox"/> Adjustable response)
<input checked="" type="checkbox"/> 0: No Reaction <input checked="" type="checkbox"/> 1: Fault <input checked="" type="checkbox"/> 2: Trouble <input checked="" type="checkbox"/> 3: TroubleQuickStop <input checked="" type="checkbox"/> 4: WarningLocked <input checked="" type="checkbox"/> 5: Warning <input checked="" type="checkbox"/> 6: Information	
Cause	Remedy
User error 8 has been tripped via the <i>bSetError4</i> input of the LS_SetError_2 system block.	User-defined.

10.10 "LS_SetError_1" system block

This system block is used for error handling within the application.

- The application can trip up to four different user error messages with parameterisable error IDs and error responses via the four boolean inputs.
- If several inputs are set to TRUE at the same time, the input with the lowest number will trip the error message.



Inputs

Identifier	Data type	Information/possible settings
bSetError1	BOOL	Input for tripping " User error 1 " <ul style="list-style-type: none"> • Error subject number: 980 • Error number: $(C00581/1 \times 0x0400000) + (980 \times 0x10000) + (C00161/1)$
bSetError2	BOOL	Input for tripping " User error 2 " <ul style="list-style-type: none"> • Error subject number: 981 • Error number: $(C00581/2 \times 0x0400000) + (981 \times 0x10000) + (C00161/2)$
bSetError3	BOOL	Input for tripping " User error 3 " <ul style="list-style-type: none"> • Error subject number: 982 • Error number: $(C00581/3 \times 0x0400000) + (982 \times 0x10000) + (C00161/3)$
bSetError4	BOOL	Input for tripping " User error 4 " <ul style="list-style-type: none"> • Error subject number: 983 • Error number: $(C00581/4 \times 0x0400000) + (983 \times 0x10000) + (C00161/4)$

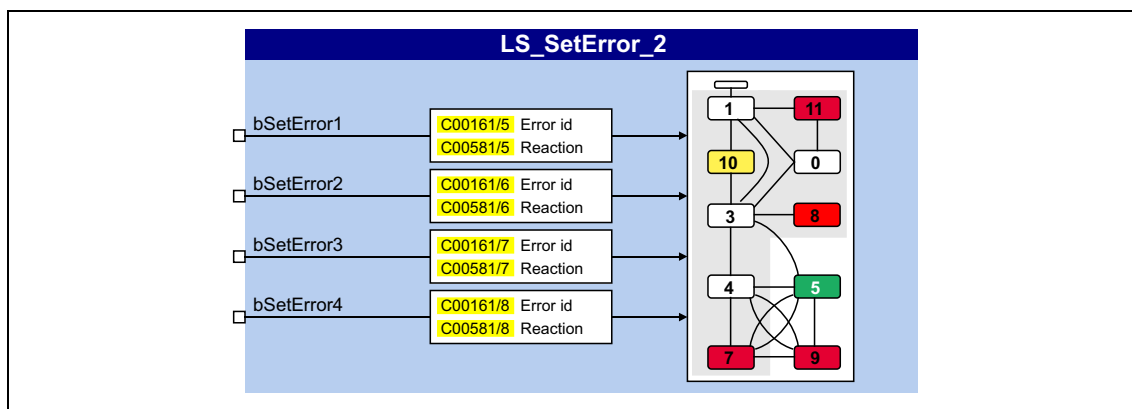
Parameter

Parameter	Possible settings			Info
C00161/1...4	0	...	65535	Error ID for user errors 1 ... 4
C00581/1...4				Response to user errors 1 ... 4
	0	No Reaction		
	1	Fault		
	2	Trouble		
	3	TroubleQuickStop		
	4	WarningLocked		
	5	Warning		
	6	Information		

10.11 "LS_SetError_2" system block

This system block is used for error handling within the application.

- The application can trip up to four different user error messages with parameterisable error IDs and error responses via the four boolean inputs.
- If several inputs are set to TRUE at the same time, the input with the lowest number will trip the error message.



Inputs

Identifier	Data type	Information/possible settings
bSetError1	BOOL	Input for tripping " User error 5 " <ul style="list-style-type: none"> • Error subject number: 984 • Error number: $(C00581/5 \times 0x0400000) + (984 \times 0x10000) + (C00161/5)$
bSetError2	BOOL	Input for tripping " User error 6 " <ul style="list-style-type: none"> • Error subject number: 985 • Error number: $(C00581/6 \times 0x0400000) + (985 \times 0x10000) + (C00161/6)$
bSetError3	BOOL	Input for tripping " User error 7 " <ul style="list-style-type: none"> • Error subject number: 986 • Error number: $(C00581/7 \times 0x0400000) + (986 \times 0x10000) + (C00161/7)$
bSetError4	BOOL	Input for tripping " User error 8 " <ul style="list-style-type: none"> • Error subject number: 987 • Error number: $(C00581/8 \times 0x0400000) + (987 \times 0x10000) + (C00161/8)$

Parameter

Parameter	Possible settings			Info
C00161/5...8	0	...	65535	Error ID for user errors 5 ... 8
C00581/5...8				Response to user errors 5 ... 8
	0	No Reaction		
	1	Fault		
	2	Trouble		
	3	TroubleQuickStop		
	4	WarningLocked		
	5	Warning		
	6	Information		

11 Oscilloscope function

[This function extension is available from version 12.00.00!](#)

The oscilloscope function integrated in the 8400 TopLine can be used as support for commissioning, maintenance, and troubleshooting. It is operated via a user interface in the »Engineer«.

Typical applications

- Graphical representation of measured values (e.g. speed setpoint, actual speed and torque)
- Detection of process values without additional measuring instruments (e.g. oscilloscope, voltmeter and ammeter)
- Convenient documentation for fine tuning of control circuits or parameter changes of the controller

Special features

- Recording and saving of measured values in the 8400 TopLine
- Simultaneous measuring on eight independent channels
- Measuring of fast and slow signals by means of adjustable sample rate
- Triggering on a channel
- Detecting of measured values before and after a trigger event (pre-/post-trigger)
- Transfer of the measured values to the Engineering PC for the graphical representation and evaluation in the »Engineer«
- The measured data represented in the form of interpolated curves can be optionally shown and hidden, represented in any colour or overlaid with the signal characteristics of other variables recorded.
- Cursor and zoom function for the measurement analysis
- Saving & loading of oscilloscope configurations on the Engineering PC
- Export of measured values via the clipboard for further processing

Functional description

In the »Engineer«, you set the trigger condition and sample rate and select the variables to be recorded via the oscilloscope user interface when an online connection to the 8400 TopLine has been established. In this case, "variables" are the internal output signals of the function, system, application and port blocks.

Every configuration change is transferred to the 8400 TopLine and checked. If invalid settings are found, the oscilloscope triggers an error.

With an online connection, the measured 8400 TopLine data are transferred to the »Engineer« and graphically represented on the oscilloscope user interface as soon as the measurement has been completed.

11.1

Technical data

Oscilloscope function of 8400 TopLine	
Number of channels	1 ... 8
Memory depth	Max. 8192 measured values, depending on the number of channels and the size of the variables to be recorded
Data width of a channel	Max. 32 bits, corresponding to the data type of the variable to be recorded
Sample rate	1 ms or a multiple thereof
Time base	5, 10, 20, 50, 100, 200, 500 ms or 1 s
Trigger level	Corresponding to the value range of the variable to be triggered
Trigger selection	The trigger is activated if the trigger value set for the respective channel is fallen short of or exceeded. The trigger value "must actually pass" the threshold.
Trigger delay	-100 % ... +400 %
Trigger source	Channel 1 ... 8

11.2 User interface

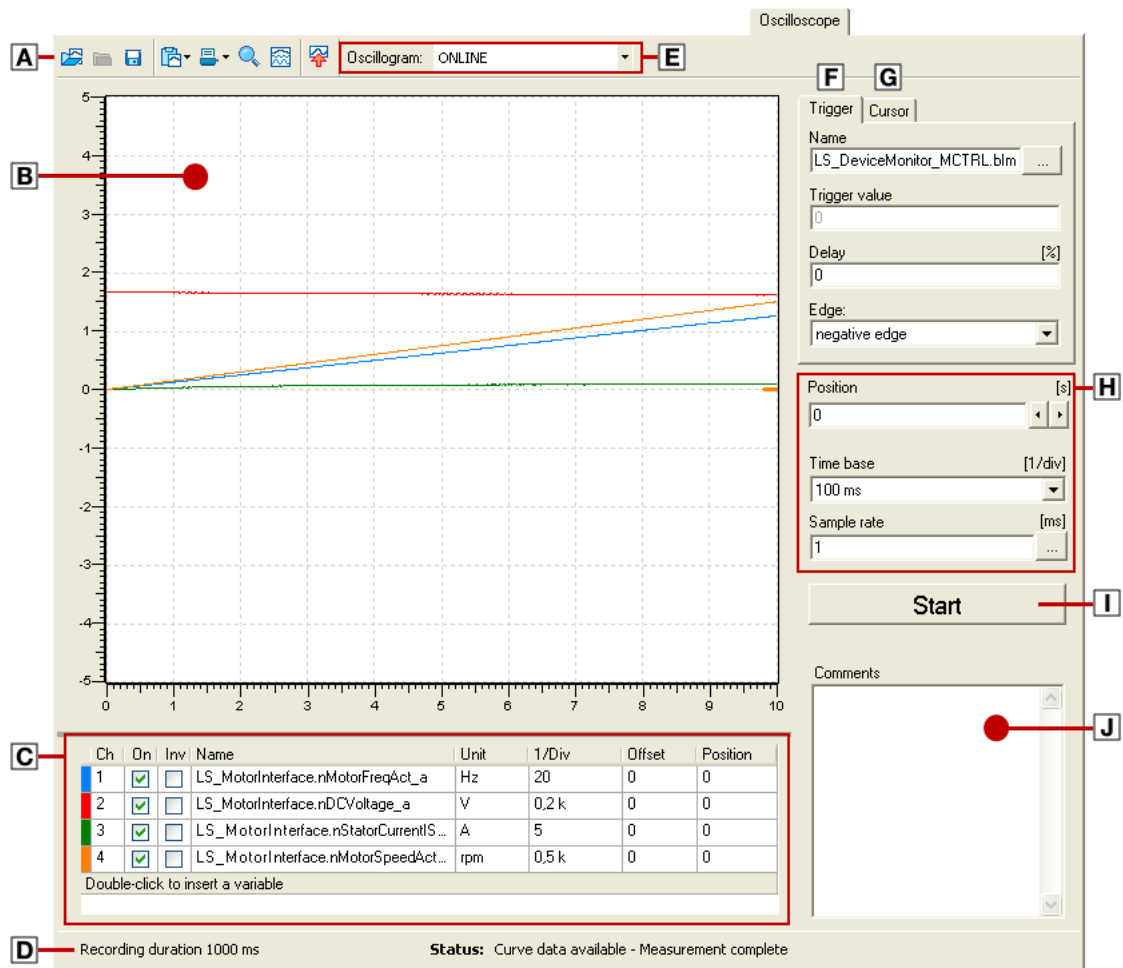
The oscilloscope user interface is available in the »Engineer« from version 2.16 onwards!



How to go to the oscilloscope user interface:

1. Go to the *Project* view and select the controller.
2. Select the **Oscilloscope** tab from the *Workspace*.

The oscilloscope user interface contains the following control and function elements:



A [Oscilloscope toolbar](#)

B Oscillogram

C Vertical channel settings
 ▶ [Selecting the variables to be recorded](#)

D Status bar

E [Oscillogram selection](#)

F [Trigger settings](#)









G [Cursor function: Reading individual measured values](#)

H Horizontal settings
 ▶ [Selecting the recording time/sample rate](#)

I [Starting recording](#)

J Input field for [comments](#)

Oscilloscope toolbar

Icon	Function
	Loading the oscillogram (📖 746)
	Closing the oscillogram (📖 747)
	Saving the oscillogram (📖 745)
	Copy to clipboard: Copy as text Copy as image <ul style="list-style-type: none"> • For documentation purposes, it is possible to copy the measured data of a data set as a table or, alternatively, the oscilloscope user interface as a picture, to the clipboard for use in other programs.
	Printer settings Print view Print
	Activate zoom function ▶ Adjusting the representation (📖 740)
	Activate automatic scaling function ▶ Adjusting the representation (📖 740)
	Load recorded oscillogram from device <ul style="list-style-type: none"> • Transfer data from the measured data memory of the 8400 TopLine to the Engineering PC as data set. • Only possible when an online connection has been established to the 8400 TopLine.

11.3 Operation

This chapter describes step-by-step how to record the signal characteristics of 8400 TopLine variables and represent, analyse, document and process them in the oscilloscope.



Note!

The oscilloscope can only be configured and recording can only be started when an online connection has been established to the 8400 TopLine.

11.3.1 Selecting the variables to be recorded

The oscilloscope supports up to eight channels, i.e. max. eight variables can be recorded in a data set.

The variables to be recorded can be configured by means of the **Vertical channel settings** list field. Four variables have already been selected in the default setting:

Ch	On	Inv	Name	Unit	1/Div	Offset	Position
1	<input checked="" type="checkbox"/>	<input type="checkbox"/>	LS_MotorInterface.nMotorFreqAct_a	Hz	20	0	0
2	<input checked="" type="checkbox"/>	<input type="checkbox"/>	LS_MotorInterface.nDCVoltage_a	V	0,2 k	0	0
3	<input checked="" type="checkbox"/>	<input type="checkbox"/>	LS_MotorInterface.nStatorCurrentIS...	A	5	0	0
4	<input checked="" type="checkbox"/>	<input type="checkbox"/>	LS_MotorInterface.nMotorSpeedAct...	rpm	0,5 k	0	0

Double-click to insert a variable

Column	Name	Meaning
1	-	Curve colour for representation in the oscillogram
2	Ch	Channel number
3	On	On/off
4	Inv	On/off inversion
5	Name	Selection of the variable to be recorded
6	Unit	Scaling
7	1/Div	Vertical scaling factor
8	Offset	Offset value <ul style="list-style-type: none"> The offset value depends on the scaling factor. It is indicated by a dashed line in the colour of the curve on the left-hand edge of the oscillogram.
9	Position	Position value <ul style="list-style-type: none"> The position value is independent of the scaling factor. It is indicated by a line on the left-hand edge of the oscillogram.

**How to change a selection:**

1. Go to the **Vertical channel settings** list field and double-click the variable to be changed in the **Name** column.
2. Select a new variable in the *Select variable* dialog box.
3. Click **Ok**.
 - The dialog box is closed and the selection is accepted.

**How to delete a selection:**

1. Go to the **Vertical channel settings** list field and right-click the variable to be removed to open the *context menu*.
2. Select the **Delete** command from the *context menu*.

If not all available channels are assigned, you can add more variables for recording.

**How to add more variables for recording:**

1. Double-click the bottom line highlighted in grey in the **Vertical channel settings** list field.
2. Select the desired variable in the *Select variable* dialog box.
3. Click **Ok**.
 - The dialog box is closed and the selection is accepted.

11.3.2 Selecting the recording time/sample rate

**How to select the recording time and the sample rate:**

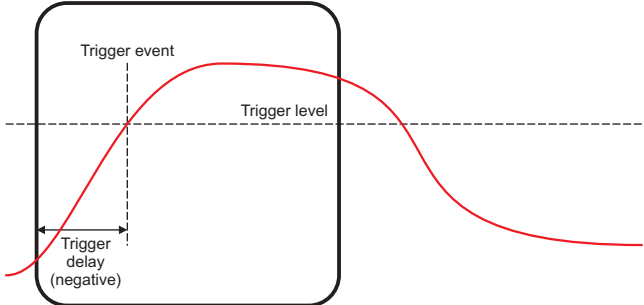
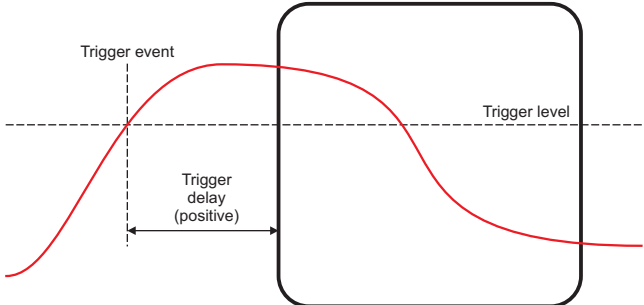
1. Select the desired time base from the **Time base** list field.
 - The current time base setting multiplied by ten results in the recording time.
 - Since the measured data memory of the 8400 TopLine has a limited capacity, usually a compromise is made between sample rate and recording time.
2. Enter the desired sample rate in [ms] in the **Sample rate** input field.

11.3.3 Defining the trigger condition

The trigger condition serves to define the starting time of recording in the 8400 TopLine. The oscilloscope provides various trigger conditions by means of which recording of the measured values can be controlled.



If the **Cursor** tab is selected, click the **Trigger** tab to show the input fields for configuring the trigger condition.

Setting	Function
Source	Selection of trigger source:
Channel	The oscilloscope triggers on a channel configured in the Vertical channel settings list field.
Force trigger	No trigger condition, recording starts immediately after the start.
Trigger value	Value from which on triggering is activated.
Delay	Delay between recording and trigger event.
Pre-trigger	<p>Select a negative delay time to detect signals prior to the trigger event.</p>  <ul style="list-style-type: none"> • In the oscillogram, the trigger time is marked by a dashed line. • When triggering on occurrence of an event, it is thus possible to detect the values that have caused the event.
Post-trigger	<p>Select a positive delay time to detect signals occurring a certain time after the trigger event.</p> 
Edge	Three trigger modes are available:
Positive edge	For trigger activation, the selected trigger value must first be fallen short of and then be exceeded.
Negative edge	For trigger activation, the selected trigger value must first be exceeded and then be fallen short of.
Change	<p>For triggering on a BOOL variable:</p> <ul style="list-style-type: none"> • Trigger activation requires a state change. <p>For triggering on a different variable:</p> <ul style="list-style-type: none"> • For trigger activation, the current value must be different than the last value.

11.3.4 Starting recording



Note!

Recording can only be started when an online connection has been established to the 8400 TopLine.



Click **Start** to start recording.

To obtain a maximum sample rate when recording the variable values, the data are first stored in the measured data memory of the 8400 TopLine and then transferred as a data set to the Engineering PC. The current recording status is displayed in the status bar.

11.3.5 Adjusting the representation

After the variable values have been recorded and the online data set has been transferred to the Engineering PC, the data set is visualised in the oscillogram. If required, the representation can now be adjusted by using the zoom or the automatic scaling function.



Tip!

When the oscillogram does not show the complete measurement, a scrollbar appears below the time axis. You can use this scrollbar for horizontal scrolling of the visible area. The labelling of the time axis and the position display are automatically adapted.

Selection of the horizontal display position

The **Position** input field can be used to change the horizontal display position.

- The position value can be directly entered into the input field or selected using the arrow buttons.
- When the arrow buttons are used and the <Ctrl> key is pressed, you can increase the step size to accelerate the shift.


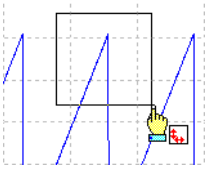






Subsequently changing the time base

Change the time base to stretch or compress measurements that have already been completed.

Zoom function




Go to the *oscilloscope toolbar* and click the icon to activate the zoom function.

Zoom function	Procedure	
Zoom selection		<p>Hold down the left mouse button and draw the oscillogram section to be zoomed:</p>  <ul style="list-style-type: none"> • While being drawn, the selection is shown with a frame. • When the left mouse button is released, the selection is zoomed in the oscillogram.
Horizontal/vertical shift of selection		<p>Hold down the left and right mouse button and move the mouse pointer on the scale to shift the selection accordingly. With a three-button mouse, you can use the mouse button in the middle.</p>
Horizontal stretching	On the horizontal scale:	
		Hold down the left mouse button and move the mouse pointer to the left to stretch the shown selection from the right edge.
		Hold down the right mouse button and move the mouse pointer to the right to stretch the shown selection from the left edge.
Moving the mouse pointer in opposite direction continuously reduces the stretching.		
Vertical stretching	On the vertical scale:	
		Hold down the left mouse button and move the mouse pointer to the bottom to stretch the shown selection from the top.
		Hold down the right mouse button and move the mouse pointer to the top to stretch the shown selection from the bottom.
Moving the mouse pointer in opposite direction continuously reduces the stretching.		
Return to original representation		Click the right mouse button in the oscillogram to return step by step to the original representation.

Automatic scaling function

Use the automatic scaling function to automatically scale and reposition the representation of selectable signal characteristics in the oscillogram and reset the offset to "0".

**How to carry out automatic scaling:**

1. Go to the *oscilloscope toolbar* and click the  icon to activate the automatic scaling function.
2. Select the channels/variables for automatic scaling in the *Select variable* dialog box.
3. Click **Ok**.
 - The dialog box is closed and the selected channels/variables are scaled automatically.

11.3.6 Cursor function: Reading individual measured values

In addition to the zoom and scaling function, the oscilloscope offers a "cursor function" that can be used to display individual measured values of a selectable channel or the difference between two measured values.



How to use the cursor function:

1. Click the **Cursor** tab to display it in the foreground and activate the cursor function.
 - Now two movable vertical measuring lines are shown in the oscillogram.
2. Select the channel for which individual measured values are to be indicated from **Channel** list field.
3. Hold down the left mouse button and drag the red vertical measuring line to the desired position.
 - The active measuring line is represented by a continuous line, the inactive measuring line is represented by a dashed line.
 - If you position the mouse pointer over the inactive measuring line, the measuring line automatically becomes active.
 - The value measured at the position of the active measuring line is indicated in the **Value** group box.
 - The difference between the values measured at the two measuring lines is indicated in the **Difference** group box.
 - Comparing peak values: Several values displayed in the oscillogram can be compared by means of a horizontal measurement line. This measurement line is automatically generated based on the current cursor position and thus cannot be moved separately.

11.4 Managing oscillograms (measured data sets)

If several measured data sets are loaded in the oscilloscope at the same time, the data set to be displayed is selected via the **Oscillogram** list field. There are three types of data sets:

Online data record

The ONLINE data set is the only data set which can be used to establish a connection to the target system to carry out an oscilloscope measurement.

Offline data record

The OFFLINE data set is a data set already stored in the project or a data set imported from a file.

- The configuration of the OFFLINE data set can be reused for future recordings.
- The OFFLINE data set is displayed in the **Oscillogram** list field with the name assigned to it upon saving.



Merge data record

The MERGE data set is automatically available in the **Oscillogram** list field if two or more data sets are loaded in the oscilloscope at the same time.

- In the merge data record, several characteristics from the currently loaded data records can overlaid, e.g. to compare signal characteristics from different recordings. ▶ [Overlay function](#) (📖 747)

11.4.1 Commenting the oscillogram

In the **Comments** text field, you can enter a comment on the oscillogram selected.

- When the  [Saving the oscillogram](#) command is executed, the comment is saved in the file together with the data set.
- If you execute the  [Loading the oscillogram](#) command and then select a data set in the *Load data set* dialog box, the corresponding comment is shown in the dialog box.

11.4.2 Saving the oscillogram

After the variables to be recorded have been selected and the required settings have been entered, you can save the configuration and recording, if already executed, for future use in the project or export them to a file.




Note!

The reuse of a saved configuration is only reasonable for controllers of the same type, as otherwise due to a scaling of the oscilloscope channels that is not adapted, incorrect values are displayed!



How to save the data set in the project:

1. Click the  icon in the *oscilloscope toolbar*.
 - The *Save data set* dialog box appears.
2. Enter a name in the **Name of the data set to be stored** input field.
3. Click **Filing in the project**.
 - The dialog box is closed and the current data set is filed in the project.




Note!

The data set is only saved if the entire project is saved!



How to export the data set to a file:

1. Click the  icon in the *oscilloscope toolbar*.
 - The *Save data set* dialog box appears.
2. Enter a name in the **Name of the data set to be stored** input field.
3. Click the **Export to file** button.
4. Specify the filing folder and the file name of the data set to be stored in the *Save as* dialog box.
5. Click **Save**.
 - The dialog box is closed and the current data set is saved.

11.4.3 Loading the oscillogram

Configurations/data sets already stored can be reloaded into the oscilloscope any time, e.g. for the overlay function.




Note!

The reuse of a saved configuration is only reasonable for controllers of the same type, as otherwise due to a scaling of the oscilloscope channels that is not adapted, incorrect values are displayed!




How to load a data set from the project:

1. Click the  icon in the *oscilloscope toolbar*.
 - The *Load data set* dialog box appears.
2. Select the data set to be loaded from the upper list field.
3. If the data set is to be used as a configuration, select the option **as configuration....**
4. Click **Open**.
 - The dialog box is closed and the selected data set/configuration is loaded.
 - If the configuration to be loaded contains variables that are no longer available in the controller, these variables are automatically removed from the configuration.



How to import a data set from a file:


1. Click the  icon in the *oscilloscope toolbar*.
 - The *Load data set* dialog box appears.
2. Click the **Search...** button.
3. Select the file to be imported within the desktop environment from the *Open* dialog box.
4. If the data set is to be used as a configuration, select the option **as configuration....**
5. Click **Open**.
 - The dialog box is closed and the selected data set/configuration is imported.
 - If the configuration to be loaded contains variables that are no longer available in the controller, these variables are automatically removed from the configuration.

11.4.4 Closing the oscillogram

You can close an open offline data record at any time.

- After a data set is closed, it is no longer available in the **Oscillogram** list field. The oscilloscope automatically displays the ONLINE data set.
- If the closed data set was included in the MERGE data set, its channels will be removed from the MERGE data set.



Go to the *Oscilloscope toolbar* and click the  symbol to close the currently displayed offline data record.

11.4.5 Overlay function


The overlay function serves to lay several characteristics from the currently loaded data sets on top of each other, e.g. to compare signal characteristics from different recordings.

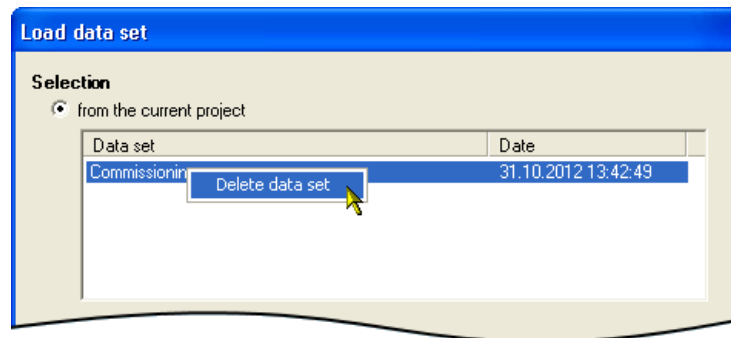
- If two or more data sets are loaded in the oscilloscope, e.g. the ONLINE data set and a data set saved before in the project, a "MERGE" data set is automatically provided in the **Oscillogram** list field.
- If the merge data record is selected, the desired characteristics to be overlaid or compared can be selected from the loaded data records in the **Vertical channel settings** group field.
- If an online data record is used in the merge data record, an update is carried out in the merge data record in case of a renewed recording.
- Removing variables from an offline or online data record causes the characteristics in the merge data record to be deleted.

11.4.6 Deleting a data set saved in the project



How to delete a data set saved in the project:

1. Click the  icon in the *oscilloscope toolbar*.
 - The *Load data set* dialog box appears.



2. In the upper list field, click the data set to be deleted using the right mouse button to open the *Context menu*.
3. In the *Context menu*, select the **Delete data set** command to delete the data set in the project.
4. Click **Cancel** to close the *Load data set* dialog box again.

12 System bus "CAN on board"

The controller has an integrated CANopen interface ("CAN on board") which is used to exchange i.a. process data and parameter values between the nodes. Furthermore, other modules can be connected via this interface such as decentralised terminals, operator and input devices (HMIs), as well as external controls and host systems.

The interface transfers CAN objects following the CANopen communication profile (CiA DS301, version 4.02) developed by the umbrella organisation of CiA (CAN in Automation) in conformity with the CAL (CAN Application Layer).



Tip!

- In the »Engineer« parameter list and in the keypad, category **CAN**, you can find the parameters relevant for the CANopen interface classified in different subcategories.
- Information on CAN communication modules and CANopen interfaces of other Lenze devices is provided in the "CAN" communication manual in the Lenze library.

12.1 General information

For many years, the system bus (CAN) based on the CANopen communication profile has been integrated in Lenze controllers. Due to the lower number of data objects available, the functionality and compatibility of the previous system bus are lower as compared to CANopen. For parameter setting, two parameter data channels are always available to the user while CANopen provides only one active parameter channel.

The system bus (CANopen) of the Inverter Drives 8400 is a further development of the system bus (CAN) including the following properties:

- Full compatibility with CANopen DS301 V4.02.
- Support of the "Heartbeat" NMT slave function (DS301 V4.02)
- 1 or 2 parameterisable parameter data channels for transmitting SDOs (*Service Data Objects*)
- Up to four parameterisable process data channels (dependent on the device version) for transmitting PDOs (*Process Data Objects*)
 - All process data channels are functionally equivalent
 - Monitoring of the receive PDOs for data reception
- Adjustable error response to ...
 - physical CAN errors (frame, bit, ACK error)
 - bus-stop, bus working
 - absent PDOs
- Telegram counters for SDOs and PDOs
- Bus status diagnostics
- Boot-up telegram generation
- Emergency telegram generation
- Reset node telegram generation (for master configuration)
- Sync telegram generation and response to sync telegrams:
 - Data transmission/reception
 - Device-internal time base synchronisation
- Abort codes
- All CAN on board functions can be parameterised via codes
- Object directory (all mandatory functions, optional functions, indexes)

12.1.1 General data and application conditions

Range	Values
Communication profile	CANopen, DS301 V4.02
Communication medium	DIN ISO 11898
Network topology	Line terminated at both ends
Adjustable node addresses (max. number of nodes)	Depending on the number of SDO channels set in C00366 : <ul style="list-style-type: none"> • 1 SDO: Node address 1 ... 127 (max. 127 nodes) • 2 SDO: Node address 1 ... 63 (max. 63 nodes) • adjustable via DIP switches or via code C00350.
Adjustable baud rates	20, 50, 125, 250, 500, 1000 kbps <ul style="list-style-type: none"> • adjustable via DIP switches or via code C00351.

Range	Values
Process data	For "BaseLine C" version: <ul style="list-style-type: none"> • Max. 2 transmit PDOs (TPDOs) with 1 ... 8 bytes (adjustable) • Max. 2 receive PDOs (RPDOs) with 1 ... 8 bytes (adjustable)
	For "StateLine C" version: <ul style="list-style-type: none"> • Max. 4 transmit PDOs (TPDOs) with 1 ... 8 bytes (adjustable) • Max. 4 receive PDOs (RPDOs) with 1 ... 8 bytes (adjustable) (Process data channel 4 is available from version 15.00.00!)
Parameter data	Max. 2 server SDO channels with 1 ... 8 bytes <ul style="list-style-type: none"> • Because of the 2 server SDO channels, the address range from 1 ... 63 is available
Transfer mode for TPDOs	<ul style="list-style-type: none"> • in case of data change (including adjustable blocking time) • Time-controlled, 1 to x ms • After the reception of 1 to 240 sync telegrams

12.1.2 Supported protocols

Protocols	
Standard PDO protocols	PDO write PDO read
SDO protocols	SDO download SDO download initiate SDO download segment
	SDO upload SDO upload initiate SDO upload segment
	SDO abort transfer
	SDO block download SDO block download initiate SDO block download end
	SDO block upload SDO block upload initiate SDO block upload end
NMT protocols	Start remote node (master and slave)
	Stop remote node (slave)
	Enter pre-operational (slave)
	Reset node (slave and local device)
	Reset communication protocol (slave)
Monitoring protocols	Heartbeat (heartbeat producer and heartbeat consumer) <ul style="list-style-type: none"> • Up to 15 Heartbeat Producers can be monitored.
	Emergency telegram (to master)
More protocols	Transmitting and receiving a sync telegram <ul style="list-style-type: none"> • Synchronisation of the internal time base to the reception of the CAN sync telegram is possible. ▶ Synchronisation of the internal time base

12.1.3 Communication time

The communication time is the time between the start of a request and the arrival of the corresponding response.

**Tip!**

The communication times in the CAN network depend on:

- the processing time in the device
- the telegram runtime (baud rate/telegram length)
- the bus load (especially if the bus is charged with PDOs and SDOs at a low baud rate)

Processing time in the 8400 controller

No dependencies exist between parameter data and process data.

- Parameter data: approx. 5 ms (typical value)
 - For parameters concerning the motor control (e.g. C00011), the processing time may be longer (up to 30 ms).
- Process data: 1 ms

12.2 Possible settings via DIP switch

The following settings for the "CAN on board" system bus can be made via the front panel DIP switches:

DIP switch	Possible settings/detailed information
	a ... c ▶ Setting the baud rate
	1 ... 64 ▶ Setting the node address
	CA ▶ Activating the bus terminating resistor

Lenze setting: All DIP switches are in the "OFF" position



Note!

- The DIP switch settings are accepted if a node address is unequal zero when the device or the 24-V supply is switched on by the DIP address.
- If all DIP switches are OFF when the device or the 24 V supply is switched on, the setting of the baud rate and node address are read out of the parameter set/parameter.



Tip!

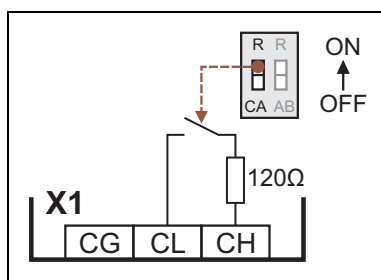
The current DIP switch settings are displayed in code [C00349](#).

Bit 15 indicates that the setting of the DIP switches has been accepted when the device or the 24V supply has been switched on.

12.2.1 Activating the bus terminating resistor

The system bus must be terminated between CAN low and CAN high at the first and last physical node each by a resistor (120 Ω).

The 8400 controller is provided with an integrated bus terminating resistor, which can be activated via the DIP switch labelled with "CA":



- OFF = bus terminating resistor is inactive
- ON = bus terminating resistor is active

[12-1] Activation of the integrated bus terminating resistor

12.2.2 Setting the baud rate

The baud rate can be set via code [C00351](#) or with the DIP switches a to c:



Note!

- All DIP switches (a ... c, 1 ... 64) = OFF (Lenze setting):
 - At switching on, the settings under code [C00350](#) (node address) and [C00351](#) (baud rate) will become active.
- Preset baud rate: 500 kbps

DIP switch position			Baud rate
c	b	A	
ON	OFF	ON	20 kbps
OFF	ON	ON	50 kbps
OFF	ON	OFF	125 kbps
OFF	OFF	ON	250 kbps
OFF	OFF	OFF	500 kbps
ON	OFF	OFF	1000 kbps

12.2.3 Setting the node address

The node address can be set via code [C00350](#) or with the DIP switches 1 to 64.

- The labelling on the housing corresponds to the values of the individual DIP switches for determining the node address.
- The valid address range depends on the number of SDO channels set in [C00366](#):
 - 1 SDO (Lenze setting): 1 ... 127
 - 2 SDO: 1 ... 63











Note!

- The addresses of the nodes must differ from each other.
- All DIP switches (a ... c, 1 ... 64) = OFF (Lenze setting):
 - At switching on, the settings under code [C00350](#) (node address) and [C00351](#) (baud rate) will become active.

Example: Setting of the node address 23

DIP switch	64	32	16	8	4	2	1
Switch position	OFF	OFF	ON	OFF	ON	ON	ON
Value	0	0	16	0	4	2	1
Node address	= Sum of the values = 16 + 4 + 2 + 1 = 23						



12.3**LED status displays for the system bus**

	CAN-RUN
	CAN-ERR
	DRV-RDY
	DRV-ERR
	AB-STATE
	
	
	USER

Information about the status of the system bus can be obtained quickly via LED displays "CAN-RUN" and "CAN-ERR" on the front of the controller.




The meaning can be seen from the tables below.

Controller is not (yet) active on the system bus




LED display	Meaning
 (CAN-ERR is permanently lit)	Controller is not active on the system bus / Bus Off
 (CAN-RUN and CAN-ERR flicker)	Automatic detection of baud rate is active

Controller is active on the system bus

- LED "CAN-RUN" signals the CANopen state:

LED display	CANopen state
 (CAN-RUN is blinking every 0.2 seconds)	Pre-Operational
 (CAN-RUN is permanently lit)	Operational
 (CAN-RUN is blinking every second)	Stopped

- LED "CAN-ERR" signals a CANopen error:

LED display	CANopen error
 (CAN-ERR is blinking once, then off for 1 second)	Warning Limit reached
 (CAN-ERR is blinking twice, then off for 1 second)	Node Guard Event
 (CAN-ERR is blinking three times, then off for 1 second)	Sync Message Error (only possible in the "Operational" state)

12.4 Going online via the system bus

The integrated system bus interface (CAN on board, X1 terminal) can also be used for the communication between the »Engineer« and the controller, alternatively to the USB diagnostic adapter.

- Lenze offers the following communication accessories for connection to the PC:

Communication accessories	PC interface
PC system bus adapter 2173 incl. connection cable and voltage supply adapter <ul style="list-style-type: none"> • for DIN keyboard connection (EMF2173IB) • for PS/2 keyboard connection (EMF2173IBV002) • for PS/2 keyboard connection with electrical isolation (EMF2173IBV003) 	Parallel interface (LPT port)
PC system bus adapter 2177 incl. connection cable (EMF2177IB)	USB (Universal Serial Bus)



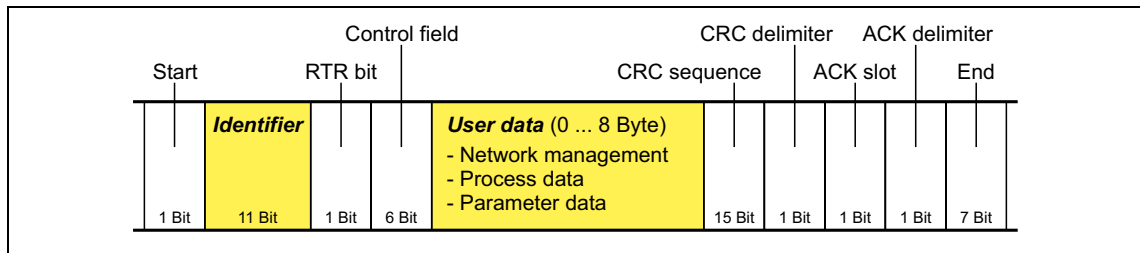
Note!

- For detailed information about the PC system bus adapter, please see the "CAN Communication Manual".
- Please observe the documentation for the PC system bus adapter!
- In the »Engineer«, go to the *Device assignment offline devices* dialog box and select the "System bus CAN" entry from the **Bus connection** list field to establish an online connection.

12.5 Reinitialising the CANopen interface

The [C00002/26](#) = "1: EOn / start" device command reinitialises the CANopen interface of the controller ("Reset node"), which is required after e.g. changing the data transfer rate, the node address or the identifiers, respectively.

12.6 Structure of the CAN data telegram



[12-2] Basic structure of the CAN telegram

The following subchapters provide a detailed description of the identifier and the user data. The other signals refer to the transfer characteristics of the CAN telegram whose description is not included in the scope of this documentation.



Tip!

Please visit the homepage of the CAN user organisation CiA (CAN in automation) for further information:

<http://www.can-cia.org>

12.6.1 Identifier

The principle of the CAN communication is based on a message-oriented data exchange between a transmitter and many receivers. All nodes can transmit and receive quasi-simultaneously.

The identifier, also called COB-ID (abbr. for communication object identifier), is used to control which node is to receive a transmitted message. In addition to the addressing, the identifier contains information on the priority of the message and the type of user data.

The identifier consists of a basic identifier and the node address of the node to be addressed:

Identifier (COB-ID) = basic identifier + node address (node ID)

Exception: The identifier for process data/heartbeat/emergency objects as well as network management and sync telegrams is freely assigned by the user (either manually or automatically by the network configurator), or is permanently assigned.

Node address (node ID)

Every node of the system bus network must be assigned to a node address (also called node ID) within the valid address range (1 ... 127) for unambiguous identification.

- Assigning a node address more than once within a network is impermissible.
- The own node address can be configured via the DIP switches or via code [C00350](#). ▶ [Setting the node address](#) (📖 754)

Identifier assignment

The system bus is message-oriented instead of node-oriented. Every message has an unambiguous identification, the identifier. For CANopen, node-oriented transfer is achieved by the fact that every message has only one transmitter.

- The basic identifiers for network management (NMT) and the basic SDO channel (SDO1) are defined in the CANopen protocol and cannot be changed.
- The basic identifiers of the PDOs are preset in the Lenze setting according to the "Predefined Connection Set" of DS301 V4.02.

Object		Basis identifier (CANBaseID)		Direction
Network management (NMT)		0	0x0000	
Sync ¹⁾		128	0x0080	
Emergency ¹⁾		128	0x0080	Device → system bus
PDO1 (Process data channel 1)	TPDO1	384	0x0180	Device → system bus
	RPDO1	512	0x0200	System bus → device
PDO2 (Process data channel 2)	TPDO2	640	0x0280	Device → system bus
	RPDO2	768	0x0300	System bus → device
PDO3 (Process data channel 3)	TPDO3	896	0x0380	Device → system bus
	RPDO3	1024	0x0400	System bus → device
PDO4 ²⁾ (Process data channel 4)	TPDO4	1152	0x0480	Device → system bus
	RPDO4	1280	0x0500	System bus → device
SDO1 (Parameter data channel 1)	TSDO1	1408	0x0580	Device → system bus
	RSDO1	1536	0x0600	System bus → device
SDO2 (Parameter data channel 2)	TSDO2	1472	0x05C0	Device → system bus
	RSDO2	1600	0x0640	System bus → device
Heartbeat		1792	0x0700	Device → system bus
Boot-up		1792	0x0700	Device → system bus

¹⁾ If you set the sync identifiers manually, observe the use of the emergency telegram, since it has the same COB-ID.
²⁾ [From version 15.00.00](#)



Tip!

If required, the identifiers of the PDOs and the identifiers for the sync telegram can be changed via parameters/indices.

▶ [Identifiers of the process data objects](#) (📖 778)

▶ [PDO synchronisation via sync telegram](#) (📖 782)

The active identifiers for the PDOs are displayed in [C00355/x](#).

12.6.2 User data

All nodes communicate by exchanging data telegrams via the system bus. The user data area of the CAN telegram either contains network management data or parameter data or process data:

Network management data

(NMT data)

- Control information on start, stop, reset, etc. of communication to specific nodes or to all nodes of the CAN network.

Process data

(PDOs – process data objects)

- Process data are transferred via the process data channel.
- Process data can be used to control the controller.
- Process data are not saved to the controller.
- Process data are transmitted between host system and nodes to ensure continuous exchange of current input and output data.
- Process data usually are unscaled/scalable raw data.
- Process data are, for instance, setpoints and actual values.
- The exact meaning of the PDO file contents is determined via the function block editor (FB Editor) in the I/O level or via the PDO mapping.

Parameter data

(SDOs – service data objects)

- Parameter data are the CANopen indexes or, in case of Lenze devices, the codes.
- Parameters are, for instance, used for one-off plant setting during commissioning or when the material is changed on a production machine.
- Parameter data are transmitted as SDOs via the parameter data channel. They are acknowledged by the receiver, i.e. the transmitter gets a feedback about the transmission being successful or not.
- The parameter data channel enables access to all Lenze codes and CANopen indexes.
- Parameter changes are automatically saved to the controller until mains switching.
- In general, the parameter transfer is not time-critical.
- Parameter data are, for instance, operating parameters, diagnostic information and motor data as well as control information on the interconnection of function blocks in the I/O level of the FB Editor.

12.7 Communication phases/network management

Regarding communication via the system bus, the controller distinguishes between the following statuses:

Status	Explanation
"Initialisation" (Initialisation)	After switch-on, an initialisation run is carried out. <ul style="list-style-type: none"> During this phase, the controller is not involved in the data exchange via the bus. The standard values are re-written to all CAN-relevant parameters. After initialisation is completed, the controller is automatically set to the "Pre-Operational" status.
"Pre-Operational" (before being ready for operation)	Parameter data can be received, process data are ignored.
"Operational" (ready for operation)	Parameter data and process data can be received!
"Stopped" (stopped)	Only network management telegrams can be received.

Communication object	Initialisation	Pre-Operational	Operational	Stopped
PDO			●	
SDO		●	●	
Sync		●	●	
Emergency		●	●	
Boot-up	●			
Network management (NMT)		●	●	●

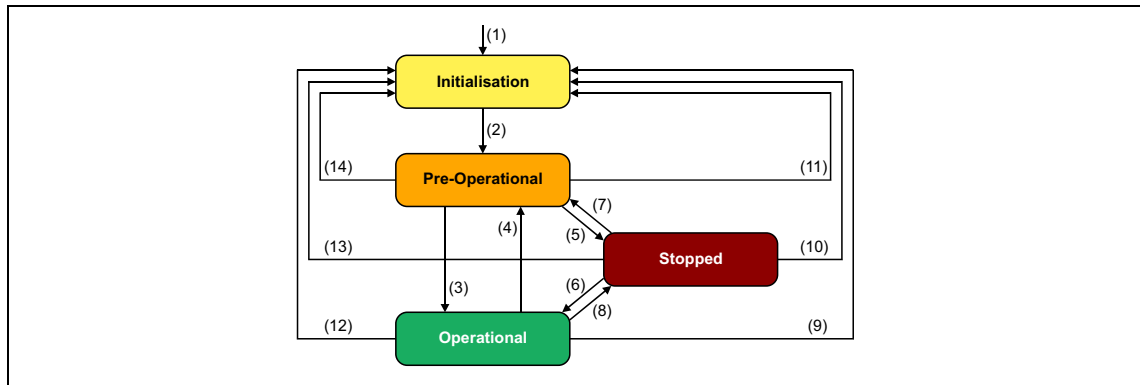


Tip!



Part of the initialisation or the entire initialisation can be carried out anew in every status by transferring the corresponding network management telegrams.

The current CAN status is displayed in [C00359](#) for diagnostic purposes.

12.7.1 Status transitions

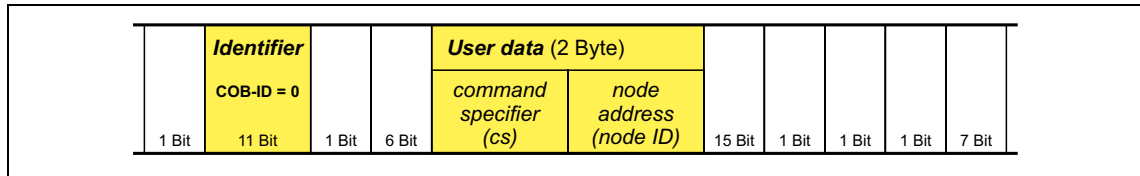


[12-3] NMT status transitions in the CAN network

Transition	NMT command	Status after change	Effects on process/parameter data after status change
(1)	-	Initialisation	Initialisation starts automatically when the mains is switched on. <ul style="list-style-type: none">During initialisation, the controller is not involved in the data exchange.After the initialisation is completed, the node sends a boot-up message with an individual identifier and automatically changes to the "pre-operational" status.
(2)	-	Pre-Operational	In this phase, the master determines the way in which the node(s) takes/take part in communication.
	From here, the master changes the statuses for the entire network. <ul style="list-style-type: none">A target address included in the NMT command defines the receiver(s).If the 8400 controller is configured as CAN master, the status is automatically changed to "Operational" after a waiting time has expired (C00356/1), and the 0x0100 ("Start remote node") NMT command is transmitted to all nodes.Data can only be exchanged via process data objects if the status is "Operational"!		
(3), (6)	0x01 xx Start remote node	Operational	Network management/sync/emergency telegrams as well as process data (PDO) and parameter data (SDO) are active. Optional: When the status is changed, event and time-controlled process data (PDOs) are transmitted once.
(4), (7)	0x80 xx Enter Pre-Operational	Pre-Operational	Network management/sync/emergency telegrams and parameter data (SDO) are active.
(5), (8)	0x02 xx Stop remote node	Stopped	Only network management telegrams can be received.
(9), (10), (11)	0x81 xx Reset node	Initialisation	All CAN-relevant parameters (CiA DS 301) are initialised with the saved values.
(12), (13), (14)	0x82 xx Reset communication		All CAN-relevant parameters (CiA DS 301) are initialised with the saved values.
	Meaning of the node address in the NMT command: <ul style="list-style-type: none">xx = 0x00: If this assignment is selected, the telegram addresses all nodes (broadcast telegram). The status of all nodes can be changed at the same time.xx = Node ID: If a node address is specified, only the status of the node with the corresponding address changes.		

12.7.2 Network management telegram (NMT)

The telegram for the network management contains identifier "0" and the command included in the user data which consists of the command byte and the node address:



[12-4] Network management telegram for changing over the communication phases

Command specifier (cs)		NMT command
dec	hex	
1	0x01	Start remote node
2	0x02	Stop remote node
128	0x80	Enter Pre-Operational
129	0x81	Reset node
130	0x82	Reset communication

The change-over of the communication phases for the entire network is carried out by one node, the CAN master. The function of the CAN master can also be carried out by the controller.

► [Parameterising the controller as CAN master](#) (📖 763)

Meaning of the node address in the user data:

- node ID = "0": The telegram addresses all nodes (broadcast telegram). The status of all nodes can be changed at the same time.
- node ID = "1" ... "127": If a node address is specified, only the status of the node with the corresponding address changes.

Example:

Data can only be exchanged via process data objects if the status is "Operational". If the CAN master is supposed to switch all nodes connected to the bus from the "Pre-Operational" communication status to the "Operational" communication status, the identifier and user data in the transmission telegram must be set as follows:

- Identifier: 0x00 (network management)
- User data: 0x0100 ("Start remote node" NMT command to all nodes)

12.7.3 Parameterising the controller as CAN master

If the initialisation of the system bus and the associated status change from "Pre-Operational" to "Operational" is not effected by a superimposed host system, the controller can instead be defined to be a "quasi" master to execute this task.

The controller is configured as CAN master in [C00352](#).

- Being the CAN master, the controller sets all nodes connected to the bus (broadcast telegram) to the "Operational" communication status with the "Start remote node" NMT telegram. Only in this communication status, data can be exchanged via process data objects.
- A delay time can be set in [C00356/1](#) which must expire after mains switching before the controller transmits the "Start remote node" NMT telegram.

Parameter	Info	Lenze setting	
		Value	Unit
C00352	CAN slave/master	Slave	
C00356/1	CAN delay boot-up - Operational	3000	ms



Note!

The changes of the master/slave operation in [C00352](#) will not be activated until

- another mains switching of the controller

or

- the "Reset node" or "Reset communication" NMT telegram has been transmitted to the controller.

The "CAN reset node" device command ([C00002/26](#)) is provided as an alternative to the "Reset node" NMT telegram for the reinitialisation of the CAN-specific device parameters.

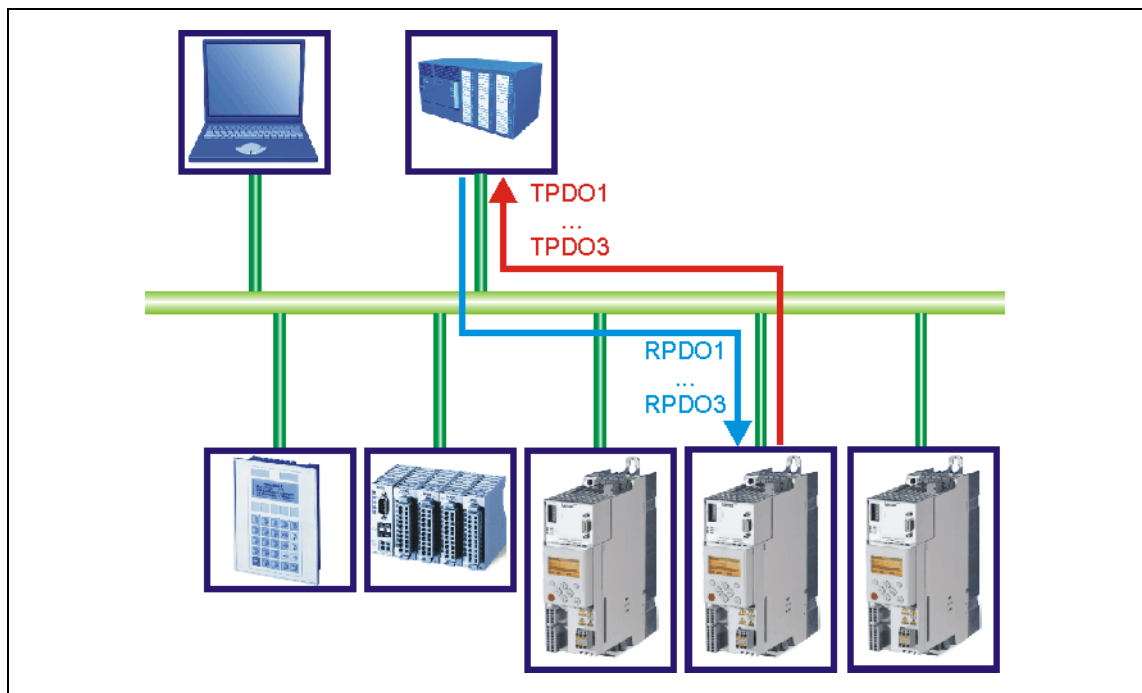


Tip!

Master functionality is only required during the initialisation phase of the drive system.

12.8

Process data transfer



[12-5] PDO data transfer from / to the higher-level host system

For transmitting process data, up to four separated process data channels (PDO1 ... PDO4) are available depending on the device version and software version.

Definitions

- Process data telegrams between the host system and the devices are distinguished in terms of direction as follows:
 - Process data telegrams to the device (RPDO)
 - Process data telegrams from the device (TPDO)
- The CANopen process data objects are designated as seen from the node's view:
 - Receive PDOs (RPDOx): Process data object received by a node
 - Transmit PDOs (TPDOx): Process data object sent by a node



Note!

Data can only be exchanged via process data objects if the status is "Operational"!

► [Communication phases/network management](#) (760)

12.8.1 Available process data objects

The number of available process data objects for controllers of the 8400 series depends on the device version:

Process data object	Version "BaseLine C"	from version "StateLine C"
RPDO1 Port block "LP_CanIn1"	●	●
RPDO2 "LP_CanIn2" port block	●	●
RPDO3 "LP_CanIn3" port block		●
RPDO4 "LP_CanIn4" port block		● (from version 15.00.00)
TPDO1 "LP_CanOut1" port block	●	●
TPDO2 "LP_CanOut2" port block	●	●
TPDO3 "LP_CanOut3" port block		●
TPDO4 "LP_CanOut4" port block		● (from version 15.00.00)

Receive PDOs (RPDOs)

The process data objects transmitted from the system bus to the drive are processed via the [LP_CanIn1](#) ... [LP_CanIn4](#) port blocks.

- Every port block provides 4 words (2 bytes/word). The data of every first word are provided in a bit decoded manner (bit 0 ... 15).
- The first word of the [LP_CanIn1](#) port block is defined as control word *wCtrl*. The *wCtrl* control word does not have a permanent connection to the device control and can be used as required. The predefined assignment of the *wCtrl* control word in the [C00007](#) = "30: CAN" control mode depends on the technology application selected in [C00005](#):
 - TA "Actuating drive speed":
[Process data assignment for fieldbus communication](#) (450)
 - TA "Table positioning":
[Process data assignment for fieldbus communication](#) (513)
 - TA "Abschaltpositionierung":
[Process data assignment for fieldbus communication](#) (539)

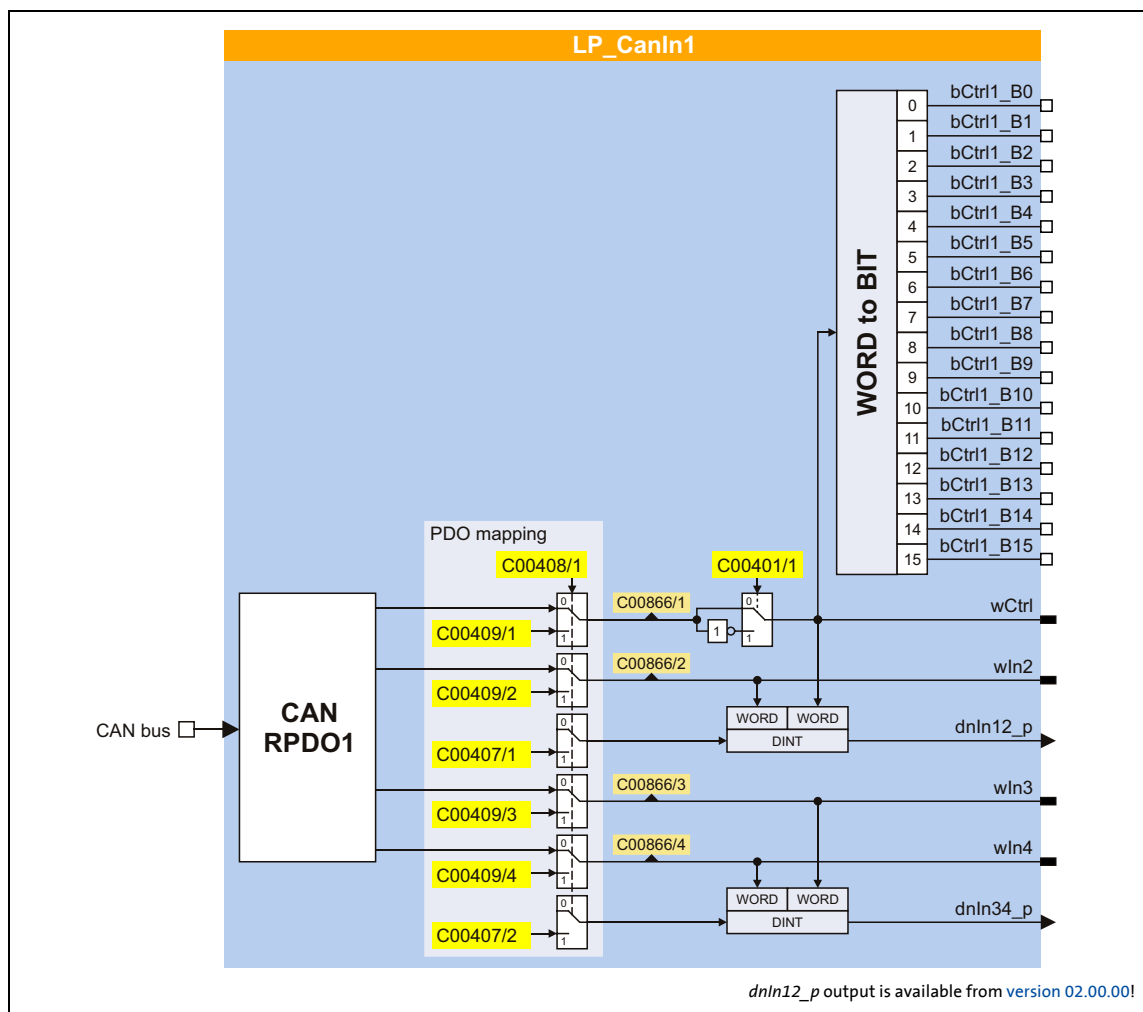
Transmit PDOs (TPDOs)

The process data transmitted from the drive to the system bus are processed via the [LP_CanOut1](#) ... [LP_CanOut4](#) port blocks.

- Every port block receives 4 words (2 bytes/word). The data of every first word are transmitted bit by bit (bit 0 ... 15).
- The first word of the [LP_CanOut1](#) port block is defined as the *wState* status word. The *wState* status word does not have a permanent connection to the device control and can be used as required.
 - Vordefinierte Belegung siehe [wDeviceStatusWord status word](#) der Antriebsschnittstelle.

12.8.1.1 RPDO1 | Port block "LP_CanIn1"

The LP_CanIn1 port block maps process data object RPDO1 in the FB Editor.



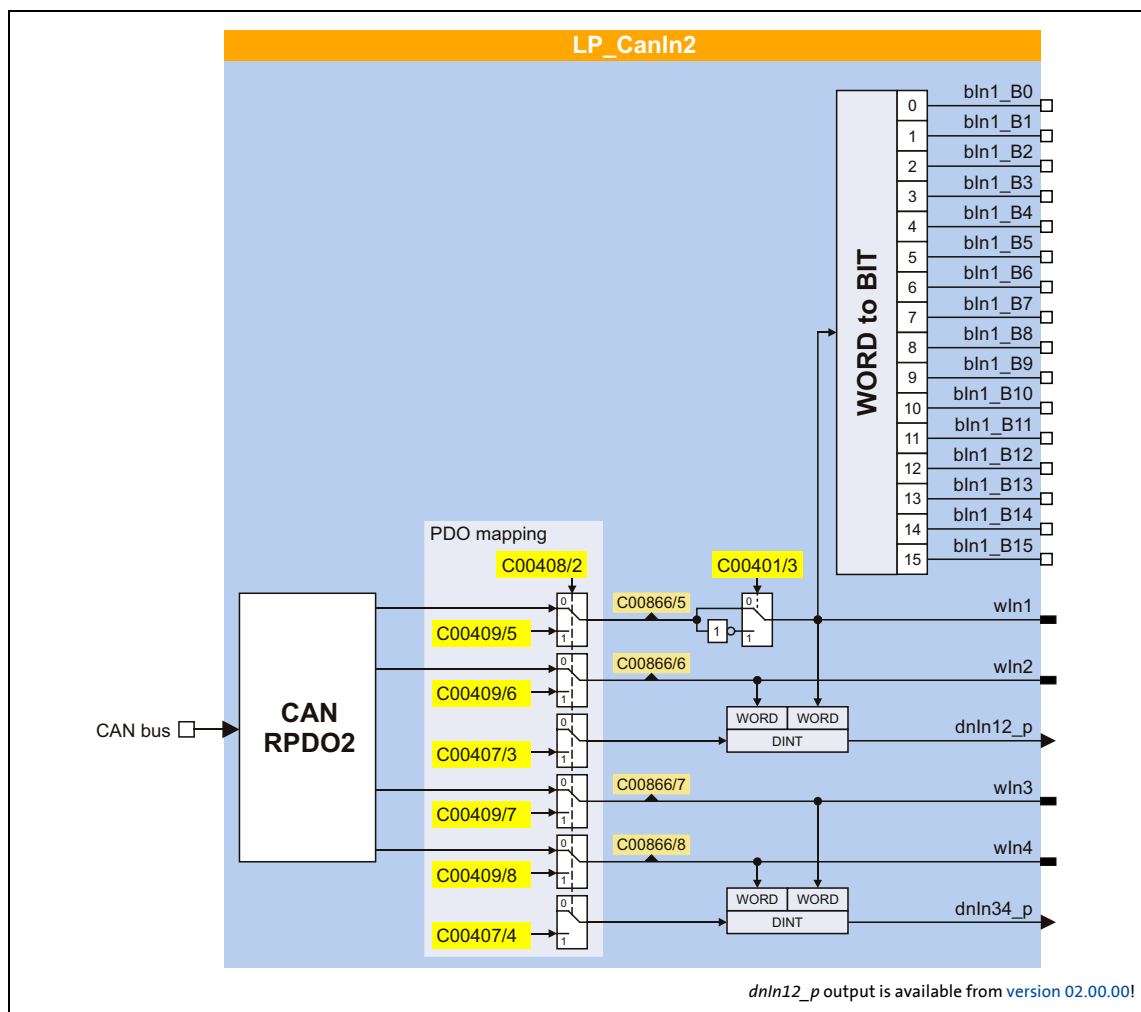
Short overview of the parameters for LP_CanIn1:

Parameter	Info	Lenze setting	
C00401/1	LP_CanIn1: Inversion bCtrl1_B0..15	0x0000	
C00866/1	LP_CanIn1: wCtrl	-	
C00866/2	LP_CanIn1: wIn2	-	
C00866/3	LP_CanIn1: wIn3	-	
C00866/4	LP_CanIn1: wIn4	-	
PDO mapping			
C00408/1	LP_CanIn1: Mapping selection	CanIn	
C00409/1	LP_CanIn1: wCtrl MapVal	0	
C00409/2	LP_CanIn1: wIn2 MapVal	0	
C00409/3	LP_CanIn1: wIn3 MapVal	0	
C00409/4	LP_CanIn1: wIn4 MapVal	0	
Highlighted in grey = display parameter			

Parameter	Info	Lenze setting
C00407/1	LP_CanIn1: dwIn12 MapVal • From version 12.00.00 • The mapping for the double word is ORed with the mapping setting in C00409/1 and C00409/2 .	0
C00407/2	LP_CanIn1: dwIn34 MapVal • From version 12.00.00 • The mapping for the double word is ORed with the mapping setting in C00409/3 and C00409/4 .	0
Highlighted in grey = display parameter		

12.8.1.2 RPDO2 | "LP_CanIn2" port block

The LP_CanIn2 port block maps process data object RPDO2 in the FB Editor.



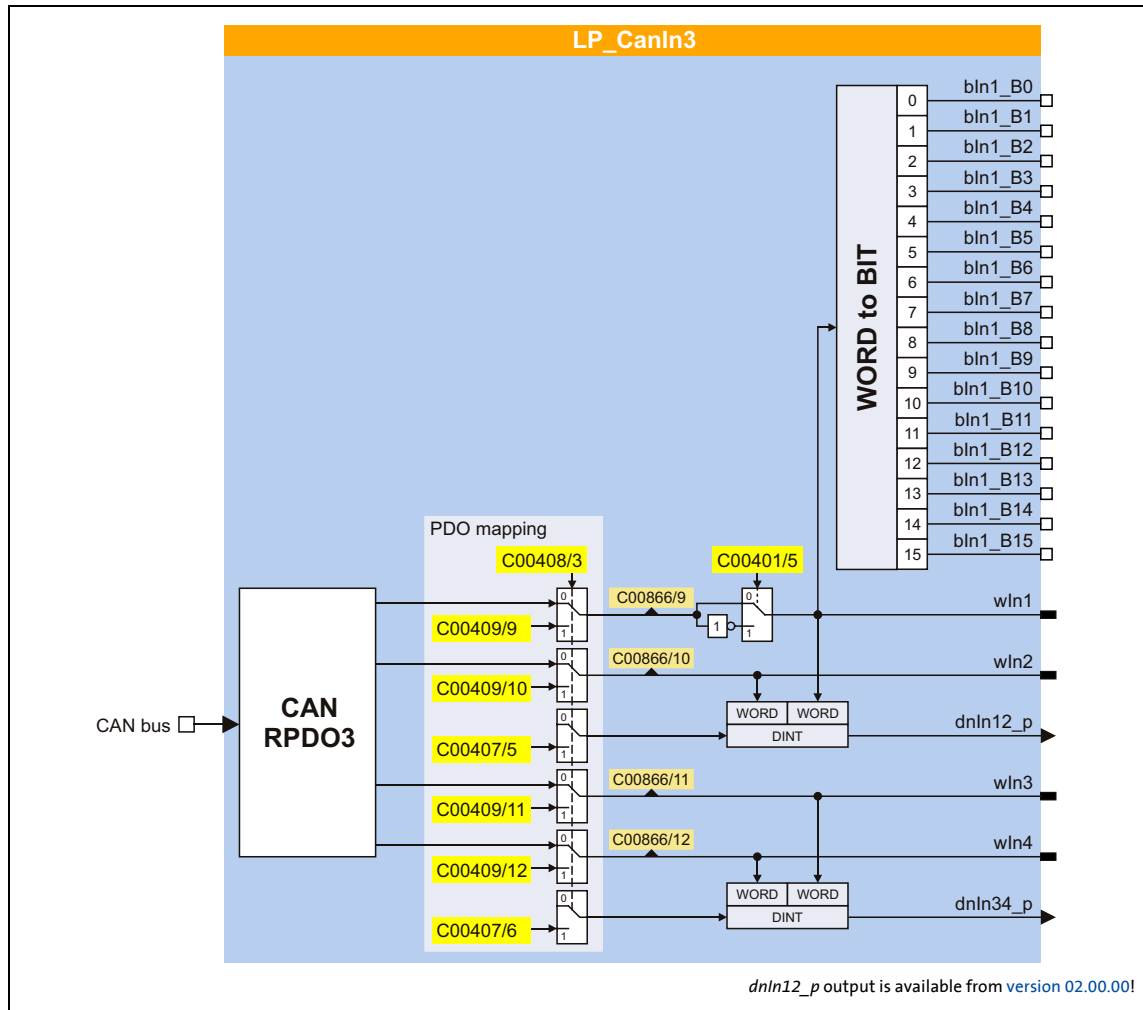
Short overview of the parameters for LP_CanIn2:

Parameter	Info	Lenze setting
C00401/3	LP_CanIn2: Inversion bln1_B0..15	0x0000
C00866/5	LP_CanIn2: wln1	-
C00866/6	LP_CanIn2: wln2	-
C00866/7	LP_CanIn2: wln3	-
C00866/8	LP_CanIn2: wln4	-
PDO mapping		
C00408/2	LP_CanIn2: Mapping selection	CanIn
C00409/5	LP_CanIn2: wln1 MapVal	0
C00409/6	LP_CanIn2: wln2 MapVal	0
C00409/7	LP_CanIn2: wln3 MapVal	0
C00409/8	LP_CanIn2: wln4 MapVal	0
Highlighted in grey = display parameter		

Parameter	Info	Lenze setting
C00407/3	LP_CanIn2: dwIn12 MapVal <ul style="list-style-type: none"> • From version 12.00.00 • The mapping for the double word is ORed with the mapping setting in C00409/5 and C00409/6. 	0
C00407/4	LP_CanIn2: dwIn34 MapVal <ul style="list-style-type: none"> • From version 12.00.00 • The mapping for the double word is ORed with the mapping setting in C00409/7 and C00409/8. 	0
Highlighted in grey = display parameter		

12.8.1.3 RPDO3 | "LP_CanIn3" port block

The LP_CanIn3 port block maps process data object RPDO3 in the FB Editor.



Short overview of the parameters for LP_CanIn3:

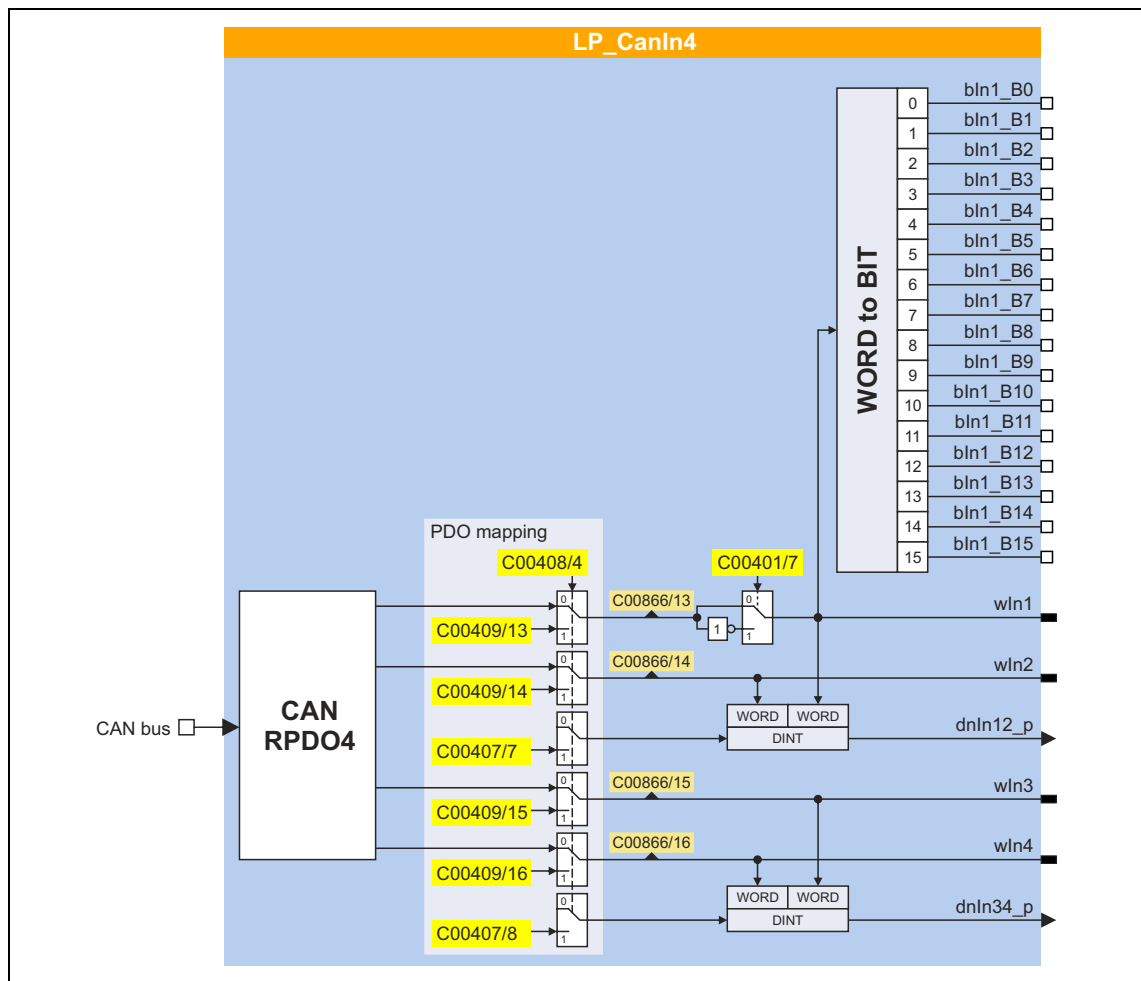
Parameter	Info	Lenze setting
C00401/5	LP_CanIn3: Inversion bln1_B0..15	0x0000
C00866/9	LP_CanIn3: wln1	-
C00866/10	LP_CanIn3: wln2	-
C00866/11	LP_CanIn3: wln3	-
C00866/12	LP_CanIn3: wln4	-
PDO mapping		
C00408/3	LP_CanIn3: Mapping selection	CanIn
C00409/9	LP_CanIn3: wln1 MapVal	0
C00409/10	LP_CanIn3: wln2 MapVal	0
C00409/11	LP_CanIn3: wln3 MapVal	0
C00409/12	LP_CanIn3: wln4 MapVal	0
Highlighted in grey = display parameter		

Parameter	Info	Lenze setting
C00407/5	LP_CanIn3: dwIn12 MapVal <ul style="list-style-type: none"> • From version 12.00.00 • The mapping for the double word is ORed with the mapping setting in C00409/9 and C00409/10. 	0
C00407/6	LP_CanIn3: dwIn34 MapVal <ul style="list-style-type: none"> • From version 12.00.00 • The mapping for the double word is ORed with the mapping setting in C00409/11 and C00409/12. 	0
Highlighted in grey = display parameter		

12.8.1.4 RPDO4 | "LP_CanIn4" port block

This function extension is available from version 15.00.00!

The **LP_CanIn4** port block maps process data object RPDO4 in the FB Editor.



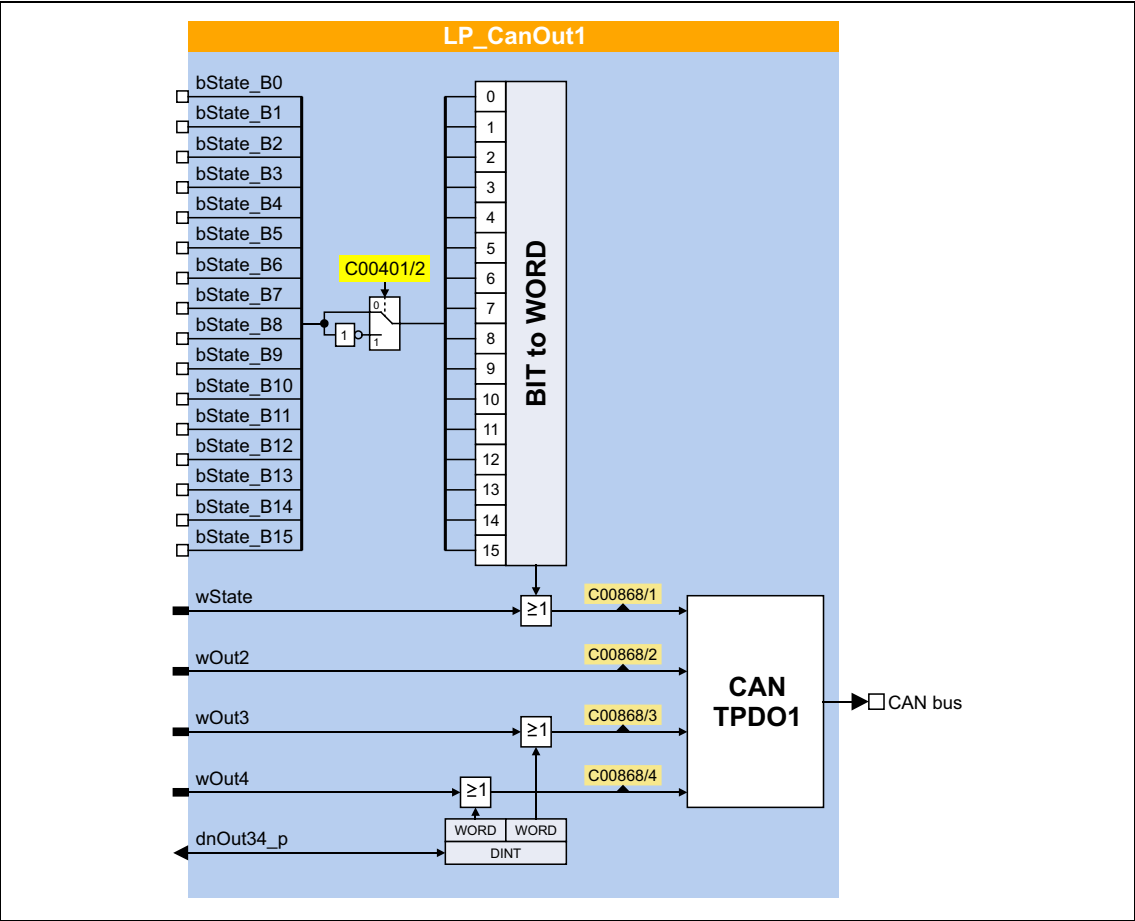
Short overview of the parameters for **LP_CanIn4**:

Parameter	Info	Lenze setting
C00401/7	LP_CanIn4: Inversion bln1_B0..15	0x0000
C00866/13	LP_CanIn4: wln1	-
C00866/14	LP_CanIn4: wln2	-
C00866/15	LP_CanIn4: wln3	-
C00866/16	LP_CanIn4: wln4	-
PDO mapping		
C00408/4	LP_CanIn4: Mapping selection	CanIn
C00409/13	LP_CanIn4: wln1 MapVal	0
C00409/14	LP_CanIn4: wln2 MapVal	0
C00409/15	LP_CanIn4: wln3 MapVal	0
C00409/16	LP_CanIn4: wln4 MapVal	0
Highlighted in grey = display parameter		

Parameter	Info	Lenze setting
C00407/7	LP_CanIn4: dwIn12 MapVal • The mapping for the double word is ORed with the mapping setting in C00409/13 and C00409/14 .	0
C00407/8	LP_CanIn4: dwIn34 MapVal • The mapping for the double word is ORed with the mapping setting in C00409/15 and C00409/16 .	0
Highlighted in grey = display parameter		

12.8.1.5 TPDO1 | "LP_CanOut1" port block

The LP_CanOut1 port block maps process data object TPDO1 in the FB Editor.

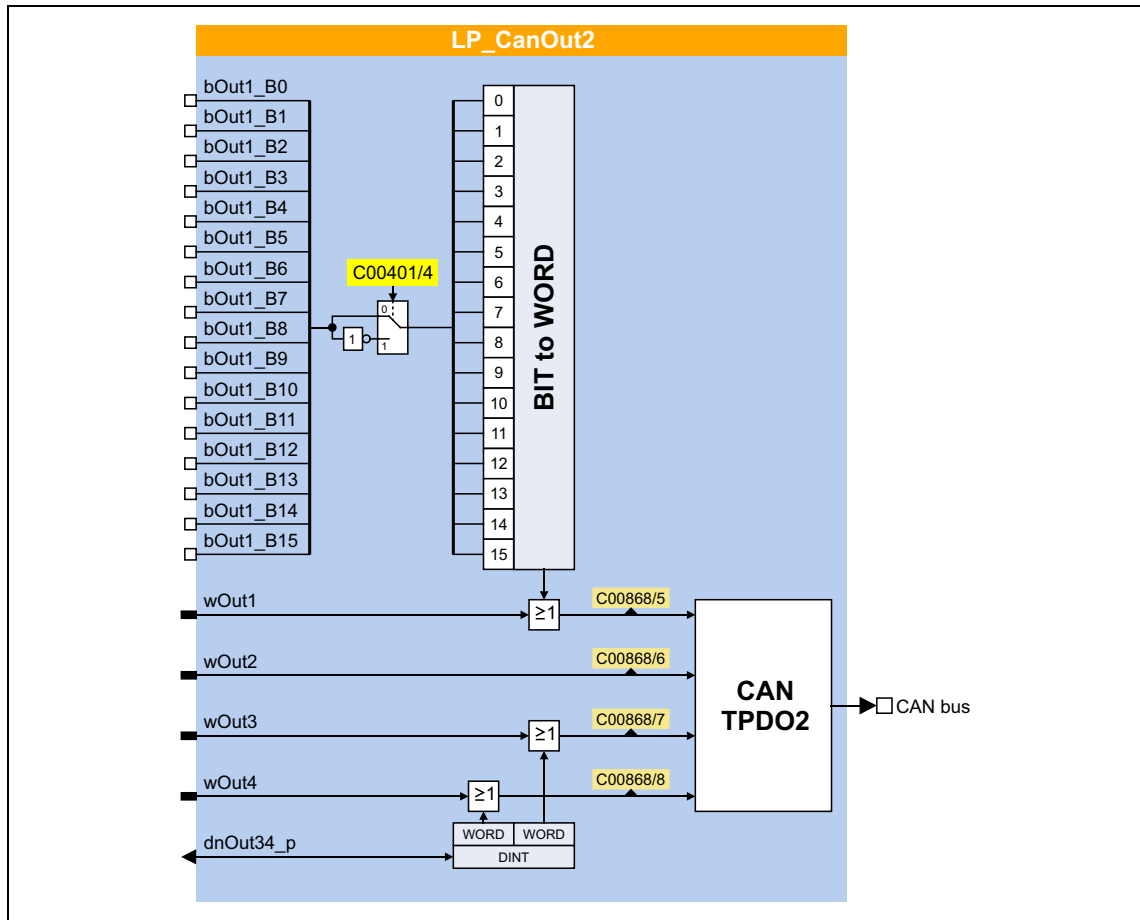


Short overview of the parameters for LP_CanOut1:

Parameter	Info	Lenze setting
C00401/2	LP_CanOut1: Inversion bState_B0..15	0x0000
C00868/1	LP_CanOut1:wState	-
C00868/2	LP_CanOut1:wOut2	-
C00868/3	LP_CanOut1:wOut3	-
C00868/4	LP_CanOut1: wOut4	-
Highlighted in grey = display parameter		

12.8.1.6 TPDO2 | "LP_CanOut2" port block

The LP_CanOut2 port block maps process data object TPDO2 in the FB Editor.

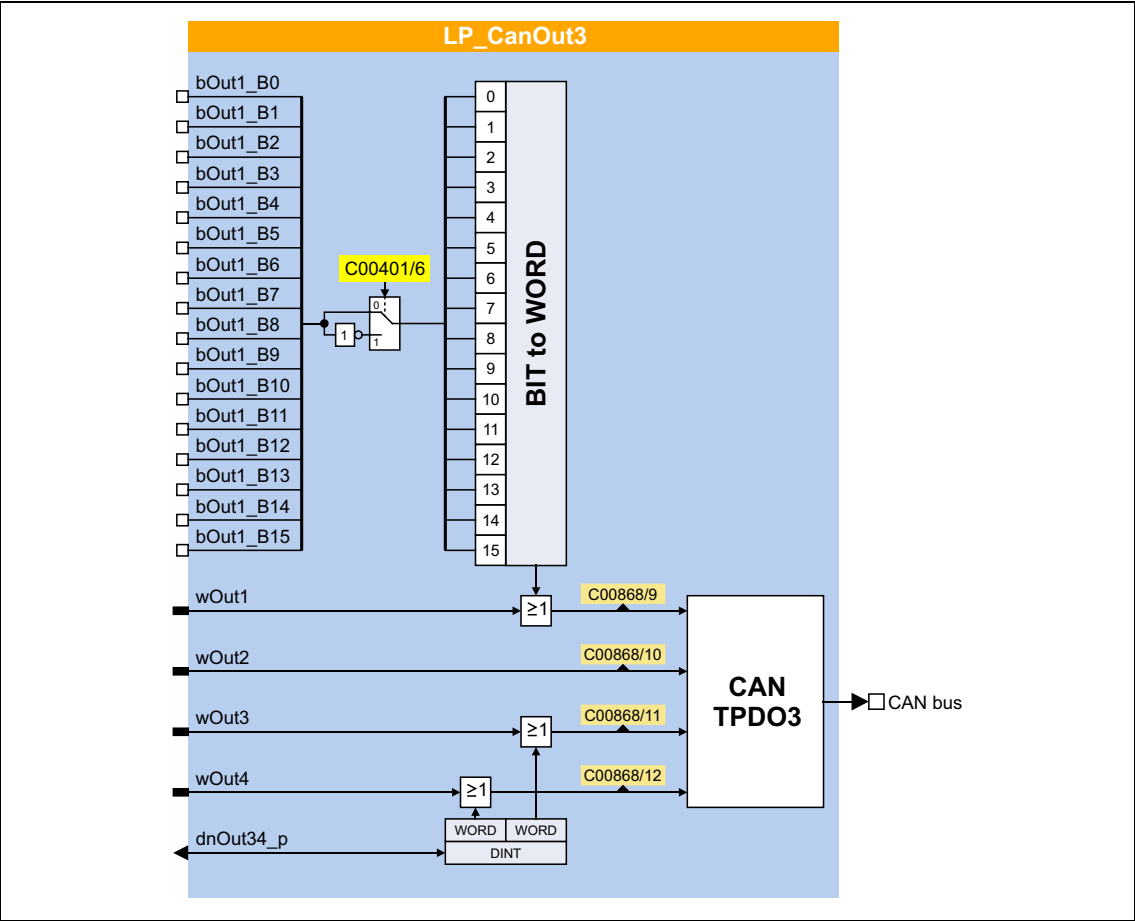


Short overview of the parameters for LP_CanOut2:

Parameter	Info	Lenze setting
C00401/4	LP_CanOut2: Inversion bOut1_B0..15	0x0000
C00868/5	LP_CanOut2: wOut1	-
C00868/6	LP_CanOut2: wOut2	-
C00868/7	LP_CanOut2: wOut3	-
C00868/8	LP_CanOut2: wOut4	-
Highlighted in grey = display parameter		

12.8.1.7 TPDO3 | "LP_CanOut3" port block

The LP_CanOut3 port block maps process data object TPDO3 in the FB Editor.



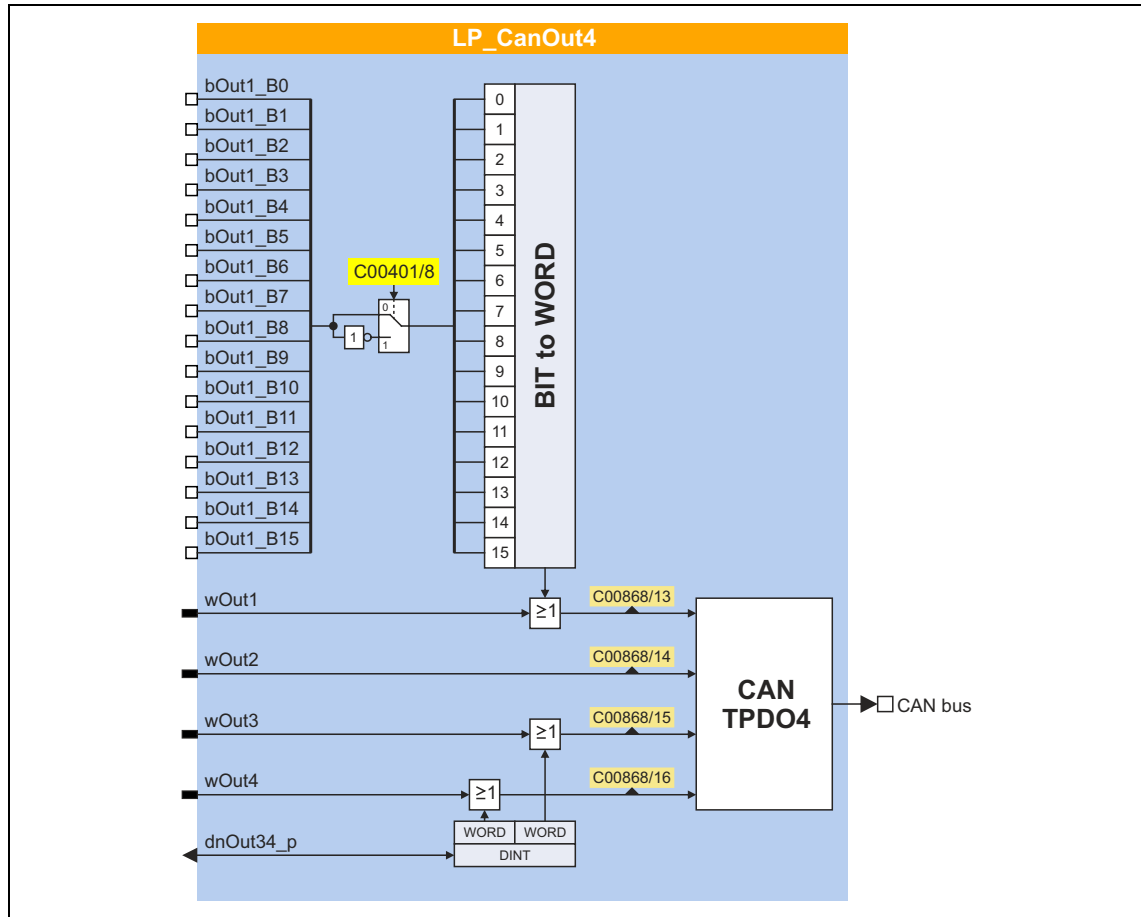
Short overview of the parameters for LP_CanOut3:

Parameter	Info	Lenze setting
C00401/6	LP_CanOut3: Inversion bOut1_B0..15	0x0000
C00868/9	LP_CanOut3: wOut1	-
C00868/10	LP_CanOut3: wOut2	-
C00868/11	LP_CanOut3: wOut3	-
C00868/12	LP_CanOut3: wOut4	-
Highlighted in grey = display parameter		

12.8.1.8 TPDO4 | "LP_CanOut4" port block

This function extension is available from version 15.00.00!

The **LP_CanOut4** port block maps process data object TPDO4 in the FB Editor.



Short overview of the parameters for **LP_CanOut4**:

Parameter	Info	Lenze setting
C00401/8	LP_CanOut4: Inversion bOut1_B0..15	0x0000
C00868/13	LP_CanOut4: wOut1	-
C00868/14	LP_CanOut4: wOut2	-
C00868/15	LP_CanOut4: wOut3	-
C00868/16	LP_CanOut4: wOut4	-
Highlighted in grey = display parameter		

12.8.2 Identifiers of the process data objects

For the process data objects PDO1 ... PDO4, three identifier assignment procedures are available in [C00353/1...4](#):

- Identifier (COB-ID) = node address (C00350) + CANBaseID (Lenze setting)
- Identifier (COB-ID) = node address (C00350) + LenzeBaseID
- Identifier (COB-ID) = C0354/x

Lenze setting: Basic identifiers according to the "Predefined Connection Set" of DS301 V4.02

In the Lenze setting, the identifiers for the process data objects PDO1 ... PDO4 consist of the node address set in [C00350](#) and a basic identifier (CANBaseID) which corresponds to the "Predefined Connection Set" of DS301 V4.02:

Object			Basis identifier (CANBaseID)	
PDO1	TPDO1	COB-ID = node address (C00350) +	384	0x180
	RPDO1		512	0x200
PDO2	TPDO2		640	0x280
	RPDO2		768	0x300
PDO3	TPDO3		896	0x380
	RPDO3		1024	0x400
PDO4	TPDO4		1152	0x480
	RPDO4		1280	0x500



Tip!

The active identifiers (COB-ID) are displayed in [C00355/x](#).

OPTIONAL: Use the basic identifier according to Lenze definition (LenzeBaseID)

If the basic identifiers shall be used instead according to the Lenze definition, go to [C00353/x](#) and select "0: COBID = C0350 + LenzeBaseID" for the corresponding PDO.

The basic Lenze identifiers which differ from the "Predefined Connection Set" are highlighted in colour in the following table:

Object			Basic identifier (LenzeBaseID)	
PDO1	TPDO1	COB-ID = node address (C00350) +	384	0x180
	RPDO1		512	0x200
PDO2	TPDO2		640	0x280
	RPDO2		641	0x281
PDO3	TPDO3		768	0x300
	RPDO3		769	0x301
PDO4	TPDO4		896	0x380
	RPDO4		897	0x381

OPTIONAL: Set identifier individually

When "2: COBID = C0354/x" in [C00353/x](#), the identifiers for the PDOs can be individually set via the Lenze codes and CANopen indexes listed in the table below. That way, identifiers independent of the node address can be set for specific PDOs.

- If identifiers are assigned individually, all PDOs must have basic identifier values in the range of 385 ... 1407.

Object			Lenze code	CANopen index	Default setting
PDO1	TPDO1	COB-ID =	C00354/1	I-1400/1	0x201
	RPDO1		C00354/2	I-1800/1	0x181
PDO2	TPDO2		C00354/3	I-1401/1	0x301
	RPDO2		C00354/4	I-1801/1	0x281
PDO3	TPDO3		C00354/5	I-1402/1	0x401
	RPDO3		C00354/6	I-1802/1	0x381
PDO4	TPDO4		C00354/7	I-1403/1	0x501
	RPDO4		C00354/8	I-1803/1	0x481

**Note!**

After a node address change ([C00350](#)) and a CAN reset node afterwards, the subcodes of [C00354](#) automatically resume the values which result from the respective basic identifier and the set node address.

12.8.3 Transmission type

Process data objects can be transmitted in an event-controlled or time-controlled manner. The below table shows that it is possible to combine the different methods by means of logic operations (AND, OR):

- Event-controlled
The PDO is sent when a special device-internal event has occurred, e.g. when the data contents of the TPDO have changed or when a transmission cycle time has elapsed
- Synchronous transmission
A TPDO (or RPDO) is transmitted (or received) after the device has received a sync telegram (COB-ID 0x80).
- Cyclic transmission
The cyclic transmission of PDOs takes place when the transmission cycle time has elapsed.
- Polled via RTR
A TPDO is transmitted when another device requests it by means of a data request telegram (RTR remote transmit request). For this purpose, the data requester (e.g. the master) sends the data request telegram with the COB-ID of the TPDO requested to be sent. The receiver recognises the RTR and transmits the corresponding PDO.

Transmission type	PDO transmission			Logic combination of different transmission types
	cyclic	synchronous	event-controlled	
0		•	•	AND
1 ... 240		•		-
254, 255	•		•	OR

Transmission type	Description
0	Synchronous and acyclic: The PDO is transmitted on an event-controlled basis with every sync (e.g. when a bit change occurs in the PDO).
1 ... 240	Synchronous and cyclic (sync-controlled with response): <ul style="list-style-type: none"> • Selection $n = 1$: The PDO is transmitted with <u>every</u> sync. • Selection $1 < n \leq 240$: The PDO is transmitted with <u>every n-th</u> sync.
241 ... 251	Reserved
252	Synchronous - RTR only
253	Asynchronous - RTR only
254, 255	Asynchronous - manufacturer-specific / device profile-specific: If this value is entered, the PDO transmission is event-controlled <u>or</u> cyclic. (Note: The values "254" and "255" have the same meaning). For a cyclic transmission, a cycle time must be entered for the respective PDO. In this case, cyclic transmission takes place in addition to event-controlled transmission.

The communication parameters such as the transmission mode and cycle time can be set freely for every PDO and independently of the settings of other PDOs:

Parameter	Info	Lenze setting	
		Value	Unit
CAN1_OUT			
C00322/1	Transmission mode	254	
C00324/2	Blocking time	0	ms
C00356/5	Cycle time	0	ms
C00358/1	Data length	8	Bytes
CAN2_OUT			
C00322/2	Transmission mode	254	
C00324/3	Blocking time	0	ms
C00356/2	Cycle time	0	ms
C00358/2	Data length	8	Bytes
CAN3_OUT			
C00322/3	Transmission mode	254	
C00324/4	Blocking time	0	ms
C00356/3	Cycle time	0	ms
C00358/3	Data length	8	Bytes
CAN4_OUT (from version 15.00.00)			
C00322/4	Transmission mode	254	
C00324/5	Blocking time	0	ms
C00356/6	Cycle time	0	ms
C00358/4	Data length	8	Bytes
CAN1_IN ... CAN4_IN			
C00323/1...4	Transmission mode CAN1_IN ... CAN4_IN • In the case of the RPDO serves as monitoring setting in the case of sync-controlled PDOs.	254	

Blocking time

In [C00324/x](#) a "blocking time" can be set which defines the shortest transmission cycle with the transmission type "asynchronous - manufacturer-specific/device profile-specific".

Example: Cycle time = 500 ms, blocking time = 100 ms, sporadic data change:

- With a sporadic data change < 500 ms, quickest transmission takes place every 100 ms due to the set blocking time (event-controlled transmission). The transmission cycle timer is reset to 0 if the transmission has been activated in an event-controlled way.
- In the case of a sporadic data change > 500 ms, due to the cycle time set, transmission takes place every 500 ms (cyclic transmission).



Tip!

The communication parameters can also be set via the following CANopen objects:

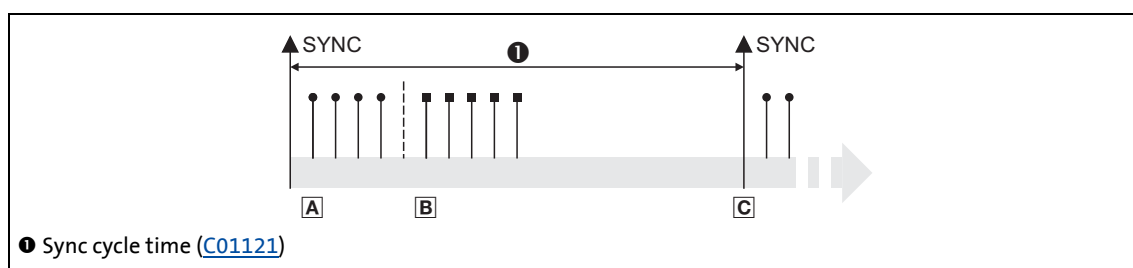
- [I-1400](#) ... [I-1403](#): Communication parameters for RPDO1 ... RPDO4
- [I-1800](#) ... [I-1803](#): Communication parameters for TPDO1 ... TPDO4

12.8.4 PDO synchronisation via sync telegram

During cyclic transmission, one or more PDOs are transmitted/received in fixed time intervals. An additional specific telegram, the so-called sync telegram, is used for synchronising cyclic process data.

- The sync telegram is the trigger point for the transmission of process data from the slaves to the master and for the acceptance of process data from the master in the slaves.
- For sync-controlled process data processing, the sync telegram must be generated accordingly.
- The response to a sync telegram is determined by the selected transmission type. ▶ [Transmission type](#) (□ 780)

Basic workflow



[12-6] Sync telegram

- After the sync telegram has been received, the slaves transmit the synchronous process data to the master (TPDOs). The master reads them as process input data.
- When the transmission process is completed, the slaves receive (RPDOs) the process output data (of the master).
 - All other telegrams (e.g. parameters or event-controlled process data) are accepted acyclically by the slaves after the transmission is completed.
 - Illustration [12-6] does not include acyclic data. However, they need to be considered when dimensioning the cycle time.
- The data are accepted in the slave with the next sync telegram if the Rx mode is set to 1 ... 240. If the Rx mode is 254 or 255, the data are accepted in the next device cycle, irrespective of the sync telegram.

Short overview: Parameters for the synchronisation via sync telegram

Parameter	Info	Lenze setting		Assignment	
		Value	Unit	Sync master	Sync slave
C00367	CAN SYNC Rx identifier	0x0080			●
C00368	CAN SYNC Tx identifier	0x0080		●	
C00369	CAN sync transmission cycle time	0	ms	●	

Related topics:

- ▶ [Synchronisation of the internal time base](#) (□ 857)

12.8.5 Monitoring of the RPDOs for data reception

For RPDO1 ... RPDO4 each, a monitoring time can be parameterised within which the RPDO must arrive. If the RPDO is not received within the monitoring time or not with the configured sync, the response parameterised for each RPDO takes place.

Short overview: Parameters for RPDO monitoring

Parameter	Info	Lenze setting	
		Value	Unit
C00357/1...4	CAN1...4_IN monitoring time	3000	ms
C00593/1...4	Resp. to CAN1...4_IN monitoring	No response	

12.8.6 Configuring exception handling of the CAN PDOs

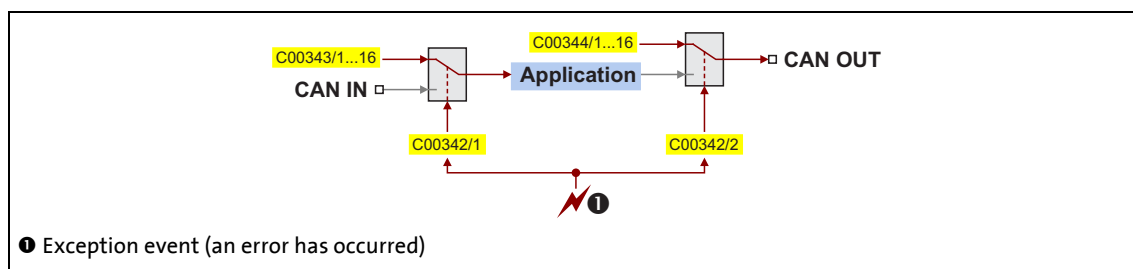
Exception handling for the CAN PDOs in the event of an error can be set via decoupling configuration and decoupling values.

- Bit coded selection is carried out in [C00342/1](#) for the process data words read by the bus, defining the events that will trigger decoupling.
- Bit coded selection is carried out in [C00342/2](#) for the process data words output by the application, defining the events that will trigger decoupling.

Bit	Event
Bit 0 <input type="checkbox"/>	BusOff_MsgErr
Bit 1 <input type="checkbox"/>	Warning
Bit 2 <input type="checkbox"/>	NodeStopped
Bit 3 <input type="checkbox"/>	HeartBeatEvent
Bit 4 <input type="checkbox"/>	CAN1_In_Überw.
Bit 5 <input type="checkbox"/>	CAN2_In_Überw.
Bit 6 <input type="checkbox"/>	CAN3_In_Überw.
Bit 7 <input type="checkbox"/>	CAN4_In_Überw.
Bit 8 <input type="checkbox"/>	Reserved
Bit 9 <input type="checkbox"/>	Reserved
Bit 10 <input type="checkbox"/>	Reserved
Bit 11 <input type="checkbox"/>	Reserved
Bit 12 <input type="checkbox"/>	Reserved
Bit 13 <input type="checkbox"/>	Reserved
Bit 14 <input type="checkbox"/>	Trouble
Bit 15 <input type="checkbox"/>	Fault

Finally, the following parameters define the value that the process data words are to have when they are decoupled:

Parameter	Info	Lenze setting	
		Value	Unit
C00343/1	LP_CanIn1:wCtrl DiscVal	0	
C00343/2...4	LP_CanIn1:wIn2...wIn4 DiscVal	0	
C00343/5...8	LP_CanIn2:wIn1...wIn4 DiscVal	0	
C00343/9...12	LP_CanIn3:wIn1...wIn4 DiscVal	0	
C00343/13...16	LP_CanIn4:wIn1...wIn4 DiscVal	0	
C00344/1	LP_CanOut1:wState DiscVal	0	
C00344/2...4	LP_CanOut1:wOut2...wOut4 DiscVal	0	
C00344/5...8	LP_CanOut2:wOut1...wOut4 DiscVal	0	
C00344/9...12	LP_CanOut3:wOut1...wOut4 DiscVal	0	
C00344/13...16	LP_CanOut4:wOut1...wOut4 DiscVal	0	



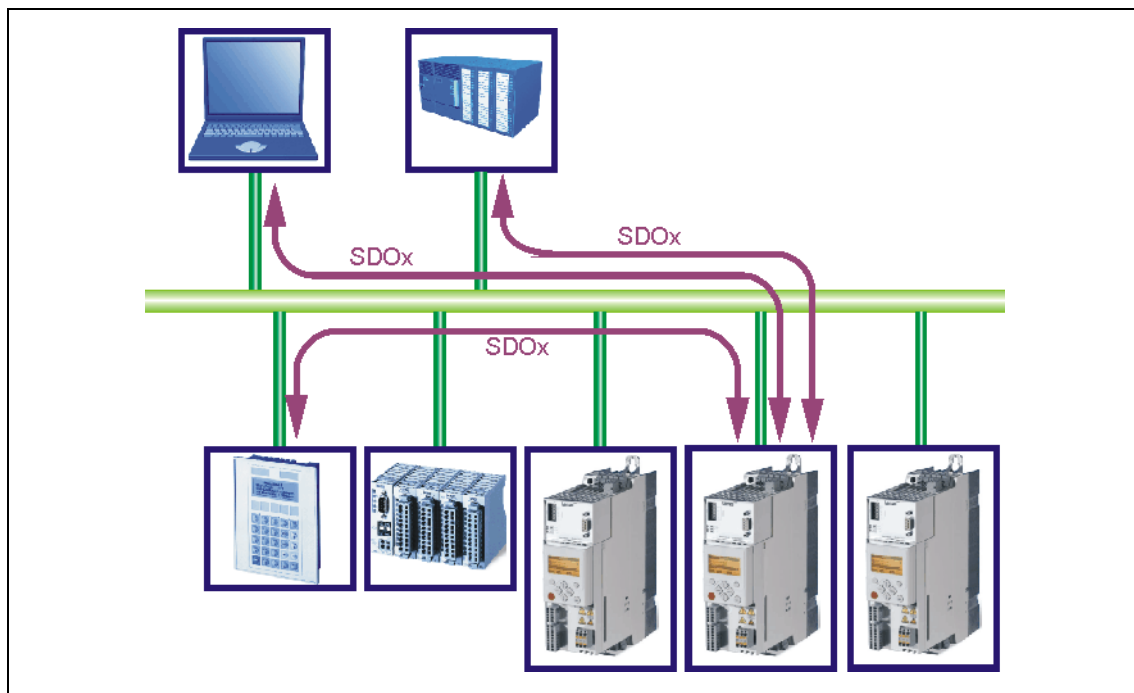
[12-7] General signal flow in the event of a configured exception

Related topics:

► [Configuring exception handling of the output terminals](#) (420)

12.9

Parameter data transfer



[12-8] Parameter data transfer via the available parameter data channels

Parameters are values stored in codes on Lenze controllers.

Two parameter data channels are available for parameter setting, enabling the simultaneous connection of different devices for configuration purposes.

Parameter data are transmitted via the system bus as SDOs (*Service Data Objects*) and acknowledged by the receiver. The SDO enables read and write access to all device parameters and to the CANopen object directory integrated in the device. Indices (e.g. 0x1000) ensure access to device parameters and functions included in the object directory. To transfer SDOs, the information contained in the user data must comply with the CAN SDO protocol.

**Note!**

In the Lenze setting, only the parameter data channel 1 is activated according to CANopen.

- In [C00366](#), set "2 SDO Lenze" to activate both parameter data channels.

12.9.1 Identifiers of the parameter data objects

In the Lenze setting, the basic identifiers of the SDOs are preset according to the "Predefined Connection Set".

The identifiers of the parameter data objects SDO1 and SDO2 result from the basic identifier and the node address set under code [C00350](#):

Identifier = basic identifier + node address

Object		Direction		Lenze-Base-ID		CANopen-Base-ID	
		from device	to device	dec	hex	dec	hex
SDO1 (Parameter data channel 1)	TSDO1	●		1408	580	1408	580
	RSDO1		●	1536	600	1536	600
SDO2 (Parameter data channel 2)	TSDO2	●		1472	5C0	1472	5C0
	RSDO2		●	1600	640	1600	640
Heartbeat		●		1792	700	1792	700
Boot-up		●		1792	700	1792	700

12.9.2 User data

Structure of the user data of the parameter data telegram

1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
Command	Index		Subindex	Data 1	Data 2	Data 3	Data 4
	LOW byte	HIGH byte		LOW word		HIGH word	
				LOW byte	HIGH byte	LOW byte	HIGH byte



Note!

For the user data, the Motorola format is used.

► [Parameter data telegram examples](#) (📖 792)

The following subchapters provide detailed information on user data.

12.9.2.1 Command

1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
Command	Index		Subindex	Data 1	Data 2	Data 3	Data 4
	LOW byte	HIGH byte		LOW word		HIGH word	
				LOW byte	HIGH byte	LOW byte	HIGH byte

The following commands can be transmitted or received for writing and reading the parameters:

Command	1st byte		Data length	Info
	hex	dec		
Write request	0x23	35	4 bytes	Writing of a parameter to the controller.
	0x2B	43	2 bytes	
	0x2F	47	1 byte	
	0x21	33	Block	
Write response	0x60	96	4 bytes	Controller acknowledges a write request.
Read request	0x40	64	4 bytes	Reading of a parameter from the controller.
Read response	0x43	67	4 bytes	Controller's response to a read request with the current parameter value.
	0x4B	75	2 bytes	
	0x4F	79	1 byte	
	0x41	65	Block	
Error response	0x80	128	4 bytes	Controller's response if the write/read request could not be executed correctly. ▶ Error messages (790)

More precisely, the command byte comprises the following information:

Command	1st byte							
	Command specifier (cs)			Toggle (t)	Length*		E	s
	Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
Write request	0	0	1	0	0/1	0/1	1	1
Write response	0	1	1	0	0	0	0	0
Read request	0	1	0	0	0	0	0	0
Read response	0	1	0	0	0/1	0/1	1	1
Error response	1	0	0	0	0	0	0	0

*Bit coding of the length: 00 = 4 bytes, 01 = 3 bytes, 10 = 2 bytes, 11 = 1 byte
e: expedited (shortened block service)
s: segmented (normal block service)

**Tip!**

More commands are defined in CANopen specification DS301, V4.02 (e.g. segmented transfer).

12.9.2.2 Addressing by means of index and subindex

1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
Command	Index		Subindex	Data 1	Data 2	Data 3	Data 4
	LOW byte	HIGH byte		LOW word		HIGH word	
				LOW byte	HIGH byte	LOW byte	HIGH byte

A parameter (a Lenze code) is addressed as per the following formula:

Index = 24575 - (Lenze code number)

Example

The [C00011](#) parameter (motor reference speed) is to be addressed.

Calculation:

- Index:
 - Decimal: $24575 - 11 = 24564$
 - Hexadecimal: $0x5FFF - 0xB = 0x5FF4$
- Subindex: 0x00 (subindex 0 since the parameter does not have any subcodes)

Entries:

1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
Command	Index		Subindex	Data 1	Data 2	Data 3	Data 4
	0xF4	0x5F	0x00				

12.9.2.3 Data 1 ... Data 4

1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
Command	Index		Subindex	Data 1	Data 2	Data 3	Data 4
	LOW byte	HIGH byte		LOW word		HIGH word	
				LOW byte	HIGH byte	LOW byte	HIGH byte

Maximally 4 bytes are available for parameter value entries. Depending on the data format, they are assigned as follows:

5th byte	6th byte	7th byte	8th byte
Parameter value (1 byte)	0x00	0x00	0x00
Parameter value (2 bytes)		0x00	0x00
LOW byte	HIGH byte		
Parameter value (4 bytes)			
LOW word		HIGH word	
LOW byte	HIGH byte	LOW byte	HIGH byte

**Note!**

The "Factor" column of the [Table of attributes](#) contains a so-called scaling factor for all Lenze parameters. The scaling factor is relevant to the transfer of parameter values which have one or more decimal positions in the parameter list.

If the scaling factor is > 1, the value must be multiplied by the indicated scaling factor prior to transmission to be able to transfer the value as an integer. At the SDO client end, the integer must be divided by the scaling factor to obtain the original value including decimal positions again.

Example

A value of "123.45" is to be transmitted for a code, unit: "%" (e.g. C00039/1: "Fixed setpoint-JOG1").

In controllers of the 8400 series, parameters with the "%" unit have two decimal positions and hence a scaling factor of "100".

Calculation:

- Value to be transmitted = scaling factor x value
- Data (1 ... 4) = 100 x 123.45 = 12345 (0x00 00 30 39)

Entries:

1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
Command	Index		Subindex	Data 1	Data 2	Data 3	Data 4
				0x39	0x30	0x00	0x00

12.9.2.4 Error messages

1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
Command	Index		Subindex	Error code			
0x80 (128)	LOW byte	HIGH byte		LOW word		HIGH word	
				LOW byte	HIGH byte	LOW byte	HIGH byte

In the event of an error, the addressed node generates a telegram with the "Error response" (0x80) command.

- The telegram includes the index and subindex of the code where the error occurred.
- The error code is entered in bytes 5 ... 8.
 - The error codes are standardised according to DS301, V4.02.
 - The representation of the error codes is provided in reverse read direction (see example below).

Example

Representation of error code "0x06 04 00 41" in bytes 5 ... 8:

1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
Command	Index		Subindex	Error code			
				0x41	0x00	0x04	0x06

Meaning of the error codes

The error codes are standardised acc. to DS301, V4.02.

Error code	Explanation
0x0503 0000	Toggle bit not changed
0x0504 0000	SDO protocol expired
0x0504 0001	Invalid or unknown client/server command specifier
0x0504 0002	Invalid block size (only block mode)
0x0504 0003	Invalid sequence number (only block mode)
0x0504 0004	CRC error (only block mode)
0x0504 0005	Not sufficient memory
0x0601 0000	Object access not supported
0x0601 0001	Attempt to read a write-only object
0x0601 0002	Attempt to write to a read-only object
0x0602 0000	Object not listed in object directory
0x0604 0041	Object not mapped to PDO
0x0604 0042	Number and length of objects to be transferred longer than PDO length.
0x0604 0043	General parameter incompatibility
0x0604 0047	General internal device incompatibility
0x0606 0000	Access denied because of hardware error
0x0607 0010	Unsuitable data type, unsuitable service parameter length
0x0607 0012	Unsuitable data type, service parameter length exceeded
0x0607 0013	Unsuitable data type, service parameter length not long enough
0x0609 0011	Subindex does not exist
0x0609 0030	Parameter value range exceeded
0x0609 0031	Parameter values too high
0x0609 0032	Parameter values too low
0x0609 0036	Maximum value falls below minimum value
0x0800 0000	General error
0x0800 0020	Data cannot be transferred/saved for application.
0x0800 0021	Data cannot be transferred/saved for application due to local control.
0x0800 0022	Data cannot be transferred/saved for application due to current device status.
0x0800 0023	Dynamic generation of object directory failed or no object directory available (e.g. object directory generated from file, generation not possible because of a file error).

12.9.3 Parameter data telegram examples

12.9.3.1 Read parameters

Task: The heatsink temperature of 43 °C (code [C00061](#), data format INTEGER16, scaling factor 1) of the controller with node address "5" is to be read.

Telegram to drive

Identifier	User data							
	1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
	Command	Index		Subindex	Data 1	Data 2	Data 3	Data 4
0x0605	0x40	0xC2	0x5F	0x00	0x00	0x00	0x00	0x00

Explanations on the telegram to the drive	
Identifier	= 1536 + node address = 1536 + 5 = 1541 = 0x0605 (1536 = SDO1 basic identifier to the controller)
Command	= 0x40 = "Read request" (read request of a parameter from the controller)
Index	= 24575 - code number = 24575 - 61 = 24514 = 0x5FC2
Subindex	= 0 (code C00061 does not have any subcodes)

Response telegram from drive (if data have been correctly transmitted)

Identifier	User data							
	1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
	Command	Index		Subindex	Data 1	Data 2	-	-
0x0585	0x4B	0xC2	0x5F	0x00	0x2B	0x00	-	-

Explanations on the telegram from the drive	
Identifier	= 1408 + node address = 1408 + 5 = 1413 = 0x0585 (1408 = SDO1 basic identifier from the controller)
Command	= 0x4B = "Read Response" (response to the read request with current value)
Index	as in telegram to the drive
Subindex	
Data 1 ... 2	= 0x002B = 43 [°C]

12.9.3.2 Write parameters

Task: The rated current of the connected motor is to be entered with $I_N = 10.20 \text{ A}$ (code [C00088](#)) into the controller with node address "2".

Data 1 ... 4	Calculation
Value for motor current, (data type U16; display factor 1/100)	$10.20 \times 100 = 1020 \text{ (0x03 FC)}$

Telegram to drive

Identifier	User data							
	1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
	Command	Index		Subindex	Data 1	Data 2	Data 3	Data 4
0x0602	0x23	0xA7	0x5F	0x00	0xFC	0x03	0x00	0x00

Explanations on the telegram to the drive	
Identifier	= $1536 + \text{node address} = 1536 + 2 = 1538 = 0x0602$ (1536 = SDO1 basic identifier to the controller)
Command	= $0x23$ = "Write request" (write request of a parameter to the controller)
Index	= $24575 - \text{code number} = 24575 - 88 = 24487 = 0x5FA7$
Subindex	= 0 (code C00088 does not have any subcodes)
Data 1 ... 4	= $10.20 \times 100 = 1020 = 0x000003FC$ (motor current value; data type U32; display factor 1/100)

Response telegram from drive (if data have been correctly transmitted)

Identifier	User data							
	1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
	Command	Index		Subindex	Data 1	Data 2	Data 3	Data 4
0x0582	0x60	0xA7	0x5F	0x00	0x00	0x00	0x00	0x00

Explanations on the telegram from the drive	
Identifier	= $1408 + \text{node address} = 1408 + 2 = 1410 = 0x0582$ (1408 = SDO1 basic identifier from the controller)
Command	= $0x60$ = "Write response" (Acknowledgement of the write access from the controller)
Index	as in telegram to the drive
Subindex	

12.9.3.3 Read block parameters

Task: The firmware version (code [C00099](#)) is to be read from the parameter set of the controller with node address "12". The firmware version has a length of 11 ASCII characters which are transmitted as a block parameter. Depending on the block, the data width from the 2nd to 8th byte is assigned within the user data.

Telegram 1 to the drive: Read request

Identifier	User data							
	1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
	Command	Index		Subindex	Data 1	Data 2	Data 3	Data 4
0x060C	0x40	0x9C	0x5F	0x00	0x00	0x00	0x00	0x00

Explanations on the telegram to the drive	
Identifier	= 1536 + node address = 1536 + 12 = 1548 = 0x060C (1536 = SDO1 basic identifier to the controller)
Command	= 0x40 = "Read request" (read request of a parameter from the controller)
Index	= 24575 - code number = 24575 - 99 = 24476 = 0x5F9C
Subindex	= 0 (code C00099 does not have any subcodes)

Response telegram 1 from the drive: Indication of the block length (11 characters)

Identifier	User data							
	1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
	Command	Index		Subindex	Data 1	Data 2	Data 3	Data 4
0x058C	0x41	0x9C	0x5F	0x00	0x0B	0x00	0x00	0x00

Explanations on the telegram from the drive	
Identifier	= 1408 + node address = 1408 + 12 = 1420 = 0x058C (1408 = SDO1 basic identifier from the controller)
Command	= 0x41 = "Read response" (response is block telegram)
Index	as in telegram to the drive
Subindex	
Data 1 ... 4	= 0x0000000B = data length of 11 characters in the ASCII format

Telegram 2 to the drive: Request of the 1st data block

Identifier	User data							
	1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
	Command	Data 1	Data 2	Data 3	Data 4	Data 5	Data 6	Data 7
0x060C	0x60	0x00	0x00	0x00	0x00	0x00	0x00	0x00

Explanations on the telegram to the drive	
Command	= 0x60 = "Read segment request" (request: read data block) • Bit 4 = 0 (toggle bit) Influence of the toggle bit on the request command The single blocks are toggled one after another, i.e. first the request is made with the "0x60" command (= 0b0110*0000), then with the "0x70" command (= 0b0111*0000), and then again with the "0x60" command, etc. * Toggle bit

Response telegram 2 from the drive: Transmission of the 1st data block

Identifier	User data							
	1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
	Command	Data 1	Data 2	Data 3	Data 4	Data 5	Data 6	Data 7
0x058C	0x00	0x30	0x31	0x2E	0x30	0x30	0x2E	0x30
		0 _{asc}	1 _{asc}	·asc	0 _{asc}	0 _{asc}	·asc	0 _{asc}

Explanations on the telegram to the drive	
Command	= 0x00 = 0b00000000 • Bit 4 = 0 (toggle bit) Influence of the toggle bit on the transmission command • The 1st response of the controller in the command byte is "0b0000*0000" if bytes 2 ... 8 are completely filled with data and other telegrams are following. • The 2nd response of the controller in the command byte is "0b0001*0000" if bytes 2 ... 8 are completely filled with data and other telegrams are following, etc. * Toggle bit
Data 1 ... 7	= "01.00.0" (ASCII representation)

Telegram 3 to the drive: Request of the 2nd data block

Identifier	User data							
	1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
	Command	Data 1	Data 2	Data 3	Data 4	Data 5	Data 6	Data 7
0x060C	0x70	0x00	0x00	0x00	0x00	0x00	0x00	0x00

Explanations on telegram 3 to the drive

Command	= 0x70 = "Read segment request" (request: read data block) • Bit 4 = 1 (toggle bit)
---------	--

Response telegram 3 from the drive: Transmission of the 2nd data block including end identifier

Identifier	User data							
	1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
	Command	Data 1	Data 2	Data 3	Data 4	Data 5	Data 6	Data 7
0x058C	0x17	0x30	0x2E	0x30	0x30	0x00	0x00	0x00
		0 _{asc}	·asc	0 _{asc}	0 _{asc}	-	-	-

Explanations on telegram 3 from the drive

Command	= 0x17 = 0b00010111: • Bit 0 = 1 (end of transmission) • Bit 1 ... bit 3 = 0b011 (3 bytes do not contain any data) • Bit 4 = 1 (toggle bit)
	Influence of the final bit and the residual data length on the transmission command • The end of transmission is signalled via the set final bit 0. • Bits 1 ... 3 reveal the number of bytes that do not contain any data anymore. * Toggle bit
Data 1 ... 7	= "0.00" (ASCII representation) The result of the data block transmission is: "01.00.00.00"

12.10 Monitoring

12.10.1 Integrated error detection

If a node detects an error, it rejects the telegram bits received so far and transmits an error flag. The error flag consists of 6 consecutive bits with the same logic value.

The following errors are detected:

Fault	Description
Bit error	The sending node follows the transmission on the bus and interrupts the transmission if it receives a different logic value than the value transmitted. With the next bit, the sending node starts the transmission of an error flag. In the arbitration phase, the transmitter only detects a bit error if a dominantly sent bit is received as recessive bit. In the ACK slot as well, the dominant overwriting of a recessive bit is not indicated as a bit error.
Stuff-bit error	If more than 5 consecutive bits have the same logic value before the ACK delimiter in the telegram, the previously transmitted telegram will be rejected and an error flag will be sent with the next bit.
CRC error	If the received CRC checksum does not correspond to the checksum calculated in the bus controller, the bus controller will send an error flag after the ACK delimiter and the previously transmitted telegram will be annulled.
Acknowledgement error	If the sent ACK slot recessively sent by the transmitting node is not dominantly overwritten by a receiver, the transmitting node will cancel the transmission. The transmitting node will annul the transmitted telegram and will send an error flags with the next bit.
Format error	If a dominant bit is detected in the CRC delimiter, in the ACK delimiter or in the first 6 bits of the EOF field, the received telegram will be rejected and an error flag will be sent with the next bit.



Tip!

The errors mentioned before indicate that a physical error has occurred in the bus system.

Possible causes are:

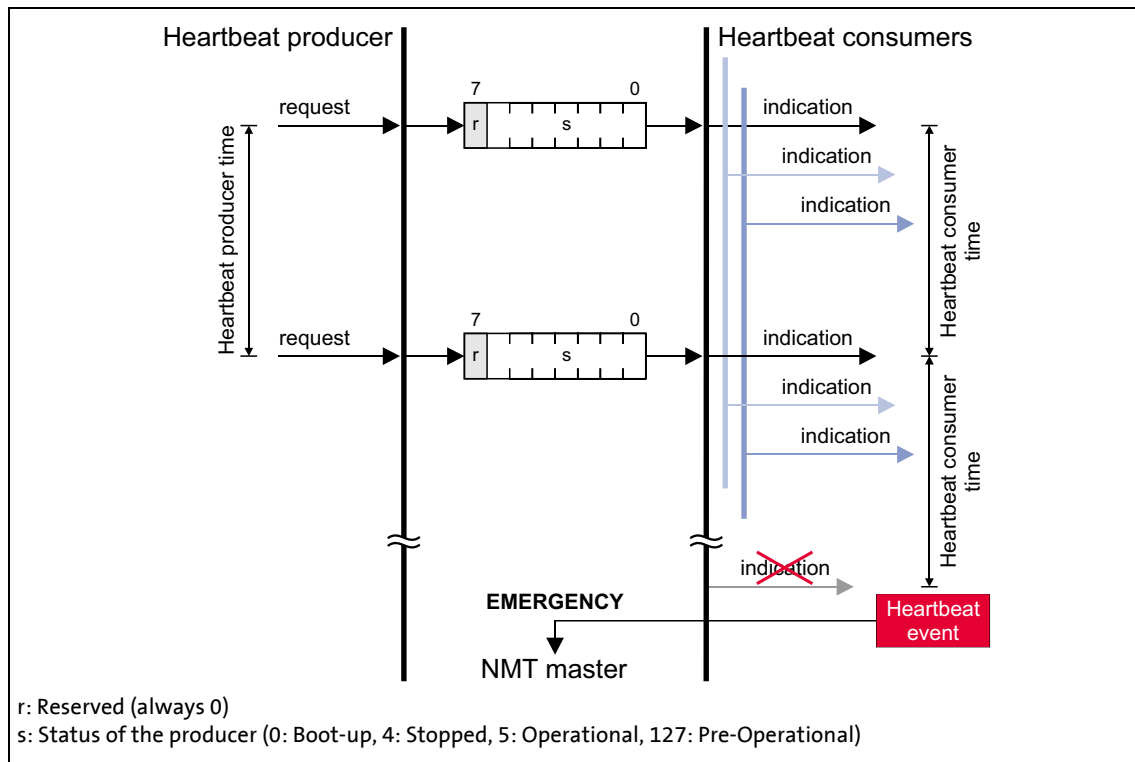
- Several nodes with identical node address
- Wrong baud rate of one or several nodes
- Too high cable length
- Too many or no terminating resistors
- Too high bus load/too many data telegrams
(e.g. since a node permanently transmits event-controlled due to data changes of an analog signal/actual value.)
- EMC interferences on the system bus
(e.g. since the CAN bus cable next to the motor cable is unshielded.)

[C00364](#) displays whether such an error is active.

12.10.2 Heartbeat protocol

The heartbeat protocol can be used for node monitoring purposes within a CAN network.

Basic workflow



[12-9] Heartbeat protocol

1. A heartbeat producer cyclically transmits a so-called heartbeat telegram to one or more consumers.
2. The consumer(s) monitor the heartbeat telegram for arrival on a regular basis.

12.10.2.1 Telegram structure

- The heartbeat telegram of the producer has the following identifier:
Identifier (COB-ID) = 1792 + producer's node address
- The user data (1 byte) contain the status (s) of the producer:

Heartbeat producer status		Data							
Communication status	Decimal value (s)	(r)	Producer status (s)						
		Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
Boot-up	0	0	0	0	0	0	0	0	0
Stopped	4	0	0	0	0	0	1	0	0
Operational	5	0	0	0	0	0	1	0	1
Pre-Operational	127	0	1	1	1	1	1	1	1

12.10.2.2 Parameter setting

Short overview of the parameters for the "Heartbeat" monitoring function:

Parameter	Info	Lenze setting		Assignment	
		Value	Unit	Consumer	Producer
C00347/1...n	CAN status of the heartbeat producer 1 ... n	-		●	
C00381	Heartbeat producer time	0	ms		●
C00385/1...n	CAN node address of the heartbeat producer 1 ... n	0		●	
C00386/1...n	Heartbeat consumer time for the heartbeat producer 1 ... n	0	ms	●	
C00592/5	Resp. to heartbeat event	No response		●	
Highlighted in grey = display parameter					

Heartbeat producer time

Time interval for the transmission of the heartbeat telegram to the consumer(s).

- Parameterisable in [C00381](#) or via object [I-1017](#). The parameterised time is rounded down to an integer multiple of 5 ms.
- The heartbeat telegram is sent automatically as soon as a time > 0 ms is set.

Heartbeat consumer time

Monitoring time for the nodes (producers) to be monitored.

- Parameterisable in [C00386/1...n](#) or via object [I-1016](#).
- The parameterised time is rounded down to an integer multiple of 5 ms and must have a greater value than the heartbeat producer time of the node to be monitored.
- The maximum number of the nodes to be monitored depends on the device version:
 - "Baseline C": 1 Heartbeat Producer can be monitored.
 - "StateLine C": Up to 7 Heartbeat Producers can be monitored.
 - "HighLine C": Up to 15 Heartbeat Producers can be monitored.
 - "TopLine C": Up to 15 Heartbeat Producers can be monitored.
- The node address(es) of the nodes to be monitored is/are set in [C00385/1...n](#) or via object [I-1016](#), too.

Heartbeat event

The "Heartbeat event" is activated in the consumer if it does not receive any heartbeat telegram from the producer within the heartbeat consumer time:

- The consumer changes from the "Operational" communication status to the "Pre-Operational" communication status.
- The NMT master receives an emergency telegram containing emergency error code 0x8130.
- The response parameterised in [C00592/5](#) is activated (Lenze setting: "No response").

**Note!**

The heartbeat monitoring will not start until the first heartbeat telegram of a monitored producer has been received successfully and the "Pre-Operational" NMT status has been assumed.

The boot-up telegram counts as the first heartbeat telegram.

12.10.2.3 Commissioning example**Task**

An 8400 controller (node 2) which is configured as heartbeat consumer is to monitor another 8400 controller (heartbeat producer, node 1).

- The heartbeat producer is to transmit a heartbeat telegram to the heartbeat consumer every 10 ms.
- The heartbeat consumer monitors the heartbeat telegram for arrival. A response is to be activated in the event of an error.

Parameterising the heartbeat producer (node 1)

1. Set the heartbeat producer time ([C00381](#)) to 10 ms.

Parameterising the heartbeat consumer (node 2)

1. Set the CAN node address of the producer in [C00385/1](#).
2. Set the heartbeat consumer time in [C00386/1](#).
 - Note: The heartbeat consumer time must be greater than the heartbeat producer time of the node to be monitored set in [C00381](#).
3. Set the desired response in [C00592/5](#) which is to be activated should a heartbeat event in the consumer occur.

**Tip!**

[C00347/1...n](#) displays the heartbeat status of the monitored nodes.

Heartbeat telegram

- The heartbeat telegram of the producer has the following identifier:
Identifier (COB-ID) = 1792 + producer's node address = 1792 + 1 = 1793 = 0x701

12.10.3 Emergency telegram

If the error status changes because an internal device error occurs or has been eliminated, the NMT master receives an emergency telegram once with the following structure:

1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
Emergency error codes		Error register	Manufacturer-specific error message				
LOW byte	HIGH byte	I-1001	0x00 (Reserved)	LOW word		HIGH word	
				LOW byte	HIGH byte	LOW byte	HIGH byte
See table below			<ul style="list-style-type: none"> For emergency error code 0xF000: Lenze error number (value displayed in C00168) All other emergency error codes have a value of "0" here. 				

Emergency error codes	Error register	Cause
0x0000	0xXX	One of several errors eliminated
	0x00	One error has been eliminated (error-free status afterwards)
0x3100	0x01	Supply voltage of standard device faulty or failed
0x8100	0x11	Communication error (warning)
0x8130	0x11	Life guarding error or heartbeat error
0x8150	0x11	Collision of identifiers (COB-IDs): An identifier parameterised for reception is also used for transmission.
0x8210	0x11	PDO length shorter than expected
0x8220	0x11	PDO length greater than expected
0x8700	0x11	Monitoring of the sync telegram
0xF000	0x01	Generic error <ul style="list-style-type: none"> An error with a "Fault", "Trouble", "TroubleQSP", "Warning", or "SystemFault" error response occurred in the standard device. Error message is the Lenze error number (C00168).

The [Short overview \(A-Z\)](#) of error messages of the operating system includes a list of more emergency error codes. ([702](#))

Example

1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
Emergency error codes		Error register	Manufacturer-specific error message				
0x00	0xF0	0x01	0x00 (Reserved)	Lenze error number			
Generic error				▶ Error messages of the operating system Corresponding error-free message: Value "0x00000000"			



Tip!

A detailed description can be found in CAN specification DS301, V4.02.

12.11 Implemented CANopen objects

Lenze devices can both be parameterised with Lenze codes and manufacturer-independent "CANopen objects". A completely CANopen-compliant communication can only be achieved by using CANopen objects for parameter setting. The CANopen objects described in this chapter are defined in the CAN specification DS301 V4.02.

Many CANopen objects can be mapped on Lenze codes. In the following table, the corresponding Lenze codes are listed in the column "Relationship to Lenze codes".



Note!

Some of the terms used here derive from the CANopen protocol.

Overview of CANopen indices and their relationship to Lenze codes

CANopen object			Relationship to Lenze code
Index	Subindex	Name	
I-1000	0	Device type	-
I-1001	0	Error register	-
I-1003	Predefined error field		
	0	Number of errors	-
	1 ... 10	Standard error field	-
I-1005	0	COB-ID SYNC message	C00367
			C00368
I-1006	0	Communication cycle period	C00369
I-1014	0	COB-ID EMCY	-
I-1016	Consumer heartbeat time		
	0	Highest subindex supported	-
	1 ... n	Consumer heartbeat time <ul style="list-style-type: none"> • "BaseLine C" version: n = 1 • "StateLine C" version: n = 7 • "HighLine C" version: n = 15 • "TopLine C" version: n = 15 	C00385/1...n C00386/1...n
I-1017	0	Producer heartbeat time	C00381
I-1018	Identity object		
	0	Highest subindex supported	-
	1	Vendor ID	-
	2	Product code	-
	3	Revision number	-
	4	Serial number	-
I-1200	SDO1 server parameter		
	0	Highest subindex supported	-
	1	COB-ID client → server (rx)	-
	2	COB-ID server → client (tx)	-
I-1201	SDO2 server parameter		
	0	Highest subindex supported	-
	1	COB-ID client → server (rx)	-
	2	COB-ID server → client (tx)	-

CANopen object			Relationship to Lenze code
Index	Subindex	Name	
I-1400	RPDO1 communication parameter		
	0	Highest subindex supported	-
	1	COB-ID used by RPDO	C00355/1
	2	Transmission type	C00323/1
I-1401	RPDO2 communication parameter		
	0	Highest subindex supported	-
	1	COB-ID used by RPDO	C00355/3
	2	Transmission type	C00323/2
I-1402	RPDO3 communication parameter		
	0	Highest subindex supported	-
	1	COB-ID used by RPDO	C00355/5
	2	Transmission type	C00323/3
I-1403	RPDO4 communication parameter (from version 15.00.00)		
	0	Highest subindex supported	-
	1	COB-ID used by RPDO	C00355/7
	2	Transmission type	C00323/4
I-1600	RPDO1 mapping parameter		
	0	Number of mapped application objects in PDO	-
	1 ... 4	Application object 1 ... 4	C00409/1...4 C00866/1...4
I-1601	RPDO2 mapping parameter		
	0	Number of mapped application objects in PDO	-
	1 ... 4	Application object 1 ... 4	C00409/5...8 C00866/5...8
I-1602	RPDO3 mapping parameter		
	0	Number of mapped application objects in PDO	-
	1 ... 4	Application object 1 ... 4	C00409/9...12 C00866/9...12
I-1603	RPDO4 mapping parameter (from version 15.00.00)		
	0	Number of mapped application objects in PDO	-
	1 ... 4	Application object 1 ... 4	C00409/13...16 C00866/13...16
I-1800	TPDO1 communication parameter		
	0	Highest subindex supported	-
	1	COB-ID used by TPDO	C00355/2
	2	Transmission type	C00322/1
	3	Inhibit time	C00324/2
	5	Event timer	C00356/5 C00369

CANopen object			Relationship to Lenze code
Index	Subindex	Name	
I-1801	TPDO2 communication parameter		
	0	Highest subindex supported	-
	1	COB-ID used by TPDO	C00355/4
	2	Transmission type	C00322/2
	3	Inhibit time	C00324/3
	5	Event timer	C00356/2 C00369
I-1802	TPDO3 communication parameter		
	0	Highest subindex supported	-
	1	COB-ID used by TPDO	C00355/6
	2	Transmission type	C00322/3
	3	Inhibit time	C00324/4
	5	Event timer	C00356/3 C00369
I-1803	TPDO4 communication parameter (from version 15.00.00)		
	0	Highest subindex supported	-
	1	COB-ID used by TPDO	C00355/8
	2	Transmission type	C00322/4
	3	Inhibit time	C00324/5
	5	Event timer	C00356/4 C00369
I-1A00	TPDO1 mapping parameter		
	0	Number of mapped application objects in PDO	-
	1 ... 4	Application object 1 ... 4	C00868/1...4
I-1A01	TPDO2 mapping parameter		
	0	Number of mapped application objects in PDO	-
	1 ... 4	Application object 1 ... 4	C00868/5...8
I-1A02	TPDO3 mapping parameter		
	0	Number of mapped application objects in PDO	-
	1 ... 4	Application object 1 ... 4	C00868/9...12
I-1A03	TPDO4 mapping parameter (from version 15.00.00)		
	0	Number of mapped application objects in PDO	-
	1 ... 4	Application object 1 ... 4	C00868/13...16

I-1000

Index I-1000	Name: Device type					
Subindex	Default setting	Display range (min. value unit max. value)			Access	Data type
0: Device type	0	0		4294967295	ro	U32

The CANopen index I-1000 specifies the profile for this device. Furthermore, additional information defined in the device profile itself can be stored here.

8th byte	7th byte	6th byte	5th byte
Data 4	Data 3	Data 2	Data 1
HIGH word		LOW word	
HIGH byte	LOW byte	HIGH byte	LOW byte
Additional information		Device profile number	

[12-1] Data telegram assignment

In case of 8400 series controllers, the four bytes contain the following values:

- 5th and 6th byte: The data content is 0x0000, i.e. no profile definition.
- 7th byte: The data content specifies the device type: Here the value is 0x00 for controllers.
- 8th byte: The data content is 0x00.

The data content for the 8400 controller thus is: 00 00 00 00

I-1001

Index: I-1001	Name: Error register					
Subindex	Default setting	Display range (min. value unit max. value)			Access	Data type
0: Error register	-	0		255	ro	U8

Error register

The error status in the data byte (U8) is bit coded. The following error states are coded in the data byte (U8):

Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0	Error status
0	0	0	0	0	0	0	0	No error
0	0	0	0	0	0	0	1	Device error message
0	0	0	1	0	0	0	1	Communication error

I-1003

Index: I-1003	Name: Predefined error field					
Subindex	Default setting	Setting range (min. value unit max. value)			Access	Data type
0: Number of errors	0	0		255	rw	U8
1 ... 10: Standard error field	-	0		4294967295	ro	U32

Error history

This object indicates that an error has occurred in the module and in the standard device.

Subindex	Meaning
0	Number of saved error messages
1 ... 10	Display of the error list The error messages (U32) consist of a 16-bit error code and a manufacturer-specific information field comprising 16 bits.

**Note!**

The values in the "standard error field" under subindex 1 ... 10 will be deleted if the subindex "number of recorded errors" is overwritten with the value "0".

Emergency error codes	Cause	Entry in the error register (I-1001)
0x0000	One of several errors eliminated	0xXX
	Elimination of one single error (afterwards no more errors)	0x00
0x1000	Standard device is in error status (error response "fault", "message", "warning", "error", "quick stop by trouble", or "system error")	0x01
0x3100	Supply voltage of standard device faulty or failed	0x01
0x8100	Communication error (warning)	0x11
0x8130	Life guard error or heartbeat error	0x11
0x8150	Collision of COB-IDs: An ID parameterised for reception is also used for transmission.	0x11
0x8210	PDO length shorter than expected	0x11
0x8220	PDO length greater than expected	0x11
0x8700	Monitoring of the sync telegram	0x11

I-1005

Index: I-1005	Name: COB-ID SYNC message					
Subindex	Default setting	Setting range (min. value unit max. value)			Access	Data type
0: COB-ID SYNC message	0x0000 0080 or 0x8000 0080	0		4294967295	rw	U32

This object can be used to activate the generation of sync telegrams and to write the identifier value.

- This object relates to codes [C00367](#) and [C00368](#).

Creating sync telegrams

Sync telegrams are created by setting bit 30 (see below) to "1". The time between the sync telegrams can be set using the object [I-1006](#).

Writing identifiers

To receive PDOs, the value 0x80 must be entered in the 11-bit identifier in the Lenze setting (and according to CANopen specification) . This means that all modules are by default set to the same sync telegram.

- If sync telegrams are only to be received by certain communication modules, their identifiers can be entered with values up to and including 0x07FF.
- The identifier can only be changed if the communication module does not send any sync telegrams (bit 30 = "0").
- How to change the identifier:
 - Deactivate identifier (set bit 30 to "0").
 - Change identifier.
 - Activate identifier (set bit 30 to "1").

8th byte		7th byte		6th byte		5th byte	
Data 4		Data 3		Data 2		Data 1	
Bit 31	Bit 30	Bit 29 ... bit 11				Bit 10 ... bit 0	
X	0/1	Extended identifier*				11-bit identifier	

* The extended identifier is not supported. Bit 11 ... bit 29 must be set to "0".

[12-2] Data telegram assignment

I-1006

Index: I-1006	Name: Communication cycle period					
Subindex	Default setting	Setting range (min. value unit max. value)			Access	Data type
0: Communication cycle period	0 µs	0	µs	65535000	rw	U32

Setting the sync telegram cycle time.

- The cycle time can be selected as "1000" or as an integer multiple of it.
- If "0 µs" is set (Lenze setting), no sync telegrams are created.
- This object relates to code [C00369](#).

I-1014

Index: I-1014	Name: COB-ID EMCY					
Subindex	Default setting	Setting range (min. value unit max. value)			Access	Data type
0: COB-ID EMCY	0x80 + node ID	0		4294967295	rw	U32

When communication errors occur and are acknowledged or when internal errors occur in the communication module or controller (e.g. "fault"), the system bus sends an error message. The telegram is sent once for every error. This function can be activated or deactivated with bit 31.

8th byte		7th byte		6th byte		5th byte	
Data 4		Data 3		Data 2		Data 1	
Bit 31	Bit 30	Bit 29 ... bit 11				Bit 10 ... bit 0	
0/1	0	Extended identifier*				11-bit identifier	

* The extended identifier is not supported. Bit 11 ... bit 29 must be set to "0".

[12-3] Data telegram assignment

Bit	Setting	
Bit 31	0	Emergency object is valid.
	1	Emergency object is invalid.

**Note!**

The identifier can only be changed in the "emergency object invalid" status (bit 31 = 1).

I-1016

Index: I-1016	Name: Consumer heartbeat time					
Subindex	Default setting	Setting range (min. value unit max. value)			Access	Data type
0: Highest subindex supported	BaseLine C: 1 StateLine C: 7 HighLine C: 15 TopLine C: 15	- (read access only)			ro	U16
1 ... n: Consumer heartbeat time	0	0		65535	rw	U16

Monitoring time for the nodes to be monitored via heartbeat. ► [Heartbeat protocol](#) (📖 798)

- The parameterised time is rounded down to an integer multiple of 5 ms and must have a greater value than the heartbeat producer time of the node to be monitored.

Subindex	Meaning	Lenze code
0	Number of nodes to be monitored	
1 ... n	Node ID and heartbeat time of the node to be monitored	Node ID: C00385/x Heartbeat time: C00386/x

8th byte	7th byte	6th byte	5th byte
Data 4	Data 3	Data 2	Data 1
Bit 31 ... bit 24	Bit 23 ... Bit 16	Bit 15 ... Bit 0	
0 (Reserved)	Node ID	Heartbeat time in [ms]	

[12-4] Data telegram assignment

I-1017

Index: I-1017	Name: Producer heartbeat time				
Subindex	Default setting	Setting range (min. value unit max. value)			Access Data type
0: Producer heartbeat time	0	0	ms	65535	rw U16

Time interval for sending the heartbeat telegram to the consumer(s). ▶ [Heartbeat protocol](#) (📖 798)

- The parameterised time is rounded down to an integer multiple of 5 ms.
- The heartbeat telegram is automatically sent as soon as a time > 0 ms is entered. In this case, the "node guarding" monitoring function is deactivated.
- This object relates to code [C00381](#).

I-1018

Index: I-1018	Name: Identity object				
Subindex	Default setting	Display range (min. value unit max. value)			Access Data type
0: Highest subindex supported	see below	0		4294967295	ro U32
1: Vendor ID					
2: Product code					
3: Revision number					
4: Serial number					

Subindex	Meaning	
1	Manufacturer's identification number <ul style="list-style-type: none"> • The identification number allocated to Lenze by the organisation "CAN in Automation e. V." is "0x0000003B". 	
2	Product code	
	0x84001	8400 BaseLine C
	0x84002	8400 StateLine C
	0x84003	8400 HighLine C
	0x84004	8400 TopLine C
3	Main and subversion of firmware	
4	Serial number	

I-1200

Index: I-1200	Name: SDO1 server parameter					
Subindex	Default setting	Display range (min. value unit max. value)			Access	Data type
0: Highest subindex supported	2	2		2	ro	U8
1: COB-ID client -> server (rx)	node ID + 0x600	0		4294967295	ro	U32
2: COB-ID server -> client (tx)	node ID + 0x580	0		4294967295	ro	U32

Identifiers for SDO server channel 1 (basic SDO channel).

- According to DS301 V4.02, the basic SDO channel can neither be changed nor deactivated.

Subindex	Meaning
1	Specification of receive identifier • For SDO server channel 1: node address (C00350) + 0x600
2	Specification of send identifier • For SDO server channel 1: node address (C00350) + 0x580

8th byte		7th byte		6th byte		5th byte	
Data 4		Data 3		Data 2		Data 1	
Bit 31	Bit 30	Bit 29 ... bit 11				Bit 10 ... bit 0	
0	0	Extended identifier*				11-bit identifier	

* The extended identifier is not supported. Bit 11 ... bit 29 must be set to "0".

* The extended identifier is not supported. Bit 11 ... bit 29 must be set to "0".

[12-5] Data telegram assignment

I-1201

Index: I-1201	Name: SDO2 server parameter					
Subindex	Default setting	Setting range (min. value unit max. value)			Access	Data type
0: Highest subindex supported	3	- (read access only)			ro	U8
1: COB-ID client -> server (rx)	0x80000000	0		4294967295	rw	U32
2: COB-ID server -> client (tx)	0x80000000	0		4294967295	rw	U32

Identifiers for SDO server channel 2.

- The SDO server parameter is only valid, if bit 31 is set to "0" for both transmission directions (subindex 1 and 2).
- In the Lenze setting, the SDO server channels 2 are deactivated (bit 31 = "1").
- The identifier can only be changed if the SDO is invalid (bit 31 = "1").

Subindex	Meaning
1	Specification of receive identifier
2	Specification of send identifier

8th byte		7th byte		6th byte		5th byte	
Data 4		Data 3		Data 2		Data 1	
Bit 31	Bit 30	Bit 29 ... bit 11				Bit 10 ... bit 0	
0/1	0	Extended identifier*				11-bit identifier	
* The extended identifier is not supported. Bit 11 ... bit 29 must be set to "0".							

* The extended identifier is not supported. Bit 11 ... bit 29 must be set to "0".

[12-6] Data telegram assignment

Bit	Setting	
Bit 31	0	SDO is valid.
	1	SDO is invalid.

How to change the identifier:

1. Deactivate identifier (set bit 31 to "1").
2. Change identifier.
3. Activate identifier (set bit 31 to "0").

Example

Parameter data channel 2 of the controller with node address 4 shall be activated.

- For this, bit 31 must be set to "0" (\equiv "SDO is valid") in subindices 1 and 2 of the object [I-1201](#).
- The master must send the two "write request" commands to the nodes via the basic SDO channel.

Identifier calculation

- Identifier (COB-ID) = basic identifier + node address (node ID)
- Basic identifier SDO2 from master to drive: 1600 (0x640)
→ Identifier = 0x640 + 0x4 = 0x644
- Basic identifier SDO2 from drive to master: 1472 (0x5C0)
→ Identifier = 0x5C0 + 0x4 = 0x5C4

Resulting data (data 1 ... data 4)

8th byte			7th byte			6th byte			5th byte		
Data 4			Data 3			Data 2			Data 1		
Bit 31	Bit 30	Bit 29 ... bit 11						Bit 10 ... bit 0			
0	0	Extended identifier = 0						11-bit identifier = 0x644			
0x00			0x00			0x06			0x44		

[12-7] Data telegram assignment for subindex 1

8th byte		7th byte		6th byte		5th byte	
Data 4		Data 3		Data 2		Data 1	
Bit 31	Bit 30	Bit 29 ... bit 11				Bit 10 ... bit 0	
0	0	Extended identifier = 0				11-bit identifier = 0x5C4	
0x00		0x00		0x05		0xC4	

[12-8] Data telegram assignment for subindex 2

User data assignment

1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
Command	Index		Subindex	Data 1	Data 2	Data 3	Data 4
0x23	0x01	0x12	0x01	0x44	0x06	0x00	0x00

[12-9] User data assignment for writing to subindex 1

1st byte	2nd byte	3rd byte	4th byte	5th byte	6th byte	7th byte	8th byte
Command	Index		Subindex	Data 1	Data 2	Data 3	Data 4
0x23	0x01	0x12	0x02	0xC4	0x05	0x00	0x00

[12-10] User data assignment for writing to subindex 2

I-1400

Index: I-1400	Name: RPDO1 communication parameter					
Subindex	Default setting	Setting range (min. value unit max. value)			Access	Data type
0: Highest subindex supported	5	- (read access only)			ro	U8
1: COB-ID used by RPDO	0x200 + node ID	0		4294967295	rw	U32
2: Transmission type	254	0		255	rw	U8
3: Inhibit time	-	- (not used for RPDOs)			rw	U16
4: Compatibility entry	-	- (reserved, read or write access leads to error message 0x06090011)			rw	U8
5: Event timer	-	- (not used for RPDOs)			rw	U16

Communication parameter for receiving process data via RPDO1

Subindex	Meaning	Code
0	"5" is permanently set. • Max. 5 subindices are supported.	-
1	RPDO1 identifier • According to the "Predefined Connection Set", the basic setting is: Identifier = 0x200 + node ID	C00354/1
2	RPDO transmission type according to DS301 V4.02 ▶ Transmission type (☞ 780)	C00323/1

8th byte		7th byte		6th byte		5th byte	
Data 4		Data 3		Data 2		Data 1	
Bit 31	Bit 30	Bit 29 ... bit 11				Bit 10 ... bit 0	
0/1	0/1	Extended identifier*				11-bit identifier	

* The extended identifier is not supported. Bit 11 ... bit 29 must be set to "0".

[12-11] Data telegram assignment

How to change the identifier:

1. Deactivate identifier (set bit 31 to "1").
2. Change identifier.
3. Activate identifier (set bit 31 to "0").

Description of subindex 1

Bit no.	Value	Explanation
0 ... 10	0/1	11-bit identifier
(11 ... 28)*	0	*) The extended identifier (29 bits) is not supported. Any of these bits must be "0".
29*	0	
30	0	RTR to this PDO possible (cannot be set)
	1	RTR to this PDO not possible (Lenze)
31	0	PDO active
	1	PDO not active

[12-12] I-1400 ... I-1402, subindex 1

Description of subindex 2

cyclic	PDO transmission		Transmission type	Explanation
	synchronous	event-controlled		
X	X		n = 1 ... 240	When a value n is entered, this PDO will be accepted with every nth SYNC.
		X	n = 254	PDO will be accepted immediately.

[12-13] I-1400 ... I-1402, subindex 2

I-1401

Index: I-1401	Name: RPDO2 communication parameter				
Subindex	Default setting	Setting range (min. value unit max. value)			Access Data type
0: Highest subindex supported	5	- (read access only)			ro U8
1: COB-ID used by RPDO	0x300 + node ID	0		4294967295	rw U32
2: Transmission type	254	0		255	rw U8
3: Inhibit time	-	- (not used for RPDOs)			rw U16
4: Compatibility entry	-	- (reserved, read or write access leads to error message 0x06090011)			rw U8
5: Event timer	-	- (not used for RPDOs)			rw U16

Communication parameter for receiving process data via RPDO2

Subindex	Meaning	Code
0	"5" is permanently set. • Max. 5 subindices are supported.	-
1	RPDO2 identifier • According to the "Predefined Connection Set", the basic setting is: Identifier = 0x300 + node ID	C00354/3
2	RPDO transmission type according to DS301 V4.02 ▶ Transmission type (□ 780)	C00323/2

- For data telegram assignment and description of subindices 1 and 2, see object [I-1400](#).

How to change the identifier:

1. Deactivate identifier (set bit 31 to "1").
2. Change identifier.
3. Activate identifier (set bit 31 to "0").

I-1402

Index: I-1402	Name: RPDO3 communication parameter				
Subindex	Default setting	Setting range (min. value unit max. value)			Access Data type
0: Highest subindex supported	5	- (read access only)			ro U8
1: COB-ID used by RPDO	0x400 + node ID	0		4294967295	rw U32
2: Transmission type	254	0		255	rw U8
3: Inhibit time	-	- (not used for RPDOs)			rw U16
4: Compatibility entry	-	- (reserved, read or write access leads to error message 0x06090011)			rw U8
5: Event timer	-	- (not used for RPDOs)			rw U16

Communication parameter for receiving process data via RPDO3

Subindex	Meaning	Code
0	"5" is permanently set. • Max. 5 subindices are supported.	-
1	RPDO3 identifier • According to the "Predefined Connection Set", the basic setting is: Identifier = 0x400 + node ID	C00354/5
2	RPDO transmission type according to DS301 V4.02 ▶ Transmission type (☞ 780)	C00323/3

- For data telegram assignment and description of subindices 1 and 2, see object [I-1400](#).

How to change the identifier:

1. Deactivate identifier (set bit 31 to "1").
2. Change identifier.
3. Activate identifier (set bit 31 to "0").

I-1403

From version 15.00.00

Index: I-1403	Name: RPDO4 communication parameter					
Subindex	Default setting	Setting range (min. value unit max. value)			Access	Data type
0: Highest subindex supported	5	- (read access only)			ro	U8
1: COB-ID used by RPDO	0x500 + node ID	0		4294967295	rw	U32
2: Transmission type	254	0		255	rw	U8
3: Inhibit time	-	- (not used for RPDOs)			rw	U16
4: Compatibility entry	-	- (reserved, read or write access leads to error message 0x06090011)			rw	U8
5: Event timer	-	- (not used for RPDOs)			rw	U16

Communication parameter for receiving process data via RPDO4

Subindex	Meaning	Code
0	"5" is permanently set. • Max. 5 subindices are supported.	-
1	Identifier RPDO4 • According to the "Predefined Connection Set", the basic setting is: Identifier = 0x500 + node ID	C00354/7
2	RPDO transmission type according to DS301 V4.02 ▶ Transmission type (□ 780)	C00323/4

- For data telegram assignment and description of subindices 1 and 2, see object [I-1400](#).

How to change the identifier:

1. Deactivate identifier (set bit 31 to "1").
2. Change identifier.
3. Activate identifier (set bit 31 to "0").

I-1600

Index: I-1600	Name: RPDO1 mapping parameter					
Subindex	Default setting	Setting range (min. value unit max. value)			Access	Data type
0: Number of mapped application objects in PDO	0	0		8	rw	U8
1 ... 4: Application object 1 ... 4	0	0		4294967295	rw	U32

The object I-1600 serves to receive parameter data as RPDO1.

- This object relates to codes [C00409/1...4](#) and [C00866/1...4](#).
- **From version 12.00.00 onwards:** For 32-bit values, this object relates to codes [C00407/1...2](#).

Subindex	Meaning
0	Number of mapped objects
1 ... 4	Mapping entries 1 ... 4 for RPDO1 <ul style="list-style-type: none"> • The 4th mapping entry is used for the statistic mapping. For this, there is no value available.

8th byte	7th byte	6th byte	5th byte
Data 4	Data 3	Data 2	Data 1
Bit 31 ... bit 16		Bit 15 ... bit 8	Bit 7 ... bit 0
Index		Subindex	Length

[12-14] Data telegram assignment

IEC 61131 process data words are mapped. Only whole bytes can be mapped (1-byte/mapping entry).

Related topics:

- ▶ [RPDO1 | Port block "LP_CanIn1"](#) (📖 766)

I-1601

Index: I-1601	Name: RPDO2 mapping parameter				
Subindex	Default setting	Setting range (min. value unit max. value)			Access Data type
0: Number of mapped application objects in PDO	0	0		8	rw U8
1 ... 4: Application object 1 ... 4	0	0		4294967295	rw U32

The object I-1601 serves to receive parameter data as RPDO2.

- This object relates to codes [C00409/5...8](#) and [C00866/5...8](#).
- **From version 12.00.00 onwards:** For 32-bit values, this object relates to codes [C00407/3...4](#).

Subindex	Meaning
0	Number of mapped objects
1 ... 4	Mapping entries 1 ... 4 for RPDO2 <ul style="list-style-type: none"> • The 4th mapping entry is used for the statistic mapping. For this, there is no value available.

- For data telegram assignment, see object [I-1600](#).

Related topics:

► [RPDO2 | "LP_CanIn2" port block](#) (📖 768)

I-1602

Index: I-1602	Name: RPDO3 mapping parameter				
Subindex	Default setting	Setting range (min. value unit max. value)			Access Data type
0: Number of mapped application objects in PDO	0	0		8	rw U8
1 ... 4: Application object 1 ... 4	0	0		4294967295	rw U32

The object I-1602 serves to receive parameter data as RPDO3.

- This object relates to codes [C00409/9...12](#) and [C00866/9...12](#).
- **From version 12.00.00 onwards:** For 32-bit values, this object relates to codes [C00407/5...6](#).

Subindex	Meaning
0	Number of mapped objects
1 ... 4	Mapping entries 1 ... 4 for RPDO3 <ul style="list-style-type: none"> • The 4th mapping entry is used for the statistic mapping. For this, there is no value available.

- For data telegram assignment, see object [I-1600](#).

Related topics:

► [RPDO3 | "LP_CanIn3" port block](#) (📖 770)

I-1603

From version 15.00.00

Index: I-1603	Name: RPDO4 mapping parameter					
Subindex	Default setting	Setting range (min. value unit max. value)			Access	Data type
0: Number of mapped application objects in PDO	0	0		8	rw	U8
1 ... 4: Application object 1 ... 4	0	0		4294967295	rw	U32

The object I-1603 serves to receive parameter data as RPDO4.

- This object relates to codes [C00409/13...16](#) and [C00866/13...16](#).
- For 32-bit values, this object relates to the codes [C00407/7...8](#).

Subindex	Meaning
0	Number of mapped objects
1 ... 4	Mapping entries 1 ... 4 for RPDO4 <ul style="list-style-type: none"> • The 4th mapping entry is used for the statistic mapping. For this, there is no value available.

- For data telegram assignment, see object [I-1600](#).

Related topics:

► [RPDO4 | "LP_CanIn4" port block](#) (📖 772)

I-1800

Index: I-1800	Name: TPDO1 communication parameter					
Subindex	Default setting	Setting range (min. value unit max. value)			Access	Data type
0: Highest subindex supported	5	- (read access only)			ro	U8
1: COB-ID used by TPDO	0x180 + node ID	0		4294967295	rw	U32
2: Transmission type	254	0		255	rw	U8
3: Inhibit time	0 ms	0	0.1 ms	65535	rw	U16
4: Reserved	-	- (reserved, read or write access leads to error message 0x06090011)			rw	U8
5: Event timer	0 ms	0	ms	65535	rw	U16

Communication parameter for sending process data via TPDO1

Subindex	Meaning	Code
0	"5" is permanently set. • Max. 5 subindices are supported.	-
1	TPDO1 identifier • According to the "Predefined Connection Set", the basic setting is: Identifier = 0x180 + node ID	C00354/2
2	TPDO transmission type according to DS301 V4.02 ► Transmission type (□ 780)	C00322/1
3	Minimum time between sending two identical TPDOs (see DS301 V4.02).	C00324/2
5	Cycle time for PDO transmission with transmission type "254".	C00356/5 C00369

8th byte		7th byte		6th byte		5th byte	
Data 4		Data 3		Data 2		Data 1	
Bit 31	Bit 30	Bit 29 ... bit 11				Bit 10 ... bit 0	
0/1	0/1	Extended identifier*				11-bit identifier	

* The extended identifier is not supported. Bit 11 ... bit 29 must be set to "0".

[12-15] Data telegram assignment

Bit	Setting
Bit 30	0 RTR to this PDO possible (Lenze).
	1 RTR to this PDO not possible (not adjustable)
Bit 31	0 PDO active
	1 PDO inactive

How to change the identifier:

1. Deactivate identifier (set bit 31 to "1").
2. Change identifier.
3. Activate identifier (set bit 31 to "0").

Subindex 2 - transmission type

cyclic	PDO transmission		Transmission type	Explanation
	synchronous	event-controlled		
•	•		n = 1 ... 240	When a value n is entered, this PDO will be accepted with every nth SYNC.
	•		n = 252	On sync, the PDO is filled with new data, but only sent on RTR.
		•	n = 254, 255	Event-controlled or cyclic

Subindex 3 - inhibit time

**Note!**

The delay time can only be changed when the PDO is not active (see subindex 1, bit 31 = 1).

The entered value multiplied by 0.1 gives the delay time in [ms]. Only integers will be considered, i.e. fractional numbers will be **rounded down** to integers.

Example:

- Entered value: 26
- Calculated time = $26 \times 0.1 \text{ [ms]} = 2.6 \text{ [ms]} \rightarrow \text{delay time} = 2 \text{ [ms]}$

Subindex 5 - event timer

For cyclic operation (transmission type 254), the cycle time for sending the process data object on the system bus can be set under subindex 5:

The entered value corresponds to the time in [ms].

I-1801

Index: I-1801	Name: TPDO2 communication parameter				
Subindex	Default setting	Setting range (min. value unit max. value)			Access Data type
0: Highest subindex supported	5	- (read access only)			ro U8
1: COB-ID used by TPDO	0x280 + node ID	0		4294967295	rw U32
2: Transmission type	254	0		255	rw U8
3: Inhibit time	0 ms	0	0.1 ms	65535	rw U16
4: Reserved	-	- (reserved, read or write access leads to error message 0x06090011)			rw U8
5: Event timer	0 ms	0	ms	65535	rw U16

Communication parameter for sending process data via TPDO2

Subindex	Meaning	Code
0	"5" is permanently set. • Max. 5 subindices are supported.	-
1	TPDO2 identifier • According to the "Predefined Connection Set", the basic setting is: Identifier = 0x280 + node ID	C00354/4
2	TPDO transmission type according to DS301 V4.02 ► Transmission type (□ 780)	C00322/2
3	Minimum time between sending two identical TPDOs (see DS301 V4.02).	C00324/3
5	Cycle time for PDO transmission with transmission type "254".	C00356/2 C00369

- For data telegram assignment and description of subindices, see object [I-1800](#).

How to change the identifier:

1. Deactivate identifier (set bit 31 to "1").
2. Change identifier.
3. Activate identifier (set bit 31 to "0").

I-1802

Index: I-1802	Name: TPDO3 communication parameter				
Subindex	Default setting	Setting range (min. value unit max. value)			Access Data type
0: Highest subindex supported	5	- (read access only)			ro U8
1: COB-ID used by TPDO	0x380 + node ID	0		4294967295	rw U32
2: Transmission type	254	0		255	rw U8
3: Inhibit time	0 ms	0	0.1 ms	65535	rw U16
4: Reserved	-	- (reserved, read or write access leads to error message 0x06090011)			rw U8
5: Event timer	0 ms	0	ms	65535	rw U16

Communication parameter for sending process data via TPDO3

Subindex	Meaning	Code
0	"5" is permanently set. • Max. 5 subindices are supported.	-
1	TPDO3 identifier • According to the "Predefined Connection Set", the basic setting is: Identifier = 0x380 + node ID	C00354/6
2	TPDO transmission type according to DS301 V4.02 ▶ Transmission type (□ 780)	C00322/3
3	Minimum time between sending two identical TPDOs (see DS301 V4.02).	C00324/4
5	Cycle time for PDO transmission with transmission type "254".	C00356/3 C00369

- For data telegram assignment and description of subindices, see object [I-1800](#).

How to change the identifier:

1. Deactivate identifier (set bit 31 to "1").
2. Change identifier.
3. Activate identifier (set bit 31 to "0").

I-1803

From version 15.00.00

Index: I-1803	Name: TPDO4 communication parameter					
Subindex	Default setting	Setting range (min. value unit max. value)			Access	Data type
0: Highest subindex supported	5	- (read access only)			ro	U8
1: COB-ID used by TPDO	0x480 + node ID	0		4294967295	rw	U32
2: Transmission type	254	0		255	rw	U8
3: Inhibit time	0 ms	0	0.1 ms	65535	rw	U16
4: Reserved	-	- (reserved, read or write access leads to error message 0x06090011)			rw	U8
5: Event timer	0 ms	0	ms	65535	rw	U16

Communication parameter for sending process data via TPDO4

Subindex	Meaning	Code
0	"5" is permanently set. • Max. 5 subindices are supported.	-
1	Identifier TPDO4 • According to the "Predefined Connection Set", the basic setting is: Identifier = 0x480 + node ID	C00354/8
2	TPDO transmission type according to DS301 V4.02 ► Transmission type (□ 780)	C00322/4
3	Minimum time between sending two identical TPDOs (see DS301 V4.02).	C00324/5
5	Cycle time for PDO transmission with transmission type "254".	C00356/4 C00369

- For data telegram assignment and description of subindices, see object [I-1800](#).

How to change the identifier:

1. Deactivate identifier (set bit 31 to "1").
2. Change identifier.
3. Activate identifier (set bit 31 to "0").

I-1A00

Index: I-1A00	Name: TPDO1 mapping parameter					
Subindex	Default setting	Setting range (min. value unit max. value)			Access	Data type
0: Number of mapped application objects in PDO	0	0		8	rw	U8
1 ... 4: Application object 1 ... 4	0	0		4294967295	rw	U32

The object I-1A00 serves to send parameter data as TPDO1.

- This object relates to code [C00868/1...4](#).

Subindex	Meaning
0	Number of mapped objects
1 ... 4	Mapping entries 1 ... 4 for TPDO1 <ul style="list-style-type: none"> • The 4th mapping entry is used for the statistic mapping. For this, there is no value available.

8th byte	7th byte	6th byte	5th byte
Data 4	Data 3	Data 2	Data 1
Bit 31 ... bit 16		Bit 15 ... bit 8	Bit 7 ... bit 0
Index		Subindex	Length

[12-16] Data telegram assignment

IEC 61131 process data words are mapped. Only whole bytes can be mapped (1-byte/mapping entry).

Related topics:

- ▶ [TPDO1 | "LP_CanOut1" port block](#) (📖 774)

I-1A01

Index: I-1A01	Name: TPDO2 mapping parameter					
Subindex	Default setting	Setting range (min. value unit max. value)			Access	Data type
0: Number of mapped application objects in PDO	0	0		8	rw	U8
1 ... 4: Application object 1 ... 4	0	0		4294967295	rw	U32

The object I-1A01 serves to send parameter data as TPDO2.

- This object relates to code [C00868/5...8](#).

Subindex	Meaning
0	Number of mapped objects
1 ... 4	Mapping entries 1 ... 4 for TPDO2 <ul style="list-style-type: none"> • The 4th mapping entry is used for the statistic mapping. For this, there is no value available.

- For data telegram assignment, see object [I-1A00](#).

Related topics:

- ▶ [TPDO2 | "LP_CanOut2" port block](#) (📖 775)

I-1A02

Index: I-1A02	Name: TPDO3 mapping parameter				
Subindex	Default setting	Setting range (min. value unit max. value)			Access Data type
0: Number of mapped application objects in PDO	0	0		8	rw U8
1 ... 4: Application object 1 ... 4	0	0		4294967295	rw U32

The object I-1A02 serves to send parameter data as TPDO3.

- This object relates to code [C00868/9...12](#).

Subindex	Meaning
0	Number of mapped objects
1 ... 4	Mapping entries 1 ... 4 for TPDO3 <ul style="list-style-type: none"> • The 4th mapping entry is used for the statistic mapping. For this, there is no value available.

- For data telegram assignment, see object [I-1A00](#).

Related topics:

► [TPDO3 | "LP_CanOut3" port block](#) (📖 776)

I-1A03

Index: I-1A03	Name: TPDO4 mapping parameter				
Subindex	Default setting	Setting range (min. value unit max. value)			Access Data type
0: Number of mapped application objects in PDO	0	0		8	rw U8
1 ... 4: Application object 1 ... 4	0	0		4294967295	rw U32

The object I-1A03 serves to send parameter data as TPDO4.

- This object relates to code [C00868/13...16](#).

Subindex	Meaning
0	Number of mapped objects
1 ... 4	Mapping entries 1 ... 4 for TPDO4 <ul style="list-style-type: none"> • The 4th mapping entry is used for the statistic mapping. For this, there is no value available.

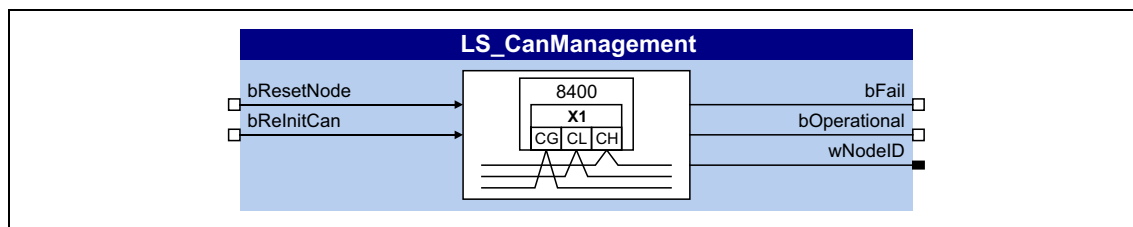
- For data telegram assignment, see object [I-1A00](#).

Related topics:

► [TPDO4 | "LP_CanOut4" port block](#) (📖 777)

12.12 Internal interfaces | System block "LS_CANManagement"

The **LS_CANManagement** system block serves to control internal functions of the CAN driver (reset node and re-initialisation) and to display the "Operational" status as well as the node address (analogous to the 9300 ServoPLC and ECS devices).



Inputs

Identifier	Data type	Information/possible settings
bResetNode	BOOL	Reset node
		TRUE Carry out reset node <ul style="list-style-type: none"> If the controller is configured as CAN master in C00352, the NMT command "Start Remote Node" is sent to all nodes at the bus (broadcast telegram). ▶ Network management telegram (NMT)
bReInitCAN	BOOL	Reinitialisation
		TRUE Reinitialise "CAN on board" interface.

Outputs

Identifier	Data type	Value/meaning
bFail	BOOL	Fault
		TRUE An event according to the error configuration in C00341 has occurred
bOperational	BOOL	"Operational" status signal
		TRUE The system bus is in the "Operational" status
wNodeID	WORD	Output of the node address



Note!

If a "Bus off" error is detected, the "CAN on board" interface will automatically be reinitialised after 1 second.








Hence, 1 second after the "Bus off" has occurred, the controller will automatically be active again on the system bus ("Auto bus off recovery").

13 Fieldbus interface (MCI)

The Inverter Drives 8400 can accommodate plug-in communication modules and can therefore take part in the data transfer of an existing fieldbus system.

When using a communication module, the major advantage for the user is the possibility of parameterising, controlling, and diagnosing the drive system via the available fieldbus.

The following fieldbuses are supported by the 8400 TopLine:

Fieldbus	Communication module (type designation)
	System bus "CAN on board" (permanently integrated in the standard device)
	EtherCAT® (E84AYCET)
	Ethernet POWERLINK (E84AYCEC)
	EtherNet/IP™ (E84AYCEO)
	INTERBUS (E84AYCIB)
	PROFIBUS® (E84AYCPM)
	PROFINET® (E84AYCER)

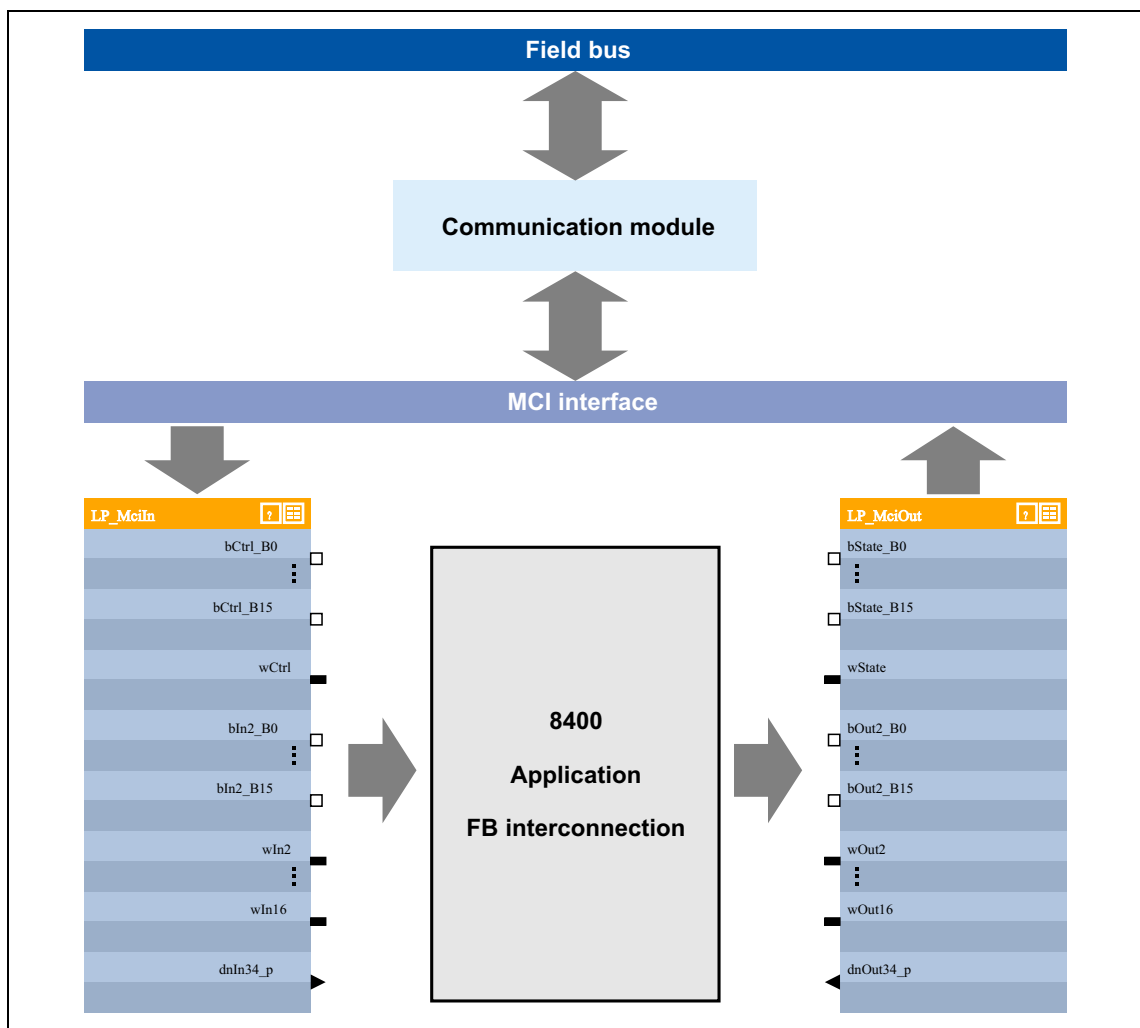


Detailed information is provided in the communication manual (KHB) for the respective fieldbus and in the »Engineer« online help.

13.1 Process data transfer

The process data serve to control the controller. Thus the transfer of the process data is time-critical.

- The process cycle is 1 ms, irrespective of the respectively plugged-in bus system and the type of drive controller.
- Process data transfer takes place cyclically between the master system and the drive controllers.
 - This concerns the continuous exchange of current input and output data.
 - In the case of the 8400 drive controller, 16 words per direction are exchanged.
- The master computer can directly access the process data.
Access to the process data takes place via the port blocks **LP_MciIn** and **LP_MciOut** (see FB interconnection of the »Engineer«).
These port blocks are also called process data channels.
- The process data are not saved in the controller.



[13-1] External and internal data transfer between bus system, drive controller and function block interconnection

Voltage supply

Depending on the complexity and functional range of the fieldbus, the communication modules are supplied by the standard device or an external 24 V supply at the module.

The external 24 V voltage supply of the communication module is required if the supply of the standard device fails but the communication via the bus is to continue.

Parameter setting of the communication modules

All codes which must be parameterised for establishing the fieldbus communication are saved in the memory module of the controller.

The archived data can be addressed by all bus systems supported by the controller.

Hotplug

The communication module (MCI module) can be plugged in/out while the controller is switched on. When the module is plugged in, it is automatically detected and checked for plausibility regarding the function and version.

Fieldbus-specific device profiles and PDO mapping

When specific bus systems are used, the controller is to behave according to a defined, manufacturer-spanning standard. The following definitions have been made for this:

- Definitions of the device state machine (e.g. DSP402, DriveCOM, ProfiDrive etc.)
- Definition of the bit assignment of control and status words
- Definition of signal scaling (on a limited scale)
- Definition of parameter scaling (on a limited scale)
- Definition of the process data mapping

These device profiles are not mapped in the communication module since some definitions have a strong effect on the device-internal behaviour and the device profiles are not uniform regarding this matter.

- The task of the communication modules is
 - to address parameters (SDOs),
 - to transfer PDOs and
 - the signal mapping of the PDOs.
- The process data objects (e.g. the meaning of the control word bits or the speed setpoint stipulated) are interpreted in the drive controller.

13.2 Control mode "MCI"

"40: MCI" can be selected as a control mode in [C00007](#) in order to quickly and easily set-up drive controller control by means of MCI-PDOs via the fieldbus interface.

Given that the technology applications are fundamentally different and have different requirements regarding the signals sent to them, predefined assignment of the MCI-PDOs depends on the technology application selected in [C00005](#):

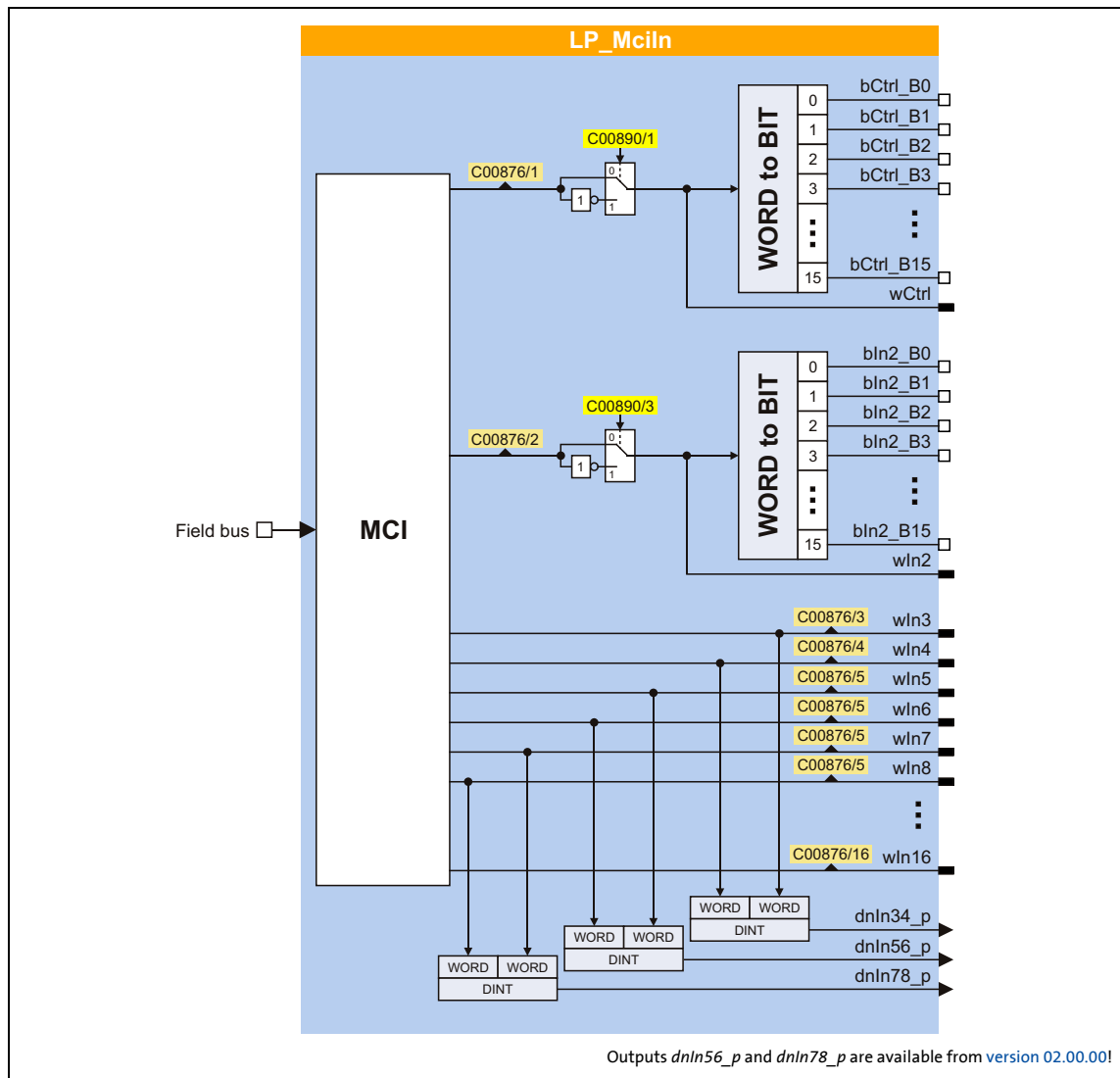
- **TA "Actuating drive speed":**
[Process data assignment for fieldbus communication](#) (📖 450)
- **TA "Table positioning":**
[Process data assignment for fieldbus communication](#) (📖 513)
- **TA "Abschaltpositionierung":**
[Process data assignment for fieldbus communication](#) (📖 539)

**Tip!**

The predefined assignment of the MCI-PDOs can be parameterised by means of PDO mapping and can be freely configured on the I/O level in the function block editor (FB editor).

13.2.1 Port block "LP_MciIn"

The **LP_MciIn** port block maps the received MCI-PDOs in the FB Editor.

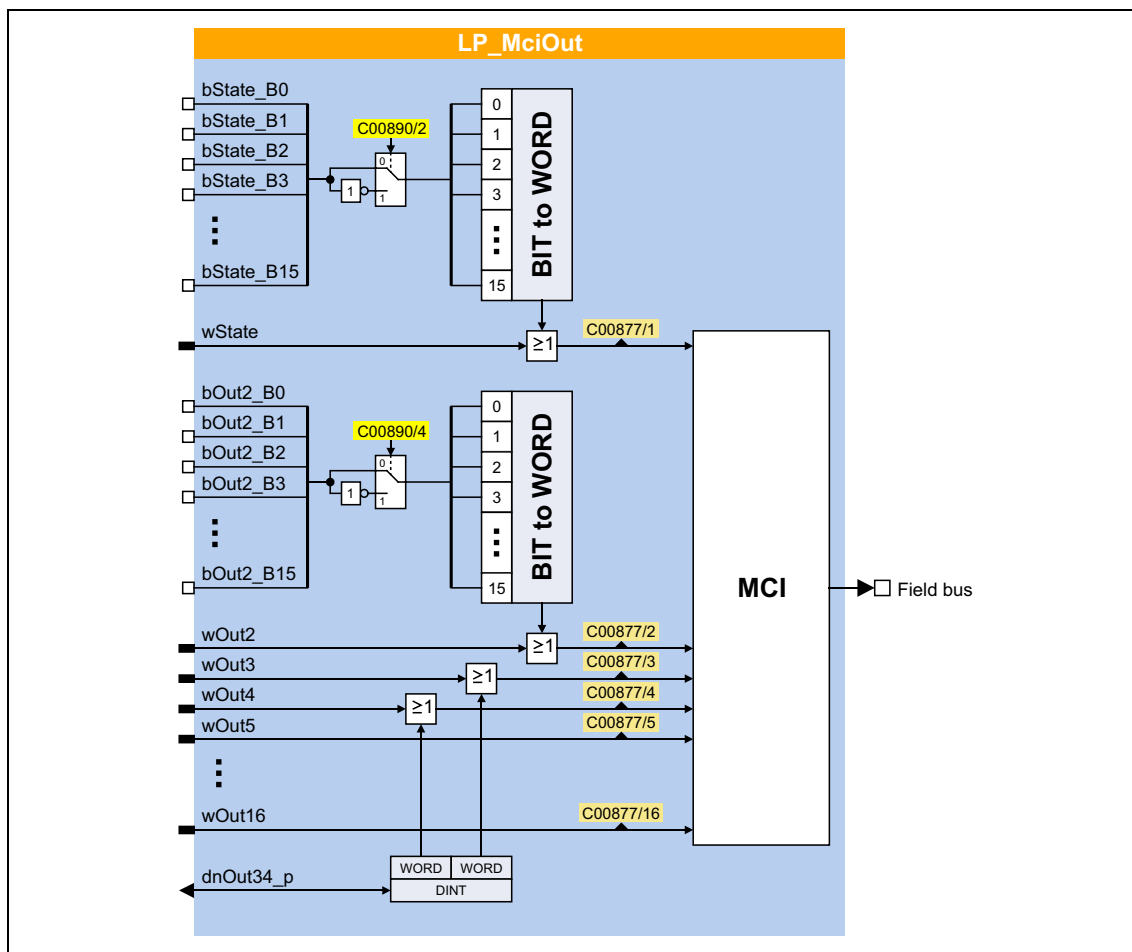


Short overview of the parameters for **LP_MciIn**:

Parameter	Info	Lenze setting
C00876/1	LP_MciIn:wCtrl	-
C00876/2...16	LP_MciIn: wln2 ... wln16	-
C00890/1	LP_MciIn: Inversion bCtrl_B0..15	0x0000
C00890/3	LP_MciIn: Inversion bln2_B0..15	0x0000
Highlighted in grey = display parameter		

13.2.2 Port block "LP_MciOut"

The **LP_MciOut** port block maps the MCI-PDOs to be transmitted in the FB Editor.



Short overview of the parameters for **LP_MciOut**:

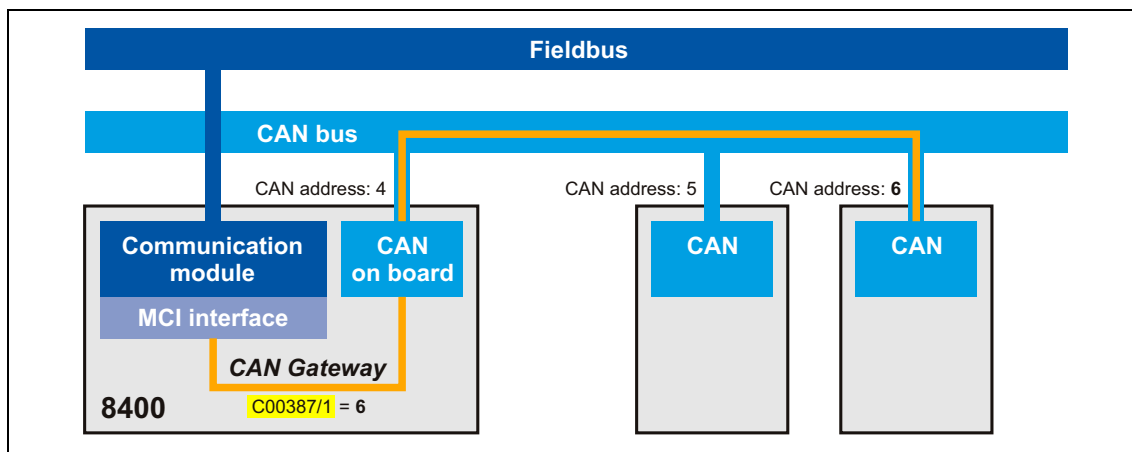
Parameter	Info	Lenze setting
C00877/1	LP_MciOut:wState	-
C00877/2...16	LP_MciOut: wOut2 ... wOut16	-
C00890/2	LP_MciOut: Inversion bState_B0..15	0x0000
C00890/4	LP_MciOut: Inversion bOut2_B0..15	0x0000
Highlighted in grey = display parameter		

CAN gateway

This function extension is available from version 12.00.00!

The CAN gateway functionality forwards the read/write requests of the attached communication module to a connected *remote* device via the "CAN on board" system bus. It also receives the responses via this way.

- From the point of view of the attached communication module, the read/write requests are identical to accesses to its own standard device.
- Block services (reading/writing parameters of the "String" data type) can also be executed via the CAN gateway.



[13-2] Functional principle of "CAN gateway"

Activating the CAN gateway

To activate the CAN gateway, the CAN address (1 ... 127) of the connected *remote* device must be set in [C00387/1](#).

- In the Lenze setting [C00387/1](#) = "0", the function is switched off.
- If the CAN gateway is activated, the own controller is the client and the *remote* device is the server.
- If the own CAN address is set, the read/write requests are forwarded to the own controller.
- The parameters of the communication module (C13000 ... C13999) are always processed in the own controller.
- The parameters [C00387/1](#) (CAN gateway address) and [C00350](#) (CAN node address) are not transferred to the *remote* device.

14 Axis bus

This function extension is available from version 02.00.00!

The 8400 TopLine controller has an integrated axis bus which is used to couple several 8400 TopLine controllers in an axis interconnection. The main task of the axis bus is a simple cross-data exchange from axis to axis.

Axis bus operation uses two transmission media, "data transfer axis bus" and "IO axis bus" that can be used as follows:

- The data transfer axis bus is based on CAN physics and enables a high-performance data transfer of master values and control signals to other 8400 TopLine controllers. This always requires a synchronisation of the internal time base of the controllers via the IO axis bus.
- The IO axis bus is a 1-wire bus with open-collector circuitry (5 V isolated). The IO axis bus can either be used to transfer controller errors in the interconnection ("release cord" principle) or as a pure open-collector IO function. In the first case, the internal time base of the controllers can be synchronised via the IO axis bus.

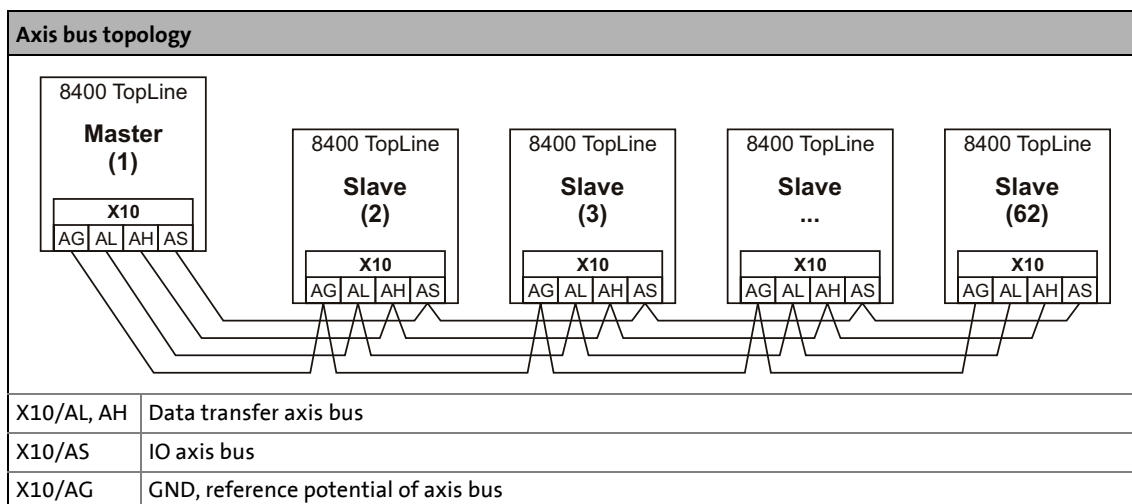
Max. 62 controllers can be connected to the axis bus.



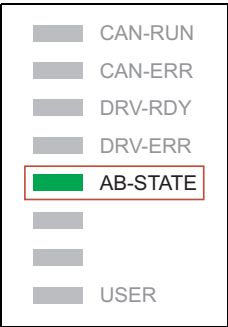
Stop!

The data transfer axis bus of the 8400 TopLine controller is designed especially for performance and simplicity. HMI's and other peripherals as well as the »Engineer« are not supported at the axis bus.





The IO axis bus of the 8400 TopLine controller is not compatible to the state bus of the 9300/9400 device series due to different voltage levels!



14.1 LED status displays of the axis bus



Information on the axis bus status can quickly be obtained via the "AB-STATE" LED display on the front of the controller.
The meaning can be seen from the table below.

LED display	Meaning
OFF	The controller is disconnected from the axis bus as in C02430/1 the node address is set to "0".
 (blinking - 10 Hz)	The axis bus is in the "boot up" phase.
 (blinking - 2 Hz)	The axis bus is in the "Stopped" state
 (blinking - double impulse)	The axis bus is in the "Warning" state. <ul style="list-style-type: none">• The error counter for incorrectly sent or received telegrams has a value > 96.• The data transfer continues to run and the error counter is tried to be reduced to 0 by error-free transfers. ▶ Axis bus data error monitoring
 (permanently on)	The axis bus is in the "PDP active" state (normal operation).

14.2 Data transfer axis bus

The data transfer axis bus is based on isolated CAN physics.

- Max. 62 nodes are supported at the bus (1 master and max. 61 slaves).
- The baud rate is permanently set to 500 kbits.
- Transfer clock = 1 ms

14.2.1 Topologies

There are generally two different topologies for an interconnected operation:

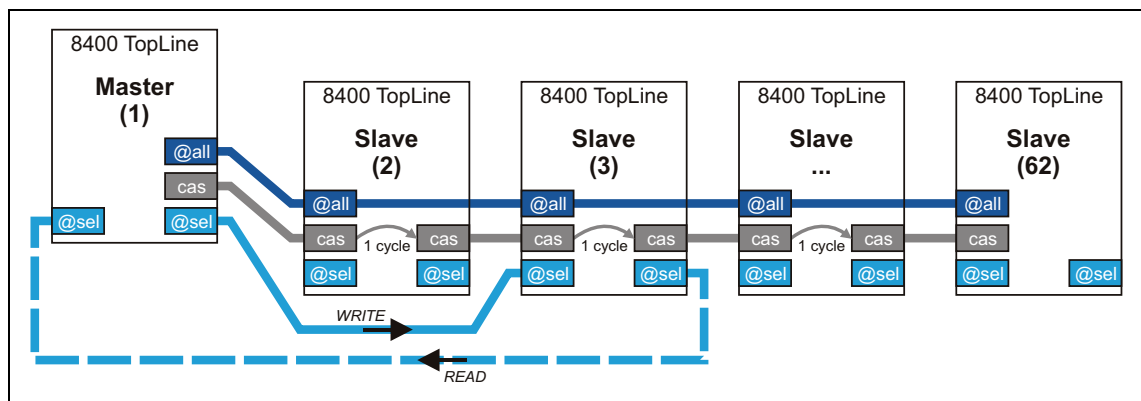
- All nodes of the network are connected to the higher-level master control via MCI module and the respective fieldbus.
 - The axes can exchange data via the axis bus.
 - Moreover, the CAN bus is available.
 - For synchronous fieldbuses as e.g. EtherCAT, synchronicity of all axes towards the EtherCAT fieldbus is achieved by selecting "MCI" as sync source for the axis bus master. The synchronisation of the slaves on the EtherCAT side has to be switched off then.
- Only the axis bus master of the network is connected to the higher-level master control via MCI module and the respective fieldbus.
 - For cost reasons, this topology only makes sense if only few information has to be transferred from the master control to the network.

In both cases, the axes can exchange data via the axis bus and the CAN bus is available in addition.

14.2.2 Transfer mechanisms

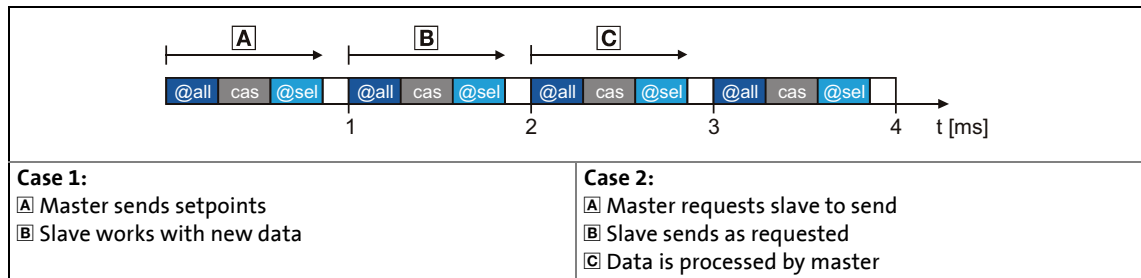
The axis bus supports three different transfer mechanisms simultaneously according to the following methodology:

- "@all": Data transfer from master to all slaves
 - A data packet is sent from the master to all slaves in the transmission cycle.
 - Application: Data distribution according to line topology
 - Cycle time = transmission cycle = 1 ms (at baud rate = 500 kbits)
- "cas": Data transfer from node to node (cascade)
 - In the first transmission cycle, a data packet is sent from master to slave 1, in the next transmission cycle from slave 1 to slave 2, etc.
 - Application: Data distribution according to cascade topology
 - Cycle time = transmission cycle * no. of slaves+1
- "@sel": Data transfer from master to a slave
 - A data packet is sent from the master to one selected slave in the transmission cycle.
 - More options: Send to no slave, send to all slaves, and read one selected slave.
 - Application: Data distribution according to line topology for controlling one single node.
 - Cycle time = transmission cycle



[14-1] Transfer mechanisms

The axis bus data is transferred in 1-ms transmission cycle:



[14-2] Data transfer

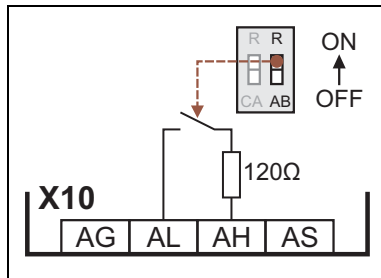
The axis bus data transfer is connected to the master/slave application via the **LS_AxisBus** systems blocks:

- For a data transfer from the master to all slaves (@all) and/or a cascaded data transfer (cas), the systems blocks [LS_AxisBusIn](#) and [LS_AxisBusOut](#) are available in the FB Editor.
- For a data transfer from the master to a certain slave (@sel), the [LS_AxisBusAux](#) system block is available.

14.2.3 Activating the bus terminating resistor

The axis bus must be terminated between axis bus low (AL) and axis bus high (AH) at the first and last physical node each by a resistor (120 Ω).

The 8400 controller is provided with an integrated bus terminating resistor, which can be activated via the DIP switch labelled with "AB":



- OFF = bus terminating resistor is inactive
- ON = bus terminating resistor is active

[14-3] Activation of the integrated bus terminating resistor

14.2.4 Parameter setting

Short overview of the relevant parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C01120	Sync signal source	0: Off	
C02430/1	Axis bus address <ul style="list-style-type: none">• 0 ≡ Node is disconnected from the axis bus• 1 ≡ Master• 2 ... 62 ≡ slave 1 ... slave 61	0	
C02430/2	Axis bus no. of nodes <ul style="list-style-type: none">• Number of controllers connected to the axis bus.	2	
C02431/1	Axis bus decel. boot-up	3000	ms
C02431/2	Axis bus decel. BusOffRecovery	1000	ms
C02431/3	Axis bus monitoring time	1000	ms
C02440/1	Axis bus IO function	0: Off	
▶ Configuring exception handling of the received data			
C02442/1	Decoupling inputs from the axis bus <ul style="list-style-type: none">• From version 12.00.00	0x0000	
C02443/1...11	Decoupling values <ul style="list-style-type: none">• From version 12.00.00	0	
▶ Axis bus data error monitoring			
C00591/1	Resp. to axis bus data error <ul style="list-style-type: none">• From version 12.00.00	1: Fault	
Diagnostic parameter			
C02435	Axis bus status <ul style="list-style-type: none">• Display whether the node participates in the axis bus data exchange (PDO active) or is only switched on passively to the axis bus (PDO stopped).	-	
C02436	Axis bus error status	-	
C02437	Axis bus MessageError <ul style="list-style-type: none">▶ Integrated error detection	-	
C02438/1	Axis bus Tx_Error <ul style="list-style-type: none">• From version 12.00.00• Error counter for faulty sent telegrams.	-	
C02438/2	Axis bus Rx_Error <ul style="list-style-type: none">• From version 12.00.00• Error counter for faulty received telegrams.	-	
C02438/3	Axis bus transmitting meter <ul style="list-style-type: none">• From version 12.00.00• Display of the entire number of sent telegrams	-	
C02438/4	Axis bus receiving meter <ul style="list-style-type: none">• From version 12.00.00• Display of the entire number of received telegrams.	-	

Highlighted in grey = display parameter

14.2.4.1 Required settings at the master

For a "safe" data transfer, one controller must be the master in the network. The master controls and synchronises the network.

Make the following two settings for the controller which is to be the master in the network:

- Axis bus address ([C02430/1](#)) = "1"
 - With this setting, the controller automatically takes over the control in the network.
 - Only one master is allowed in the network.
- Axis bus IO function ([C02440/1](#)) = "1: Master"
 - With this setting, the controller outputs a synchronisation cycle to the I/O axis bus to which the slaves can orient themselves.

Optional: Synchronisation of the internal time base of the master

For the master, a sync signal source (e.g. CAN or MCI) can be selected in [C01120](#).

- Then, the entire axis bus system behaves synchronously with this sync signal.
- The sync signal source "2: AxisBusIO" technically does not make any sense for the axis bus master and is thus ignored (same effect as with setting "0: Off").

Related topics:

- ▶ ["Master/slave" function](#) (852)
- ▶ [Synchronisation of the internal time base](#) (857)

14.2.4.2 Required settings for the slaves

Make the following settings for every slave controller in the network:

- Axis bus address ([C02430/1](#)) = "2" ... "62"
 - Make sure that all controllers connected to the axis bus have different axis bus addresses.
- Sync signal source ([C01120](#)) = "2: AxisBusIO"
 - With this setting, the synchronisation cycle output by the master is used as synchronisation source.
 - Basically, only one source is allowed to synchronise the internal time base.
- Axis bus IO function ([C02440/1](#)) = "2: Slave"
 - This setting serves to define the slave.



Note!

The selection of the "2: AxisBusIO" sync signal source serves to permanently set the parameters given in the following table for synchronising the internal time base to reasonable values in order to ensure a technically perfect operation of the axis bus!

Parameter	Info	Setting for "AxisBusIO" signal source	
		Value	Unit
C01121	Sync cycle time setpoint	2000	µs
C01122	Sync phase position	200	µs
C01123	Sync window	40	µs

Related topics:

▶ ["Master/slave" function](#) (📖 852)

14.2.4.3 Boot-up phase

After the devices (master and slave) are switched on and initialised, first a boot-up phase is executed. In this phase, the master already communicates on the axis bus with the slaves which do not participate yet in the data exchange.

Only when all nodes have been synchronised at the axis bus (synchronisation of the slaves with the axis bus IO is compulsory) and the deceleration time set in [C02431/1](#) has been expired, all nodes change to the "PDO active" bus state.

14.2.4.4 Disconnect nodes from the axis bus

The setting of the axis bus address ([C02430/1](#)) to "0" serves to switch off the corresponding node dynamically from the axis bus.

- The node does not participate in the data exchange anymore.
 - The axis bus LED "AB-STATE" of the node is switched off.
 - [C02435](#) displays the axis bus status "4: Boot-up" for the node.
- The synchronisation and the detection and report of errors via the axis bus IO cable continues to take place.

14.2.4.5 Configuring exception handling of the received data

Certain situations require the axis to be decoupled from the received data of the axis bus, e.g. if a data error has occurred. Then it is not possible anymore, for instance, to position the slave axis to a certain target position.

Exception handling for the received data in the event of an error can be set via decoupling configuration and decoupling values in order to e.g. move the slaves to a parking position.

- Bit-coded selection is carried out in [C02442 1](#) defining the events that will trigger decoupling of the received data.

Bit	Event
Bit 0 <input type="checkbox"/>	BusOff_MsgErr
Bit 1 <input type="checkbox"/>	Warning
Bit 2 <input type="checkbox"/>	NodeStopped • For the master, the <i>bStop</i> input at the SB LS_AxisBusAux has been set to TRUE.
Bit 3 ... 13 <input type="checkbox"/>	Reserved
Bit 14 <input type="checkbox"/>	Trouble
Bit 15 <input type="checkbox"/>	Fault

- Finally, the following parameters define the value that the received data are to have when they are decoupled:

Parameter	Info	Lenze setting	
		Value	Unit
Decoupling values for received data at the SB LS_AxisBusIn :			
C02443/1	LS_AxisBusIn: wLine1 DiscVal	0	
C02443/2	LS_AxisBusIn: wLine2 DiscVal	0	
C02443/3	LS_AxisBusIn: wLine3 DiscVal	0	
C02443/4	LS_AxisBusIn: wCas1 DiscVal	0	
C02443/5	LS_AxisBusIn: wCas2 DiscVal	0	
C02443/6	LS_AxisBusIn: wCas3 DiscVal	0	
C02443/7	LS_AxisBusIn: wCas4 DiscVal	0	
Decoupling values for received data at the SB LS_AxisBusAux :			
C02443/8	LS_AxisBusAux: wAuxIn1 DiscVal	0	
C02443/9	LS_AxisBusAux: wAuxIn2 DiscVal	0	
C02443/10	LS_AxisBusAux: wAuxIn3 DiscVal	0	
C02443/11	LS_AxisBusAux: wAuxIn4 DiscVal	0	

14.2.4.6 Integrated error detection

Just like the system bus ("CAN on board"), the axis bus is also provided with an integrated error detection. If a node detects an error, it rejects the telegram bits received so far and transmits an error flag. The error flag consists of 6 consecutive bits with the same logic value.

The following errors are detected and displayed in [C02437](#):

Fault	Description
Bit error	The sending node follows the transmission on the bus and interrupts the transmission if it receives a different logic value than the value transmitted. With the next bit, the sending node starts the transmission of an error flag. In the arbitration phase, the transmitter only detects a bit error if a dominantly sent bit is received as recessive bit. In the ACK slot as well, the dominant overwriting of a recessive bit is not indicated as a bit error.
Stuff-bit error	If more than 5 consecutive bits have the same logic value before the ACK delimiter in the telegram, the previously transmitted telegram will be rejected and an error flag will be sent with the next bit.
CRC error	If the received CRC checksum does not correspond to the checksum calculated in the bus controller, the bus controller will send an error flag after the ACK delimiter and the previously transmitted telegram will be annulled.
Acknowledgement error	If the sent ACK slot recessively sent by the transmitting node is not dominantly overwritten by a receiver, the transmitting node will cancel the transmission. The transmitting node will annul the transmitted telegram and will send an error flags with the next bit.
Format error	If a dominant bit is detected in the CRC delimiter, in the ACK delimiter or in the first 6 bits of the EOF field, the received telegram will be rejected and an error flag will be sent with the next bit.



Tip!

The errors mentioned before indicate that a physical error has occurred in the bus system.

Possible causes are:

- Several nodes with identical node address
- Too high cable length
- Too many or no terminating resistors
- Too high bus load/too many data telegrams
(e.g. since a node permanently transmits event-controlled due to data changes of an analog signal/actual value.)
- EMC interferences on the axis bus
(e.g. since the axis bus cable next to the motor cable is unshielded)

14.2.4.7 Axis bus data error monitoring

Operating mode

There are two error counters, one for incorrectly sent telegrams ([C02438/1](#)) and one for incorrectly received telegrams ([C02438/2](#)).

- In an error-free normal operation, both error counters are = 0.
- Depending on the error type, the counters are increased by 8 in case of an error detection, and reduced by 1 in case no error has occurred.
 - If one of the two error counters is > 96, a warning is signalled via the LED AB-STATE (double pulse).
 - If an error counter increases or remains unchanged, a watchdog counter is increased in a 1-ms cycle.
 - If an error counter is reduced, the watchdog counter remains unchanged.
 - If the error counters are = 0, the watchdog counter is reset to 0.
- If the watchdog counter reaches the monitoring time set in [C02431/3](#):
 - The error response set in [C00591/1](#) is activated (Lenze setting: "Fault").
 - The error message "[Ab01: AchsbusTimeOut](#)" is entered into the logbook.

Parameterisation notes for "electrical shaft" application

When an "electrical shaft" is operated via an axis bus or generally via a bus system, data transfer errors may occur due to e.g. EMC interferences. In order to prevent a mechanical offset of the drives in case of a short-time interference only, the [L_Interpolator_1](#) function block should be used in the slave drives. This function block has an internal correction mechanism which provides for an automatic offset correction in case of a missing data telegram. The error monitoring can then be set to an insensitive value ([C02431/3](#) = approx. 10 ... 30 ms) which results in a very robust transfer system.

What happens in case of a cable break, loose contact or short circuit of the axis bus cable?

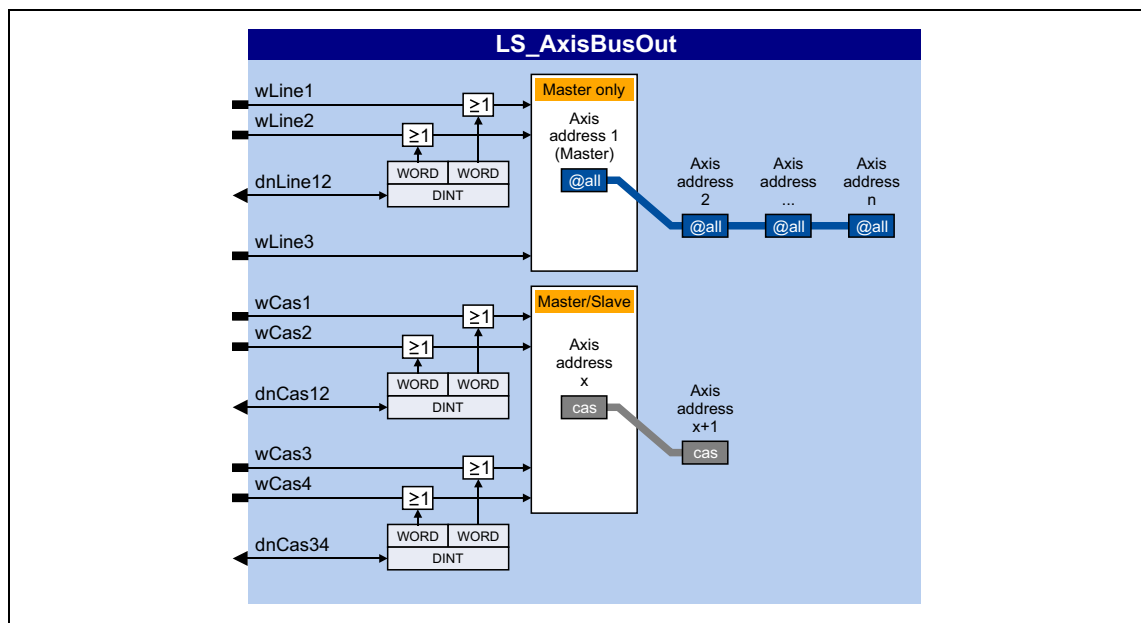
Such severe errors mostly cause a bus-off error in one or even several devices of the system.

- In this case as well, the data error monitoring is triggered.
- The "BusOff" state will be automatically reset after the time set in [C02431/2](#) has expired if the error cause has been removed. Then, the axis bus changes to normal operation again.

14.2.5 Internal interfaces | System block "LS_AxisBusOut"

This system block is used to send line data from the master to all slaves (@all) and/or send the cascaded data (cas).

- The line data is sent as process data object (PDO) per transmission cycle to all slaves and forwarded to the application. Moreover, this PDO serves to transmit an internal control word (thus, only three words are available for data transfer).
- The cascaded data is also sent as PDO per transmission cycle from one slave to the next. The control which slave has to send when and at what time a slave in the chain has to accept the data, is executed by the internal control word in the PDO of the line data.

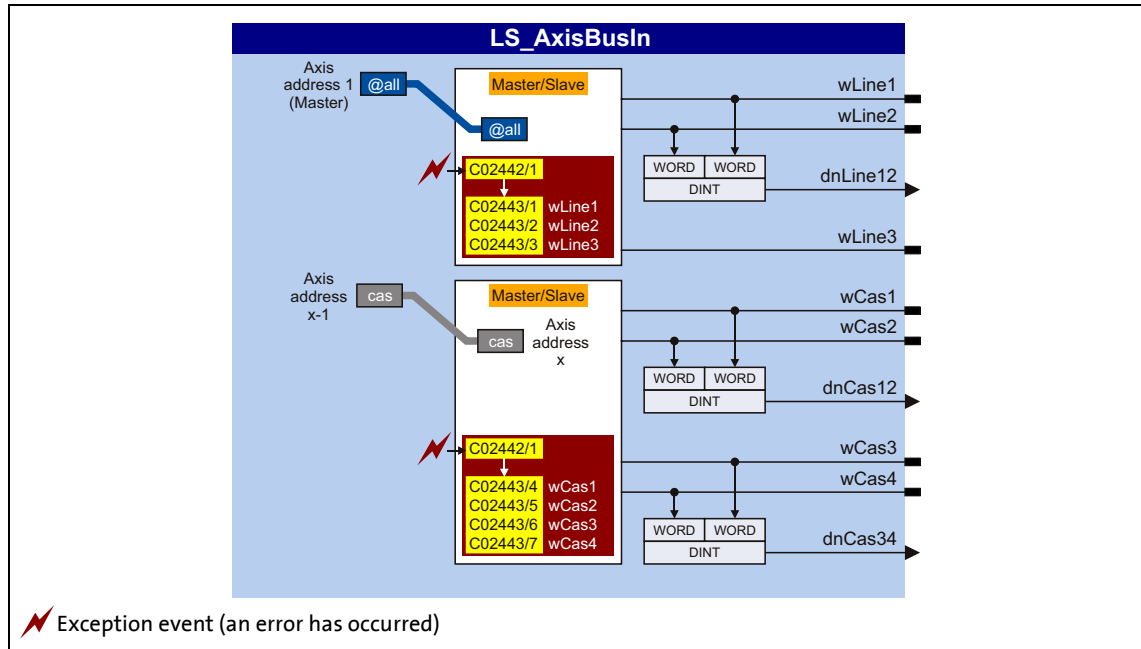


Inputs

Input	Data type	Information/possible settings
wLine1/wLine2	WORD	Line data - word 1 and word 2 <ul style="list-style-type: none"> • Selection as separate words or as double word. • The double word is OR'd with word 1 and word 2.
dnLine12	DINT	
wLine3	WORD	Line data - word 3
wCas1/wCas2	WORD	Cascaded data - word 1 and word 2 <ul style="list-style-type: none"> • Selection as separate words or as double word. • The double word is OR'd with word 1 and word 2.
dnCas12	DINT	
wCas3/wCas4	WORD	Cascaded data - word 3 and word 4 <ul style="list-style-type: none"> • Selection as separate words or as double word. • The double word is OR'd with word 3 and word 4.
dnCas34	DINT	

14.2.6 Internal interfaces | System block "LS_AxisBusIn"

This system block is used to receive the (line) data from the master (@all) and/or receive the cascaded data (cas).



Outputs

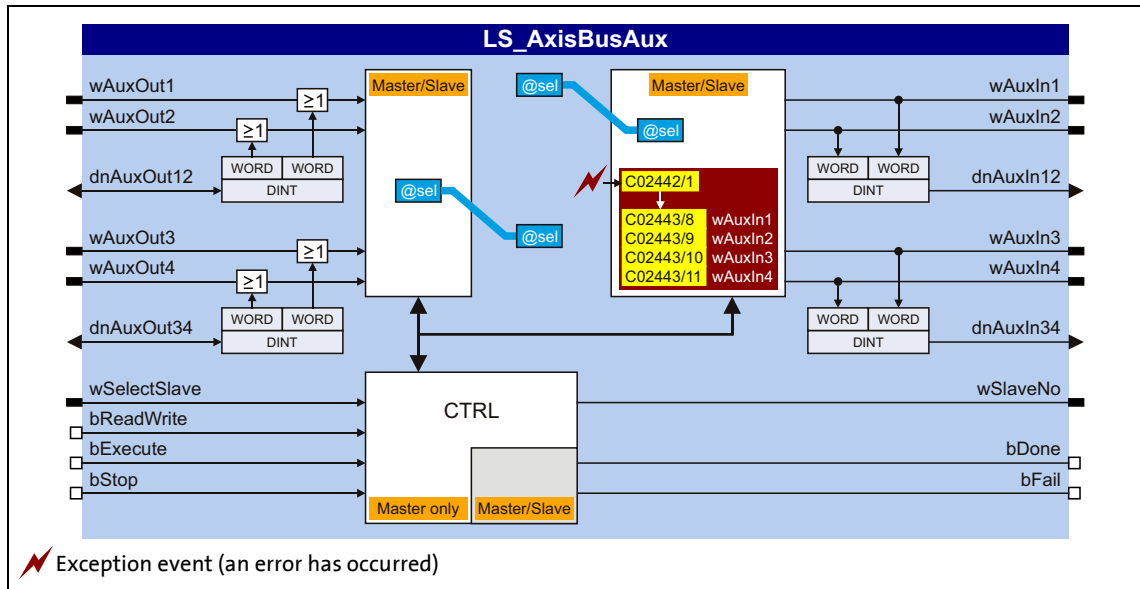
Output	Data type	Value/meaning
wLine1/wLine2	WORD	Line data - word 1 and word 2
dnLine12	DINT	Line data - word 1 and word 2 as double word
wLine3	WORD	Line data - word 3
wCas1/wCas2	WORD	Cascaded data - word 1 and word 2
dnCas12	DINT	Cascaded data - word 1 and word 2 as double word
wCas3/wCas4	WORD	Cascaded data - word 3 and word 4
dnCas34	DINT	Cascaded data - word 3 and word 4 as double word

Related topics:

- [Configuring exception handling of the received data](#) (844)

14.2.7 Internal interfaces | System block "LS_AxisBusAux"

This system block is used for data transfer between the master and one selected slave (@sel). Data can either be received from the slave ("read") or sent to the slave ("write"). By selecting the axis bus address "63", data can also be sent to all slaves at the axis bus.



Inputs

Input	Data type	Information/possible settings	
wAuxOut1/wAuxOut2	WORD	Data to be sent - word 1 and word 2 <ul style="list-style-type: none">• Selection as separate words or as double word.• The double word is OR'd with word 1 and word 2.	
dnAuxOut12			DINT
wAuxOut3/wAuxOut4	WORD	Data to be sent - word 3 and word 4 <ul style="list-style-type: none">• Selection as separate words or as double word.• The double word is OR'd with word 3 and word 4.	
dnAuxOut34			DINT
The following inputs are only relevant for the master except for <i>bExecute</i> . Via these inputs, the master controls the data acceptance of the "@sel" data in the slaves.			
wSelectSlave	WORD	Axis bus address of the slave data is to be received of or data is to be sent to. <ul style="list-style-type: none">• "0" ≡ data is sent to no slave.• "63" ≡ data is sent to all slaves.	
bReadWrite	BOOL	Read/write access	
		FALSE	Data is sent to selected slave.
		TRUE	Data is received by selected slave.
bExecute	BOOL	Data acceptance	
		TRUE	For the master: The pending data is accepted and the read/write access is executed.
			For the slave: The @sel data received by the master are provided via the outputs <i>wAuxIn1...4</i> of this function block.

Input	Data type	Information/possible settings
bStop	BOOL	Stop data transfer TRUE The axis bus changes to the "Stopped" state. <ul style="list-style-type: none"> The slaves neither accept any data nor send any data anymore. The master continues to send the line data. The bit 2 ("NodeStopped") in C02442/1 serves to set whether the last received data remain active or the decoupling values are set. ▶ Configuring exception handling of the received data

Outputs

Output	Data type	Value/meaning
wAuxIn1/wAuxIn2	WORD	Received data - word 1 and word 2
dnAuxIn12	DINT	Received data - word 1 and word 2 as double word
wAuxIn3/wAuxIn4	WORD	Received data - word 3 and word 4
dnAuxIn34	DINT	Received data - word 3 and word 4 as double word
wSlaveNo	WORD	Display which slave has sent its data. <ul style="list-style-type: none"> Output only relevant for master.
bDone	BOOL	Status signal "Data transfer completed" FALSE The master has sent a new read request to a slave. TRUE Data has been received correctly.
bFail	BOOL	Status signal "Fault" TRUE Data has not been received correctly (e.g. bus error). ▶ Axis bus data error monitoring

Related topics:

▶ [Configuring exception handling of the received data](#) (□ 844)

14.3

IO axis bus

**Stop!**

The IO axis bus of the 8400 TopLine controller is not compatible to the state bus of the 9300/9400 device series due to different voltage levels!

In order to use the IO axis bus, first decide whether the IO axis bus is to be used for transferring controller errors in the network ("release cord" principle) or as a pure open-collector IO function. The required function of the IO axis bus must then be set for all nodes in [C02440/1](#).

- "Master/slave" function ("release cord" principle)
 - In this setting, the IO axis bus only knows the two statuses "OK" and "Error".
 - Each node connected to the IO axis bus can set the IO axis bus into the "Error" status.
 - In the "Error" status, all nodes start their adjustable response, e.g. a synchronised braking of the drive system or the master only brakes the network to standstill.
 - The "Error" status can only be reset by the node defined as "master".
 - The internal time base of the controllers can be synchronised via the IO axis bus.
- "IO" function
 - With this setting, the IO axis bus is used as a pure IO transmission medium.
 - Each node connected to the IO axis bus can transmit a TRUE signal to all nodes.

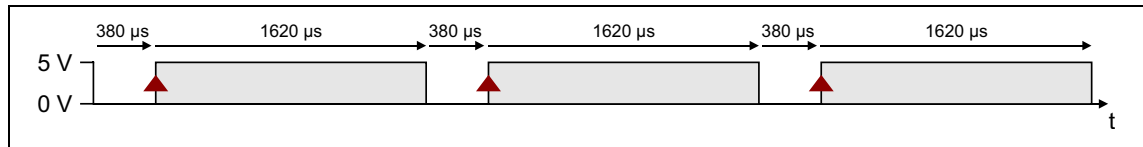
Short overview of the relevant parameters:

Parameter	Info	Lenze setting	
		Value	Unit
C00591/2	Resp. to axis bus IO error <ul style="list-style-type: none"> • From version 12.00.00 	1: Fault	
C01120	Sync signal source	0: Off	
C02440/1	Axis bus IO function	0: Off	
C02444/1	Axis bus settings (bit coded) <ul style="list-style-type: none"> • From version 12.00.00 • Bit 0 serves to reconfigure the LS AxisBusIO.bSetFail_DigOut input from level-sensitive to edge-sensitive. 	0x0000	

14.3.1 "Master/slave" function

With this setting, the IO axis bus can be used as "release cord", i.e. each node can set all other nodes into an error status.

One IO axis bus node takes over the master role. The master's task is to output a synchronisation cycle to the IO axis bus to which the slaves can orient themselves:

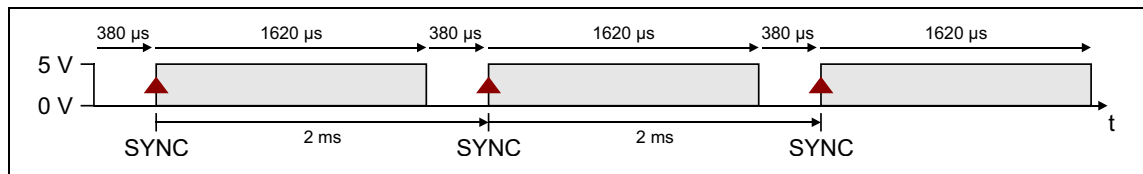


[14-4] IO axis bus: Synchronisation cycle from the master (error-free status)

The controller is configured as master or slave in [C02440/1](#) or by selecting "1: Master" or "2: Slave".

Synchronisation of the internal time base

The internal time base of the slaves can be synchronised via the IO axis bus. The slaves orient themselves to the synchronisation cycle output by the master:



[14-5] Synchronisation cycle

- In order that the IO axis bus is used as synchronisation source, all slaves must be set to "AxisBusIO" in [C01120](#).
- The internal time base is synchronised based on the HIGH edge in a 2-ms cycle (see illustration above).
- Internal timing and trimming of the phase position are set automatically.
- Basically, only one source is allowed to synchronise the internal time base. If "AxisBusIO" is selected, this is the IO axis bus master.



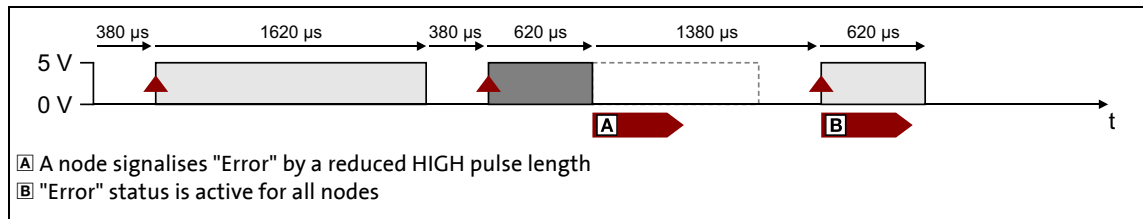
More information on this subject can be found in the following main chapter ["Synchronisation of the internal time base"](#). (857)

Error-free status

In the error-free status, all nodes are error-active, i.e. each node can set the IO axis bus into the "Error" status.

Error status

By setting the [LS AxisBusIO.bSetFail_DigOut](#) input to TRUE, each node can set the IO axis bus into the "Error" status. The node signals this by reducing the HIGH pulse length to 620 µs:



[14-6] Synchronisation cycle (error status)

All other nodes detect the "error status" due to the changed pulse length which has the following effect:

- The [LS AxisBusIO.bFail_DigIn](#) output is set to TRUE. This digital signal can be used for any application within the function block interconnection.
- From version 12.00.00:
 - The error response set in [C00591/2](#) is activated (Lenze setting: "Fault").
 - The error message "[Ab02: Axis bus IO error](#)" is entered into the logbook.
- The nodes are now error-passive, i.e. they cannot signalise any further errors in order that the HIGH edge for synchronisation can be detected after 2 ms.

Reset "error" status



Note!

The "error" status can only be reset by the master!

A FALSE/TRUE edge at the [LS AxisBusIO.bResetFail](#) input (for the master) serves to reset the "error" status again. The master signals this by providing a LOW pulse for 3 ms.

All other nodes detect the error reset due to this signal, which has the following effect:

- The [LS AxisBusIO.bFail_DigIn](#) output is reset to FALSE.
- After a delay time of 2 ms, the [LS AxisBusIO.bResetFailIn](#) output is set for 3 ms to TRUE. This digital signal can be used within the function block interconnection to e.g. reset errors.

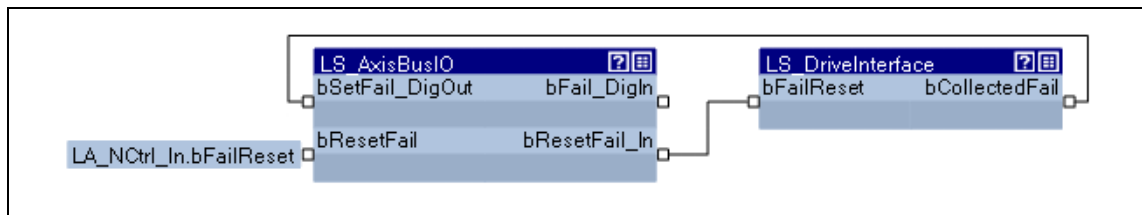
Application notes

In the event of an error in a network, a slave drive should never trigger the "Fault error response as this causes the pulse inhibit. This deactivates the coupling to the master and hence the network.

Possible solution:

1. Reconfigure the "Fault" error response to "Warning" in the slave axes.
2. Use the "master/slave" function ("release cord") to report errors and warnings to the master.
The master can then initiate the respective response for the entire network.

In the following interconnection example, the slave drive uses the *bCollectedFail* group error output of the SB [LS_DriveInterface](#) for "pulling the release cord". Non-relevant inputs/outputs of the SB [LS_DriveInterface](#) are hidden for an easier presentation.



[14-7] Configuration for "master/slave" function ("release cord")

In order that this mechanism works, the following parameter setting is additionally required for the slave drive:

1. Go to [C00148](#) and set bit 6 to "1" in order that warnings are also provided via the *bCollectedFail* group error output of the SB [LS_DriveInterface](#).
2. Go to [C02444/1](#) and set bit 0 to "1" in order that the *bSetFail_DigOut* input is edge-sensitive instead of level-sensitive. Otherwise, the error set input is "latched" and the slave drive does not respond anymore to an error reset by the master.

14.3.2 "IO" function

With this setting, the IO axis bus is used as a pure IO transmission medium, just like it the case for the 9300 and 9400 device series.

The "IO" function is activated in [C02440/1](#) by selecting "3: IO".

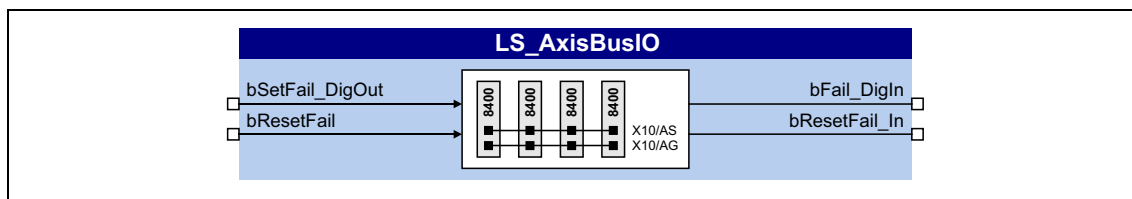


Note!

- "IO" function and [Data transfer axis bus](#) are mutually exclusive since with activated "IO" function, a synchronisation of the internal time base is not possible (which is required for a "safe" data transfer).
 - The "IO" function must be set for all IO axis bus nodes.
 - Triggering an error message with this function is only possible by function block interconnection.
 - Resetting an error message is not possible with this function.
-
- By setting the [LS_AxisBusIO.bSetFail_DigOut](#) input to TRUE, the IO axis bus is set to the dominant level and for all nodes, the [LS_AxisBusIO.bFail_DigIn](#) output is set to TRUE.
 - The [LS_AxisBusIO.bResetFail](#) input has no function.
 - The [LS_AxisBusIO.bResetFail_In](#) output is always FALSE.

14.3.3 Internal interfaces | System block "LS_AxisBusIO"

The **LS_AxisBusIO** system block maps the IO axis bus in the FB Editor:



Inputs

Identifier	Data type	Information/possible settings	
bSetFail_DigOut	BOOL	Set IO axis bus into the "error" status / IO data exchange	
		TRUE or FALSE → TRUE	For all IO axis bus nodes, the <i>bFail_DigIn</i> output is set to TRUE. • From version 12.00.00 onwards, bit 0 in C02444/1 can be used to reconfigure the <i>bSetFail_DigOut</i> input from level-sensitive to edge-sensitive.
bResetFail	BOOL	Reset "error" status • Only possible with "Master/slave" function via the IO axis bus master.	
		FALSE → TRUE	For all IO axis bus nodes, the <i>bFail_DigIn</i> output is reset to FALSE. After a delay time of 2 ms, the <i>bResetFail_In</i> output is set to TRUE for 3 ms for error reset.

Outputs

Identifier	Data type	Value/meaning	
bFail_DigIn	BOOL	With "master/slave" function: "Error" status With "IO" function: Data exchange	
		TRUE	An IO axis bus nodes has set the <i>bSetFail_Digout</i> input to TRUE.
bResetFail_In	BOOL	"Error" status has been reset • With "IO" function, this output is always FALSE.	
		TRUE	The IO axis bus master has reset the error message. This status is only pending for 3 ms.

15 Synchronisation of the internal time base

In a drive system, synchronising the internal time bases of all controllers involved makes sense because cyclic process data should be processed synchronously in all drives.

- One of the following signal sources can be used for automatic synchronisation of the internal time base of the controller:
 - CAN bus ("CAN on board") → [sync telegram](#)
 - Axis bus ("AxisBusIO") → [master/slave function](#)
 - MCI → sync signal of a plugged-in communication module (EtherCAT, PROFINET or Powerlink)

Short overview of the parameters for the synchronisation of the internal time base:

Parameter	Info	Lenze setting	
		Value	Unit
C00370/1	CAN Sync instant of transmission	-	µs
C00370/2	Sync instant of reception	-	µs
C01120	Sync signal source	Off	
C01121	Sync cycle time setpoint	1000	µs
C01122	Sync phase position	0	µs
C01123	Sync window	100	µs
C01124	Sync correction width	320	ns
Highlighted in grey = display parameter			

Sync signal source

The synchronisation signal source can be selected in [C01120](#). As a general rule, only one source can be used to synchronise the internal time base.

Sync cycle time setpoint

Time after which the internal phase-locking loop (PLL) anticipates the synchronisation signals. The time must be set in [C01121](#) according to the cycle of the synchronisation source selected in [C01120](#).



Note!

- Only integer multiples of 1000 µs can be set in [C01121](#).
- Intelligent communication modules usually define the cycle time setpoint derived from the bus cycle. In this case, a manual change is not possible.
- Even in case of a synchronisation via axis bus, a setting of the cycle time and the phase position is not required/possible and is executed automatically.

Example: For the CAN bus, 2 ms has been selected as interval between two synchronisation signals. If the CAN bus is to be used as synchronisation source, a cycle time setpoint of 2000 µs must be selected in [C01121](#).

Sync phase position

The phase position determines the zero-time of the internal system cycle with regard to the synchronisation signal (bus cycle). Since PDO processing is an inherent part of the system part of the application, the instant of acceptance of the PDOs is postponed as well by a changed phase position.

- If "0" is set, the internal system cycle starts at the same time as the synchronisation signal.
- If a value > 0 is set, the internal system cycle starts by the set time earlier (the phase position has a negative effect) than the synchronisation signal.
- Intelligent communication modules define the optimal time with activated synchronisation by themselves. In this case, a manual change is not possible.
- For determining [C01122](#), the point in time where all bus nodes have valid PDOs is decisive.

Example: If the phase position is set to 550 µs, the system part of the application starts 550 µs before the arrival of the synchronisation signal.

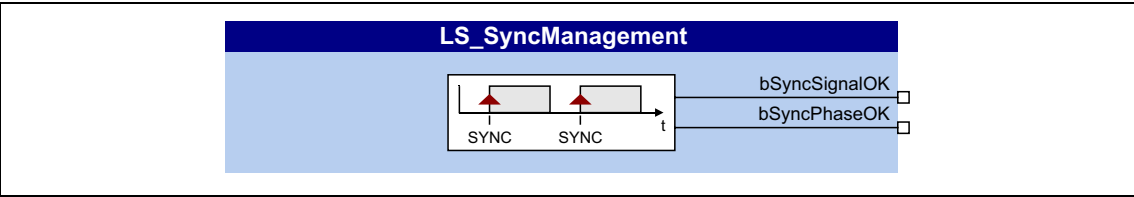
Sync correction width

If the cycle times of the synchronisation signal and the phase-locking loop (PLL) are different, the setting in [C01124](#) defines the correction increments for the phase-locking loop.

- The recommended reset time for the CAN bus as synchronisation source in case of occurring deviations is 320 ns (Lenze setting).
- If synchronisation is not reached, select a higher correction width.
- The optimum setting depends on quartz precision and must be determined empirically if required.

15.1 Internal interfaces | System block "LS_SyncManagement"

The SB **LS_SyncManagement** provides status information for synchronising the internal time base:



Outputs

Identifier	Data type	Value/meaning	
bSyncSignalOK	BOOL	TRUE	Sync signal OK
bSyncPhaseOK	BOOL	TRUE	Sync phase position OK

16 Parameter change-over

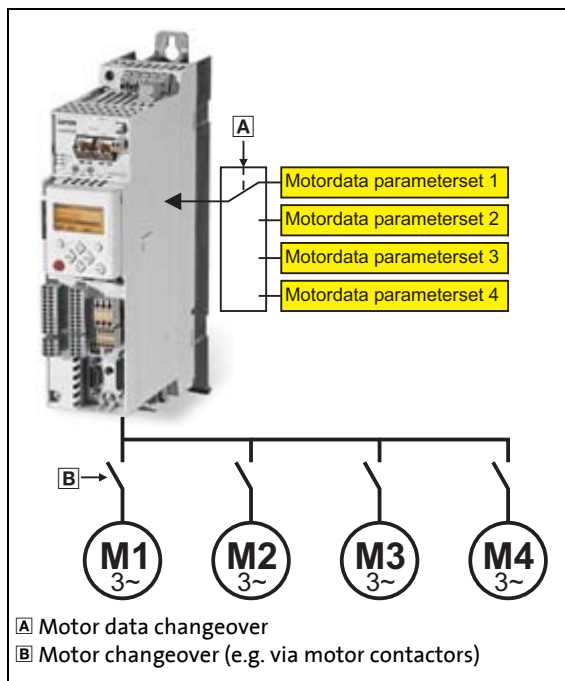
For up to 32 freely selectable parameters, this basic function provides a change-over between four sets with different parameter values.

The parameter list is created in the same way as the user menu is composed, namely by means of parameterisation. In the »Engineer«, a user-friendly parameterisation dialog with import and export functions is available for this purpose.

Motor data changeover

From version 12.00.00, an optional changeover between four parameter sets with different motor and control settings is supported in addition.

The optional motor data changeover is provided for applications/machines which have multiple axes controlled successively but which do not require the simultaneous operation of multiple motors. In this case, the very same controller can control the motors successively. Advantages of this solution: Fewer components (controllers) and hence less energy consumption.



Principle:

- The motor which is being controlled at the moment is connected to the controller via motor contactors. (The contactor system can e.g. be controlled via the digital outputs of the controller.)
- At the same time, the motor data changeover serves to activate the motor and control settings suitable for the motor in the controller.

Note:

The motor data changeover is carried out within 2 ms and hence within the opening and closing times of most motor contactors.

[16-1] Principle of the selective control of multiple motors using one controller

16.1 Configuring parameter change-over via the »Engineer« parameterisation dialog



Proceed as follows to open the dialog for parameterising the parameter change-over:

1. »Engineer« Go to the *Project* view and select the 8400 TopLine controller.
2. Select the **Application parameters** tab from the *Workspace*.
3. Go to the *Overview* dialog level and click the "Basic functions" button.
4. Go to the *Overview* → *Basic functions* dialog box and click the **Parameter change-over** button.

Application Parameters

Overview -> Basic Functions -> WriteParamList

Writing to parameter list: Activate
 Not connected

Writing to parameter list: Select value set - 1
 Not connected

Writing to parameter list: Select value set - 2
 Not connected

Selected value

Execute Mode
 0: By Execute

Definable parameter list
 ON

Motor data parameter list
 OFF

Error status
 0

Error line
 0

Copy values

Line	Code	Name	Unit	Active value	Value 1	Value 2	Value 3	Value 4
01								
02								
03								
04								
05								
06								
07								
08								
09								
10								
11								

Configure... Import... Export...



Note!

The "parameter change-over" basic function is always processed, even if the corresponding [LS WriteParamList](#) system block has been removed from the interconnection by the function block editor.

If you do not require this basic function anymore, delete the composed parameter list in order that no unwanted parameter write operations take place.

16.1.1 Configuring the parameter list(s)

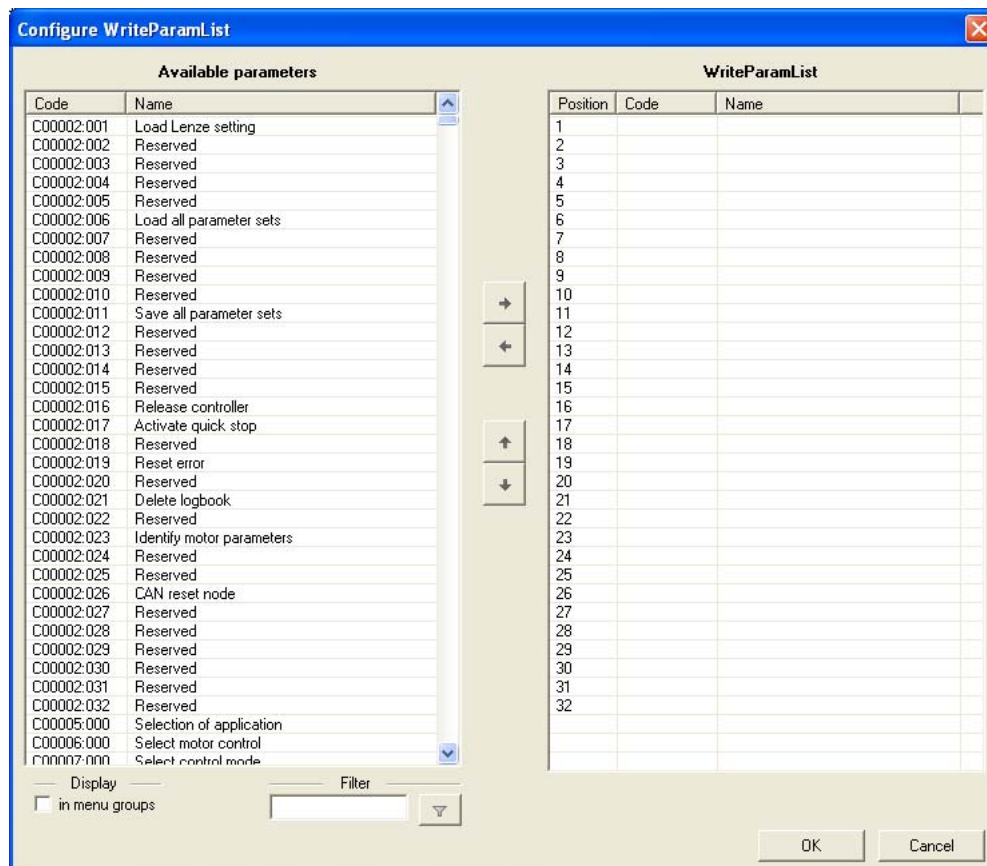
Configuring the definable parameter list


In the Lenze setting, the definable parameter list does not yet contain any parameters.






How to configure the definable parameter list:


1. Click the **Adapt...** button.
 - The dialog box entitled *Configure WriteParamList* is shown:



- On the left-hand side, all the parameters of the drive controller with write and read access are shown in the list entitled **Available parameters**.
 - If the option **In menu groups** is activated, all parameters are shown assigned to their functions.
 - By clicking on the  button in the **Filter** area, you can shorten the list of available parameters. If, for example, you enter the text "ain1" and then click on the button, only those parameters whose designation contains this text are shown for selection.
2. Highlight the parameter/parameters in the **Available parameters** list that is/are to be added to the *WriteParamList*.
 - Here, you can use the <Ctrl> key and the <Shift> key for multiple selection, as in the case of general Windows functions.

3. Click on the  button in order to add the highlighted parameters to the *WriteParamList* on the right-hand side.
 - With the  and  buttons, you can alter the sequence of parameters in the *WriteParamList*.

To remove parameters from the *WriteParamList*, proceed as follows:

 - Highlight the parameter/parameters in the **WriteParamList** that is/are to be removed from the *WriteParamList*.
 - Click on the  button to remove the highlighted parameters from the *WriteParamList*.
4. Click on the **OK** button to accept the configuration and close the dialog box.
 - You can call the configuration dialog again at any time in order to change or expand the *WriteParamList* retrospectively.

Changing the values of the definable parameter list


After the compilation of the definable parameter list, the values in the columns **1st value ... 4th value** first correspond to the Lenze setting of the respective parameter.

- Just click one of the input fields in these columns to change the displayed value.
- If you place the cursor in an input field, the permitted value range for the corresponding parameter is shown under the table.

Changing the values of the motor data parameter list

Click the **Motor data parameter list** register to put it in the foreground:

Definable parameter list		Motor data parameter list						Copy values	
Line	Code	Name	Unit	Active value	Value 1	Value 2	Value 3	Value 4	
01	C0006:000	Motor control		6	6	6	6	6	
02	C0015:000	VFC: V/f base frequency	Hz	50	50	50	50	50	
03	C0016:000	VFC: V/min boost	%	1,6	1,6	1,6	1,6	1,6	
04	C0018:000	Switching frequency		2	2	2	2	2	
05	C0019:000	Auto-DCB: Threshold	rpm	3	3	3	3	3	
06	C0021:000	Slip compensation	%	2,67	2,67	2,67	2,67	2,67	
07	C0022:000	I _{max} in motor mode	A	47	47	47	47	47	
08	C0023:000	I _{max} in generator mode	%	100	100	100	100	100	

 Import... Export...

- Unlike the "definable" parameter list, the motor data parameter list has a fixed assignment to the motor and control parameters.
 - A list of the switchable motor and control parameters is provided in chapter "[Configuring the motor data parameter list by means of parameterisation](#)". (867)
- The preset values are changed in the same way as the definable parameter list.

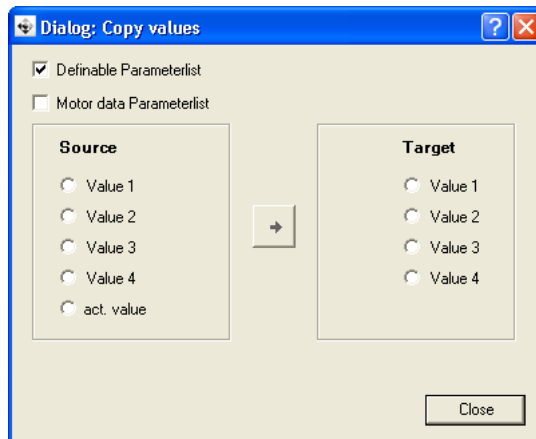
Copying values


All the settings of a value set can be copied to another value set.



To copy values, proceed as follows:

1. Click on the **Copy values** button.
 - The *Copy values* dialog box is displayed:



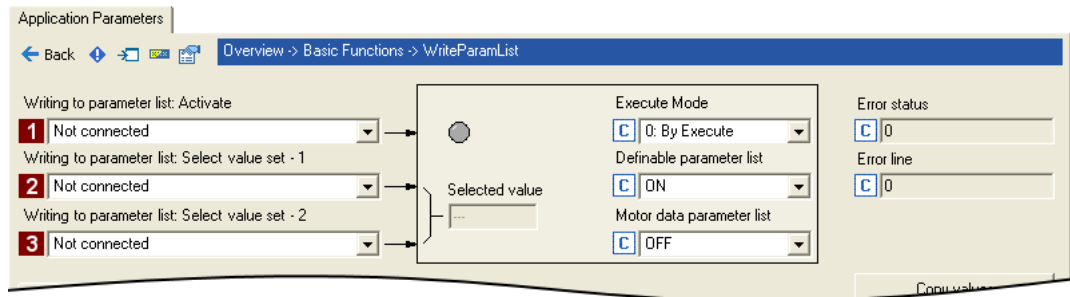
2. Define the parameter list to be copied via the two upper checkboxes.
3. Select **Source** and **Target**.
4. Click on  button in order to copy the values from **Source** to **target**.

Importing/exporting the list

For cross-device reuse of the configured *WriteParamList*, you can click on the **Export** and **Import** buttons to save the parameter selection as an *.epc file and then to re-import the saved *.epc file into another drive controller 8400.

16.1.2 Configuring control inputs

The three control inputs for parameter change-over can be configured via the following parameters:

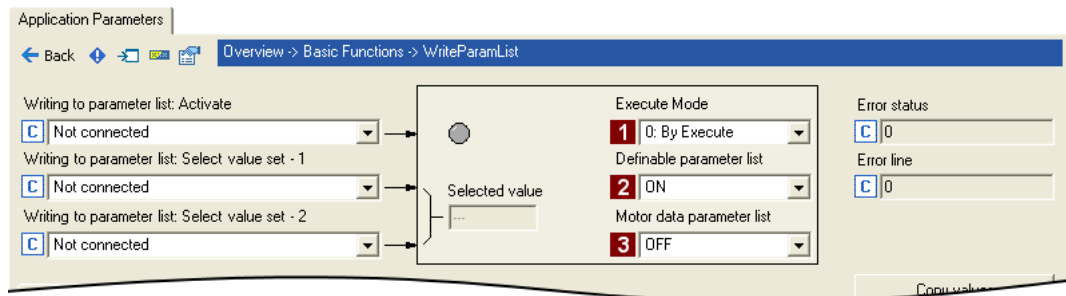


Parameter	Lenze setting	Info
1 Activate writing (C00621/123)	0: Not connected	Selection of the signal source that activates writing to the parameter list (for Execute Mode = "0: by Execute").
2 Selection value set - 1 (C00621/124)	0: Not connected	Selection of the two signal sources for the binary-coded selection of the value set 1 ... 4 to be used (see following truth table).
3 Selection value set - 2 (C00621/125)	0: Not connected	

Truth table for the selection of the value set to be used:

Selection value set - 1	Selection value set - 2	Value set used
FALSE	FALSE	Value set 1
TRUE	FALSE	Value set 2
FALSE	TRUE	Value set 3
TRUE	TRUE	Value set 4

16.1.3 Functional settings



Parameter	Lenze setting	Info
1 Execute Mode (C01082)	0: by Execute	For writing the parameter list, two modes are available: <ul style="list-style-type: none"> • 0: by Execute (Lenze setting) The writing of the parameter list is activated by a FALSE/TRUE edge at the <i>bExecute</i> control input. • 1: by Input Select The parameter list is written when the selection inputs <i>bSelectWriteValue_1</i> and <i>bSelectWriteValue_2</i> are changed and once during the initialisation of the controller. Note: If the execute mode changes from "0: by Execute" to "1: by Input Select", the parameter list selected by the selection inputs is written once. In the execute mode "1: by Input Select", the parameter list then is only written again when a change occurs on the selection inputs .
2 Definable parameter list (C02200/1)	1: On	Switch on/off parameter changeover for the definable parameter list.
3 Motor data parameter list (C02200/2)	0: Off	Switch on/off parameter changeover for the motor data parameter list.

16.1.4 Error indication

With every run through the main program, one parameter of the definable parameter list is written until the parameter list has been executed completely. If an error occurs, [C01083](#) displays an error status and [C01084](#) displays the number of the list entry causing the error (in connection with the selected value set).

- If several errors occur at the same time, only the first incorrect list entry will be displayed. Hence, after elimination of the displayed error and another activation, more errors may be displayed.
- The parameter list will always be processed from beginning to end, even if errors occur in the meantime.

16.2 Configuring the definable parameter list by means of parameterisation

The following application example shows the necessary procedure for configuring the list without using the »Engineer« parameterisation dialog.

Task:

The LS_WriteParamList SB is to be used to write to parameters [C00012](#), [C00026/1](#) and [C00027/1](#).

Compiling the parameter list

In [C01085/1 ... n](#), specify the above-named parameters in the <Code>,<Subcode> format:

- [C01085/1](#) = 12.000
- [C01085/2](#) = 26.001
- [C01085/3](#) = 27.001
- [C01085/4 ... n](#) = 0.000 (no parameter)



Note!

Gaps in the parameter list (setting = 0.000) are permissible and are skipped in the process.

Invalid parameter entries are not accepted when being entered.

Entering values for the parameters (value set 1)

In [C01086/1 ... n](#), specify the values to be used to describe the selected parameters. The values are entered according to the scaling format/scaling factor of the respective parameter.

- [C01086/1](#) = <value> for list entry 1 (in our example: for parameter [C00012](#))
- [C01086/2](#) = <value> for list entry 2 (in our example: for parameter [C00026/1](#))
- [C01086/3](#) = <value> for list entry 3 (in our example: for parameter [C00027/1](#))

These values are used in the writing process if the two *bSelectWriteValue_1* and *bSelectWriteValue_2* inputs are not assigned or both set to FALSE.

Entering other values for the parameters (value sets 2 ... 4)

If required, up to three other sets can be set in the same way in [C01087/1 ... n](#) to [C01089/1 ... n](#) which can optionally be written to the parameters. The decision as to which value set is finally used is dependent upon the assignment of the two *bSelectWriteValue_1* and *bSelectWriteValue_2* inputs:

16.3

Configuring the motor data parameter list by means of parameterisation

The setting of the values for value sets 1 ... 4 of the motor data parameter list can also be carried out directly via the codes from code [C02210](#) (see following table; columns 1st value ... 4th value).

- Unlike the "definable" parameter list, the motor data parameter list has a fixed assignment to the motor and control parameters.
- The preset values for value sets 1 ... 4 correspond to the Lenze setting of the respective motor or control parameter.
- The values are entered according to the scaling format / scaling factor of the respective motor or control parameter.

Code	Name	Lenze setting	1st value	2nd value	3rd value	4th value
C00006	Motor control	6	C02210/1	C02210/2	C02210/3	C02210/4
C00015	VFC: V/f base frequency	50.0 Hz	C02212/1	C02212/2	C02212/3	C02212/4
C00016	VFC: Vmin boost	1.60 %	C02213/1	C02213/2	C02213/3	C02213/4
C00018	Switching frequency	2	C02214/1	C02214/2	C02214/3	C02214/4
C00019	Auto-DCB: Threshold	3 rpm	C02215/1	C02215/2	C02215/3	C02215/4
C00021	Slip comp.	2.67 %	C02216/1	C02216/2	C02216/3	C02216/4
C00022	Imax in motor mode	47.00 A	C02217/1	C02217/2	C02217/3	C02217/4
C00023	Imax in generator mode	100.00 %	C02218/1	C02218/2	C02218/3	C02218/4
C00036	DC braking: Current	50.00 %	C02219/1	C02219/2	C02219/3	C02219/4
C00070/1	SLVC: Vp speed controller	15.00	C02220/1	C02220/2	C02220/3	C02220/4
C00070/2	SC: Vp speed controller	6.00	C02220/5	C02220/6	C02220/7	C02220/8
C00070/3	SLPSM: Vp speed controller	3.00	C02220/9	C02220/10	C02220/11	C02220/12
C00071/1	SLVC: Ti speed controller	100.0 ms	C02221/1	C02221/2	C02221/3	C02221/4
C00071/2	SC: Ti speed controller	50.0 ms	C02221/5	C02221/6	C02221/7	C02221/8
C00071/3	SLPSM: Ti speed controller	100.0 ms	C02221/9	C02221/10	C02221/11	C02221/12
C00072	SC: Tdn speed controller	0.00 ms	C02222/1	C02222/2	C02222/3	C02222/4
C00073/1	VFC: Vp Imax controller	0.25	C02223/1	C02223/2	C02223/3	C02223/4
C00073/2	SLVC: Vp torque controller	1.25	C02223/5	C02223/6	C02223/7	C02223/8
C00074/1	VFC: Ti Imax controller	65 ms	C02224/1	C02224/2	C02224/3	C02224/4
C00074/2	SLVC: Ti torque controller	30 ms	C02224/5	C02224/6	C02224/7	C02224/8
C00075	Vp current controller	7.00 V/A	C02225/1	C02225/2	C02225/3	C02225/4
C00076	Ti current controller	10.61 ms	C02226/1	C02226/2	C02226/3	C02226/4
C00077	SC: Vp field controller	12.80	C02227/1	C02227/2	C02227/3	C02227/4
C00078	SC: Tn field controller	256.0 ms	C02228/1	C02228/2	C02228/3	C02228/4
C00079/1	SC: Current controller - feedforward control	0	C02229/1	C02229/2	C02229/3	C02229/4
C00079/2	SC: adapt. field weak. controller	1	C02229/5	C02229/6	C02229/7	C02229/8
C00079/3	SC: n-Ctrl Anti-Wind-Up	0	C02229/9	C02229/10	C02229/11	C02229/12
C00080	Override point of field weakening	0 Hz	C02230/1	C02230/2	C02230/3	C02230/4
C00081	Rated motor power	11.00 kW	C02231/1	C02231/2	C02231/3	C02231/4
C00082	Motor rotor resistance	276 mOhm	C02232/1	C02232/2	C02232/3	C02232/4
C00084	Motor stator resistance	330 mOhm	C02233/1	C02233/2	C02233/3	C02233/4
C00085	Motor stator leakage inductance	3.50 mH	C02234/1	C02234/2	C02234/3	C02234/4
C00087	Rated motor speed	1460 rpm	C02236/1	C02236/2	C02236/3	C02236/4
C00088	Rated motor current	21.00 A	C02237/1	C02237/2	C02237/3	C02237/4
C00089	Rated motor frequency	50 Hz	C02238/1	C02238/2	C02238/3	C02238/4
C00090	Rated motor voltage	400 V	C02239/1	C02239/2	C02239/3	C02239/4
C00091	Motor cosine phi	0.85	C02240/1	C02240/2	C02240/3	C02240/4
C00092	Motor magnetising inductance	81.0 mH	C02241/1	C02241/2	C02241/3	C02241/4
C00095	Motor magnetising current	8.50 A	C02242/1	C02242/2	C02242/3	C02242/4
C00106	Auto-DCB: Hold time	0.500 s	C02244/1	C02244/2	C02244/3	C02244/4
C00107	DC braking: Hold time	999.000 s	C02245/1	C02245/2	C02245/3	C02245/4

Code	Name	Lenze setting	1st value	2nd value	3rd value	4th value
C00120	Setting of motor overload (I ^{xt})	100.00 %	C02246/1	C02246/2	C02246/3	C02246/4
C00234	Oscillation damping influence	5.00 %	C02249/1	C02249/2	C02249/3	C02249/4
C00235	Oscillation damping filter time	32 ms	C02250/1	C02250/2	C02250/3	C02250/4
C00236	Oscillation damping field weakening	14	C02251/1	C02251/2	C02251/3	C02251/4
C00254	Kp position controller	5.00 1/s	C02252/1	C02252/2	C02252/3	C02252/4
C00273	Motor moment of inertia	0.00 kg cm ²	C02256/1	C02256/2	C02256/3	C02256/4
C00495	Speed sensor selection	0	C02260/1	C02260/2	C02260/3	C02260/4
C00576	SC: Field feedforward control	200 %	C02261/1	C02261/2	C02261/3	C02261/4
C00577	SC: Vp field weakening controller	0.0010	C02262/1	C02262/2	C02262/3	C02262/4
C00578	SC: Tn field weakening controller	20.0 ms	C02263/1	C02263/2	C02263/3	C02263/4
C00653/1	Sensibility - Setpoint feedforward control	0	C02264/1	C02264/2	C02264/3	C02264/4
C00905	Motor phase direction of rotation	0	C02272/1	C02272/2	C02272/3	C02272/4
C00909/1	Max. pos. speed	120.00 %	C02273/1	C02273/2	C02273/3	C02273/4
C00909/2	Max. neg. speed	120.00 %	C02273/5	C02273/6	C02273/7	C02273/8
C00910/1	Max. pos. output frequency	1000 Hz	C02274/1	C02274/2	C02274/3	C02274/4
C00910/2	Max. neg. output frequency	1000 Hz	C02274/5	C02274/6	C02274/7	C02274/8
C00915	Motor cable length	5.0 m	C02275/1	C02275/2	C02275/3	C02275/4
C00916	Motor cable cross-section	6.00 mm ²	C02276/1	C02276/2	C02276/3	C02276/4
C00938	PSM: Maximum motor current field weakening	30.00 %	C02278/1	C02278/2	C02278/3	C02278/4
C00939	Ultimate motor current	3000.0 A	C02279/1	C02279/2	C02279/3	C02279/4
C00965	Max. motor speed	60000 rpm	C02280/1	C02280/2	C02280/3	C02280/4
C00966	VFC: Time const. slip comp.	100 ms	C02281/1	C02281/2	C02281/3	C02281/4
C00971/1	VFC: Controller limitation V/f +encoder	10.00 Hz	C02284/1	C02284/2	C02284/3	C02284/4
C00971/2	VFC: Slip limitation V/f +encoder	100.00 Hz	C02284/5	C02284/6	C02284/7	C02284/8
C00972	VFC: Vp V/f +encoder	0.100 Hz/Hz	C02285/1	C02285/2	C02285/3	C02285/4
C00973	VFC: Ti V/f +encoder	100.0 ms	C02286/1	C02286/2	C02286/3	C02286/4
C00975	VFC-ECO: Vp CosPhi controller	0.500 Hz/Hz	C02287/1	C02287/2	C02287/3	C02287/4
C00976	VFC-ECO: Ti CosPhi controller	200.0 ms	C02288/1	C02288/2	C02288/3	C02288/4
C00977	VFC-ECO: Minimum voltage V/f	20.00 %	C02289/1	C02289/2	C02289/3	C02289/4
C00982	VFC-ECO: Voltage reduction ramp	0.8 s	C02290/1	C02290/2	C02290/3	C02290/4
C00985	SLVC: Field current controller gain	0.50 %	C02291/1	C02291/2	C02291/3	C02291/4
C00986	SLVC: Cross current controller gain	0.00 %	C02292/1	C02292/2	C02292/3	C02292/4
C00987	Inverter motor brake: nAdd	80 rpm	C02293/1	C02293/2	C02293/3	C02293/4
C00988	Inverter motor brake: PT1 filter time	0.0 ms	C02294/1	C02294/2	C02294/3	C02294/4
C00990	Flying restart fct.: Activate	0	C02295/1	C02295/2	C02295/3	C02295/4
C00991	Flying restart fct.: Process	2	C02296/1	C02296/2	C02296/3	C02296/4
C00992	Flying restart fct.: Start frequency	10 Hz	C02297/1	C02297/2	C02297/3	C02297/4
C00993	Flying restart fct.: Int. time	300.0 ms	C02298/1	C02298/2	C02298/3	C02298/4
C00994	Flying restart fct.: Current	25.00 %	C02299/1	C02299/2	C02299/3	C02299/4
C00995/1	SLPSM: Controlled accelerating current	100.00 %	C02300/1	C02300/2	C02300/3	C02300/4
C00995/2	SLPSM: Controlled standstill current	20.00 %	C02300/5	C02300/6	C02300/7	C02300/8
C00996/1	SLPSM: Switching speed, closed-loop control	13.00 %	C02301/1	C02301/2	C02301/3	C02301/4
C00996/2	SLPSM: Switching speed, open-loop control	8.00 %	C02301/5	C02301/6	C02301/7	C02301/8
C00997	SLPSM: Filter cutoff frequency	5.00 %	C02302/1	C02302/2	C02302/3	C02302/4
C00998/1	SLPSM: Filter time rotor position	3.0 ms	C02303/1	C02303/2	C02303/3	C02303/4
C00998/2	SLPSM: Filter time actual speed value	5.0 ms	C02303/5	C02303/6	C02303/7	C02303/8
C00999	SLPSM: PLL gain	400 %	C02304/1	C02304/2	C02304/3	C02304/4
C01001/1	Manual entry of motor type	0	C02315/1	C02315/2	C02315/3	C02315/4
C02853/1	PSM: Lss saturation characteristic	100 %	C02305/1	C02305/2	C02305/3	C02305/4
C02853/2	PSM: Lss saturation characteristic	100 %	C02305/5	C02305/6	C02305/7	C02305/8
C02853/3	PSM: Lss saturation characteristic	100 %	C02305/9	C02305/10	C02305/11	C02305/12
C02853/4	PSM: Lss saturation characteristic	100 %	C02305/13	C02305/14	C02305/15	C02305/16

Code	Name	Lenze setting		1st value	2nd value	3rd value	4th value
C02853/5	PSM: Lss saturation characteristic	100	%	C02305/17	C02305/18	C02305/19	C02305/20
C02853/6	PSM: Lss saturation characteristic	100	%	C02305/21	C02305/22	C02305/23	C02305/24
C02853/7	PSM: Lss saturation characteristic	100	%	C02305/25	C02305/26	C02305/27	C02305/28
C02853/8	PSM: Lss saturation characteristic	100	%	C02305/29	C02305/30	C02305/31	C02305/32
C02853/9	PSM: Lss saturation characteristic	100	%	C02305/33	C02305/34	C02305/35	C02305/36
C02853/10	PSM: Lss saturation characteristic	100	%	C02305/37	C02305/38	C02305/39	C02305/40
C02853/11	PSM: Lss saturation characteristic	100	%	C02305/41	C02305/42	C02305/43	C02305/44
C02853/12	PSM: Lss saturation characteristic	100	%	C02305/45	C02305/46	C02305/47	C02305/48
C02853/13	PSM: Lss saturation characteristic	100	%	C02305/49	C02305/50	C02305/51	C02305/52
C02853/14	PSM: Lss saturation characteristic	100	%	C02305/53	C02305/54	C02305/55	C02305/56
C02853/15	PSM: Lss saturation characteristic	100	%	C02305/57	C02305/58	C02305/59	C02305/60
C02853/16	PSM: Lss saturation characteristic	100	%	C02305/61	C02305/62	C02305/63	C02305/64
C02853/17	PSM: Lss saturation characteristic	100	%	C02305/65	C02305/66	C02305/67	C02305/68
C02855	PSM: I _{max} Lss saturation characteristic	3000.0	A	C02306/1	C02306/2	C02306/3	C02306/4
C02859	PSM: Activate Ppp saturation char.	0		C02307/1	C02307/2	C02307/3	C02307/4
C02872/1	PLI without motion: Adaptation of time duration	0		C02311/1	C02311/2	C02311/3	C02311/4
C02874/1	PLI without motion	0x0001		C02312/1	C02312/2	C02312/3	C02312/4
C02875/1	PLI without motion: Adaptation of ident angle	0	°	C02313/1	C02313/2	C02313/3	C02313/4

16.4 Internal interfaces | System block "LS_WriteParamList"

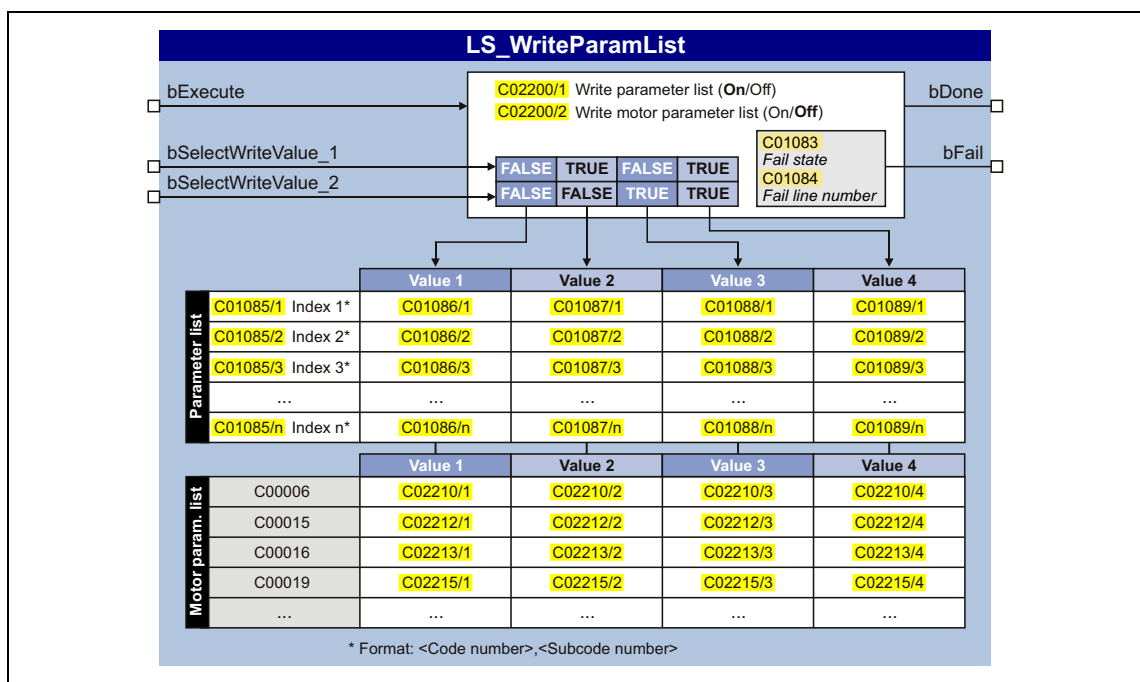
The **LS_WriteParamList** system block provides the internal interfaces for the basic "Parameter change-over" function.



Note!

The "parameter change-over" basic function is always processed, even if the **LS_WriteParamList** system block has been removed from the interconnection by the FB Editor.

If you do not require this basic function anymore, delete the composed parameter list in order that no unwanted parameter write operations take place.



Inputs

Identifier	Data type	Information/possible settings		
bExecute	BOOL	FALSE↗TRUE	For Execute Mode (C01082) = "0: by Execute": Activate writing of the parameter list	
bSelectWriteValue_1 bSelectWriteValue_2	BOOL	Binary coded selection of the value set 1 ... 4 to be used.		
		<i>bSelectWriteValue_1</i>	<i>bSelectWriteValue_2</i>	
		FALSE	FALSE	Value set 1
		TRUE	FALSE	Value set 2
		FALSE	TRUE	Value set 3
		TRUE	TRUE	Value set 4

Outputs

Identifier	Data type	Value/meaning
bDone	BOOL	"Writing of the parameter list completed" status signal <ul style="list-style-type: none"> The output is automatically reset to FALSE if writing via <i>bExecute</i> is activated again.
		TRUE Writing of the parameter list successfully completed.
		FALSE The FALSE status can have the following meanings: <ol style="list-style-type: none"> 1. There is no active writing of the parameter list. 2. Writing of the parameter list has not been completed yet. 3. An error has occurred (if <i>bFail</i> = TRUE).
bFail	BOOL	"Error" status
		TRUE An error has occurred (group signal). <ul style="list-style-type: none"> See display parameter (C01083) for details.

17 Parameter reference

This chapter describes all parameters which can be used for parameterising and monitoring the controller.

Parameters which are only available in the controller from a certain software version onwards are marked with a corresponding note in the parameter description ("from version xx.xx.xx").

The parameter descriptions are based on software version V15.00.00



Tip!

For quick reference of a parameter with a certain name simply use the **index** of the online documentation. The index always contains the corresponding code in parentheses behind the name.

General information on parameter setting can be found in the chapter "[Introduction: Parameterising the controller](#)". (📖 28)

For general information on how to read and change parameters, please see the online documentation for the »Engineer«.

17.1 Structure of the parameter descriptions

Each parameter is described in the [Parameter list](#) in the form of a table which consists of the following three areas:

Table header

The table header contains the following general information:

- Parameter number (Cxxxxx)
- Parameter name (display text in the »Engineer« and keypad)
- [Data type](#)
- Parameter index in decimal and hexadecimal notation for access via a fieldbus (e.g. CAN system bus).



Tip!

The parameter index is calculated as follows:

- Index [dec] = 24575 - code
- Index [hex] = 0x5FFF - code

Example for code C00005:

- Index [dec] = 24575 - 5 = 24570
- Index [hex] = 0x5FFF - 0x{5} = 0x5FFA

Table contents

The table contains further general explanations & notes on the parameter and the possible settings, which are represented in different ways depending on the parameter type:

- [Parameters with read-only access](#)
- [Parameters with write access](#)

Table footer

The table footer contains the [Parameter attributes](#).

17.1.1 Data type

The following data types are available for parameters:

Data type	Meaning
INTEGER_16	16-bit value with sign
INTEGER_32	32-bit value with sign
UNSIGNED_8	8-bit value without sign
UNSIGNED_16	16-bit value without sign
UNSIGNED_32	32-bit value without sign
VISIBLE_STRING	String of characters of printable characters

17.1.2 Parameters with read-only access

Parameters for which the "write access" attribute has not been set can only be read and not be changed by the user.

Description structure

Parameter Name: Cxxxxx _____		Data type: _____ Index: _____
Description		
Display range (min. value unit max. value)		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

Representation in the »Engineer«

The »Engineer« displays these parameters with a grey background or, with an online connection, with a pale-yellow background:

	C...	S	Name	Value	Unit
	3	0	Status of last device command	Successful	

17.1.3 Parameters with write access

Only parameters with a check mark (☑) in front of the "write access" attribute can be changed by the user. The Lenze setting for these parameters is **printed in bold**.

- The settings can either be selected from a selection list or the values can be entered directly.
- Values outside the valid setting range are represented in red in the »Engineer«.

17.1.3.1 Parameters with setting range

Description structure

Parameter Name: Cxxxxx _____			Data type: _____ Index: _____	
Description				
Setting range (min. value unit max. value)			Lenze setting	
☑ Read access ☑ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT Scaling factor: 1				

Parameter setting in the »Engineer«

In the »Engineer«, parameters are set by entering the desired value into the input field:

	C... / S	Name	Value	Unit
11	0	Appl.: Reference speed	1500	rpm

17.1.3.2 Parameters with selection list

Description structure

Parameter Name: Cxxxxx _____			Data type: _____ Index: _____	
Description				
Selection list (Lenze setting printed in bold)				
1				
2				
3				
☑ Read access ☑ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT Scaling factor: 1				

Parameter setting in the »Engineer«

In the »Engineer«, a list field is used for parameter setting:

	C...	S	Name	Value	Unit
	173	0	Mains voltage	0: 3ph 400V / 1ph 230V	
				0: 3ph 400V / 1ph 230V	
				1: 3ph 440V / 1ph 230V	
				2: 3ph 480V / 1ph 230V	
				3: 3ph 500V / 1ph 230V	
				4: 3ph 400V / 1ph 115V	

17.1.3.3 Parameters with bit-coded setting

Description structure

Parameter Name: Cxxxxx _____		Data type: _____ Index: _____
Description		
Value is bit-coded:		
Bit 0		
...		
Bit 31		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

Parameter setting in the »Engineer«

The »Engineer« uses a dialog box for parameter setting in which the individual bits can be set or reset. Alternatively, the value can be entered as a decimal or hexadecimal value:

Bit	Comment
<input checked="" type="checkbox"/> 0	bOut1 inverted
<input checked="" type="checkbox"/> 1	bOut2 inverted
<input checked="" type="checkbox"/> 2	bOut3 inverted
<input checked="" type="checkbox"/> 3	bOut4 inverted
<input type="checkbox"/> 4	Reserved
<input type="checkbox"/> 5	Reserved
<input type="checkbox"/> 6	Reserved
<input type="checkbox"/> 7	Reserved

17.1.3.4 Parameters with subcodes

Description structure

Parameter Name: Cxxxxx _____		Data type: _____ Index: _____
Description		
Setting range (min. value unit max. value)		
Subcodes	Lenze setting	
Cxxxxx/1		
Cxxxxx/2		
Cxxxxx/3		
Cxxxxx/4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

Parameter setting in the »Engineer«

The »Engineer« parameter list displays each subcode individually. The parameters are set as described in the previous chapters.

	C...	S	Name	Value	Unit
	39	1	Fixed setpoint 1	40.00	%
	39	2	Fixed setpoint 2	60.00	%
	39	3	Fixed setpoint 3	80.00	%
	39	4	Fixed setpoint 4	0.00	%

17.1.4 Parameter attributes

The table footers contain the parameter attributes:

<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1

Attribute	Meaning
<input checked="" type="checkbox"/> Read access	Read access to parameter possible.
<input checked="" type="checkbox"/> Write access	Write access to parameter possible. • Please also observe the following attributes:
<input checked="" type="checkbox"/> CINH	Parameter value can only be changed when the controller is inhibited.
<input checked="" type="checkbox"/> PLC STOP	Parameter value can only be changed when the application is stopped.
<input checked="" type="checkbox"/> No transfer	Parameter is not transferred to controller when the command <u>Download parameter set</u> is executed.
<input checked="" type="checkbox"/> COM	Communication-relevant parameter • This parameter is relevant for parameter data transfer via the (CAN) system bus.
<input checked="" type="checkbox"/> MOT	Motor control parameters

Scaling factor

The "scaling factor" is important for parameter access via a bus system.

Signal type	Scaling factor	Resolution	Value range
Analog (scaled)	100	16 bits signed	± 199.99 %
Angular velocity	1	16 bits signed	± 32767 incr./ms
Position in [units]	10000	32 bits signed	± 214748.3647 [units]
Digital (BOOL)	1	8 bits unsigned	0 ≡ FALSE; 1 ≡ TRUE
Time	1000	16 bits unsigned	0 ... 999.000 s
Selection value	1	16 bits unsigned	0 ... 65535

Example 1: The value "654" of the parameter [C00028/1](#) (AIN1: input voltage) read via a bus system must be divided by the corresponding scaling factor "100" to obtain the actual display value "6.54 V".

$$\frac{\text{Read value (via bus system)}}{\text{Scaling factor}} = \text{Indicated value (Engineer)}$$

[17-1] Conversion formula for read access via bus system

Example 2: In order to set the parameter [C00012](#) (acceleration time main setpoint) to the value "123.45 %" via a bus system, the integer value "12345" must be transferred, i.e. the value to be set must be multiplied by the corresponding scaling factor "100".

$$\text{Value to be written (via bus system)} = \text{Value to be set} \cdot \text{Scaling factor}$$

[17-2] Conversion formula for write access via bus system

Character length

In case of parameters of "VISIBLE_STRING" data type, the character length is given in addition. This is also important for the parameter access via a bus system.

17.2 Parameter list

This chapter lists all parameters of the operating system in numerically ascending order.

**Note!**

The parameter descriptions are based on the software version V15.00.00.

C00001

Parameter Name: C00001 Keypad Userlevel		Data type: UNSIGNED 8 Index: 24574 _d = 5FFE _h
<p>From version 12.00.00 onwards, the extent of menus, submenus and codes shown in the keypad can be adapted by selecting the "userlevel".</p> <ul style="list-style-type: none"> When the userlevel has been changed, the menus of the keypad will be reconfigured according to the selected user level. Independently of the set userlevel, the parameters of the attached communication module will always be displayed completely. 		
Selection list		Info
10	Standard	Only the most important menus and codes are displayed on the keypad.
20	Expert	All menus and codes are displayed on the keypad.
30	Service	Only for servicing purposes (Lenze service).
Subcodes	Lenze setting	Info
C00001/1	10: Standard	Keypad UserLevel
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00002

Parameter Name: C00002 Device command		Data type: UNSIGNED 8 Index: 24573 _d = 5FFD _h
<p>Note:</p> <ul style="list-style-type: none"> Before switching off the supply voltage after a device command has been executed, check the successful execution of the device command via the status display in C00003! Before activating device commands by a master control, wait for the "Ready" signal of the controller. The device will reject a write process to C00002/x if the value is >1 and issue an error message. <p>► Drive control (DCTRL): Device commands</p>		
Selection list		
0	Off / ready	
1	On / start	
4	Action cancelled	
5	No access	
6	No access controller inhibit	
20	20% working	
40	40% working	
60	60% working	
80	80% working	

Parameter Name: C00002 Device command		Data type: UNSIGNED 8 Index: 24573 _d = 5FFD _h
Subcodes	Lenze setting	Info
C00002/1	0: Off / ready	Load Lenze setting <ul style="list-style-type: none"> • All parameters are reset to the Lenze setting. • Only possible when the controller is inhibited. ▶ Load Lenze setting
C00002/2	0: Off / ready	Reserved
C00002/3	0: Off / ready	Reserved
C00002/4	0: Off / ready	Reserved
C00002/5	0: Off / ready	Reserved
C00002/6	0: Off / ready	Load all parameter sets <ul style="list-style-type: none"> • All parameter sets are loaded by the memory module. • Only possible when the controller is inhibited. ▶ Load all parameter sets
C00002/7	0: Off / ready	Reserved
C00002/8	0: Off / ready	Reserved
C00002/9	0: Off / ready	Reserved
C00002/10	0: Off / ready	Reserved
C00002/11	0: Off / ready	Save all parameter sets <ul style="list-style-type: none"> • All parameter sets are saved to the memory module safe against mains failure. ▶ Save all parameter sets
C00002/12	0: Off / ready	Reserved
C00002/13	0: Off / ready	Reserved
C00002/14	0: Off / ready	Reserved
C00002/15	0: Off / ready	Reserved
C00002/16	1: On / start	Enable controller <ul style="list-style-type: none"> 1 ≡ Enable controller 0 ≡ Inhibit controller ▶ Enable/inhibit controller
C00002/17	0: Off / ready	Activate quick stop <ul style="list-style-type: none"> 1 ≡ Activate quick stop 0 ≡ Deactivate quick stop ▶ Activate/deactivate quick stop
C00002/18	0: Off / ready	Reserved
C00002/19	0: Off / ready	Reset error <ul style="list-style-type: none"> • After the reset (acknowledgement) of the current error, further errors may be pending which must also be reset. • The status determining error is displayed in C00168. • The current error is displayed in C00170. ▶ Error messages of the operating system
C00002/20	0: Off / ready	Reserved
C00002/21	0: Off / ready	Delete logbook <ul style="list-style-type: none"> • All entries in the logbook of the controller are deleted. • In the logbook, information on the error history is saved. ▶ Logbook
C00002/22	0: Off / ready	Reserved

Parameter Name: C00002 Device command		Data type: UNSIGNED 8 Index: 24573 _d = 5FFD _h
C00002/23	0: Off / ready	<p>Motor parameter identification</p> <ul style="list-style-type: none"> This device command serves to carry out automatic motor parameter identification. The identification method can be selected in C02867. The device command is only executed when the drive controller is in the "SwitchedOn" status. In order to identify the motor parameters, the controller must be enabled after this device command. <p>► Automatic motor parameter identification</p>
C00002/24	0: Off / ready	<p>Setting Hiperface position</p> <ul style="list-style-type: none"> From version 14.00.00 <p>► SinCos absolute value encoder with HIPERFACE® protocol</p>
C00002/25	0: Off / ready	<p>Identify resolver error</p> <ul style="list-style-type: none"> The device command is only executed when the drive controller is in the "SwitchedOn" status. <p>e ► Optimise resolver behaviour</p>
C00002/26	0: Off / ready	<p>CAN reset node</p> <ul style="list-style-type: none"> Reinitialise "CAN on board" interface. Required when changing the baud rate, node address, or identifiers. <p>► "CAN on board" system bus</p>
C00002/27	0: Off / ready	<p>Device search function</p> <ul style="list-style-type: none"> This device command serves to optically locate a controller connected online (e.g. for maintenance work). <p>► Device search function</p>
C00002/28	0: Off / ready	<p>Check MasterPin</p> <p>► Unlocking the controller with a MasterPin</p>
C00002/29	0: Off / ready	<p>Set binding ID</p> <p>► Device personalisation</p>
C00002/30	0: Off / ready	<p>Delete binding ID</p> <p>► Device personalisation</p>
C00002/31	0: Off / ready	<p>Set password</p> <p>► Password protection</p>
C00002/32	0: Off / ready	<p>Check password</p> <p>► Password protection</p>
C00002/33	0: Off / ready	<p>Delete password</p> <p>► Password protection</p>
C00002/34	0: Off / ready	<p>Pole position identification (360°)</p> <ul style="list-style-type: none"> This device command is serves to carry out an automatic identification of the pole position. The device command is only executed when the drive controller is in the "SwitchedOn" status. In order to identify the pole position, the controller must be enabled after this device command. <p>► Pole position identification</p>
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00003

Parameter Name: C00003 Status of last device command		Data type: UNSIGNED_8 Index: 24572 _d = 5FFC _h
Status of the device command executed last (C00002).		
Note: Before switching off the supply voltage after carrying out a device command, check whether the device command has been carried out successfully via the status display! ▶ Drive control (DCTRL): Device commands		
Selection list (read only)		Info
0	Successful	Device command has been executed successfully.
1	Command unknown	Device command implausible or unknown to the system.
2	Password protection	Unauthorised access for requested device command. ▶ Password protection
3	Time-out	Device command could not be processed in the defined time (timeout).
4	System fault	
5	Command server assigned	
6	Controller inhibit required	
10	Memory module binding error	▶ Device personalisation
11	Password too short	▶ Password protection
12	Wrong password	
13	Password already set	
14	Password not assigned	
20	Setting the hipurface position failed	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00005

Parameter Name: C00005 Application		Data type: UNSIGNED_16 Index: 24570 _d = 5FFA _h
Selection of the technology application		
Selection list (Lenze setting printed in bold)		Info
0	Wiring has changed	This display appears if the FB interconnection has been changed in the application level using the FB Editor.
1000	Actuating drive speed	This technology application is used to solve speed-controlled drive tasks, e.g. conveying belts. ► TA "Actuating drive speed"
1100	Actuating drive speed (AC Drive Profile)	From version 13.00.00 This technology application is used to solve speed-controlled drive tasks, e.g. conveying belts. The process data word received by the master control is interpreted as "AC Drive Profile" control word. ► TA "Actuating drive speed (AC Drive Profile)"
2000	Table positioning	This technology application is used to solve position-controlled drive tasks which are usually controlled by a higher-level control system using a fieldbus. ► TA "Table positioning"
3000	Switch-off positioning	This technology application is used to solve speed-controlled drive tasks which require a pre-switch off or stopping at certain positions, e.g. roller conveyors and conveying belts. This is implemented by connecting switch-off sensors. ► TA "Switch-off positioning"
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00006

Parameter Name: C00006 Motor control		Data type: UNSIGNED_8 Index: 24569 _d = 5FF9 _h
Selection of the motor control mode		
► Motor control (MCTRL): Select control mode		
Selection list (Lenze setting printed in bold)		Info
1	SC: Servo control PSM	This control type is used for the servo control of a synchronous motor. • The control type requires a speed feedback via an encoder mounted to the motor! ► Servo control
2	SC: Servo control ASM	This control type is used for the servo control of an asynchronous motor. • The control type requires a speed feedback via an encoder mounted to the motor! ► Servo control
3	SLPSM: Sensorless PSM	This control type is used for the sensorless control of a synchronous motor. ► Sensorless control for synchronous motors
4	SLVC: Vector control	This control type is used for sensorless vector control of an asynchronous motor. • The control type requires motor parameters to be set as exactly as possible! ► Sensorless vector control

Parameter Name: C00006 Motor control		Data type: UNSIGNED_8 Index: 24569 _d = 5FF9 _h
6	VFCplus: V/f linear	<p>This control type is used for the speed control of an asynchronous motor via a linear V/f characteristic and is the simplest control type.</p> <ul style="list-style-type: none"> For setting the V/f characteristic, only the rated frequency (C00089) and the rated voltage (C00090) of the motor have to be entered. <p>► V/f characteristic control</p>
7	VFCplus: V/f linear + encoder	<p>This control type is used for speed control of an asynchronous motor via a linear V/f characteristic.</p> <ul style="list-style-type: none"> The control type requires a speed feedback via an encoder mounted to the motor! For setting the V/f characteristic, only the rated frequency (C00089) and the rated voltage (C00090) of the motor have to be entered. <p>► V/f control</p>
8	VFCplus: V/f quadr	<p>This control type is used for speed control of an asynchronous motor via a square-law V/f characteristic.</p> <ul style="list-style-type: none"> For setting the V/f characteristic, only the rated frequency (C00089) and the rated voltage (C00090) of the motor have to be entered. <p>► V/f characteristic control</p>
9	VFCplus: V/f quadr + encoder	<p>This control type is used for speed control of an asynchronous motor via a square-law V/f characteristic.</p> <ul style="list-style-type: none"> The control type requires a speed feedback via an encoder mounted to the motor! For setting the V/f characteristic, only the rated frequency (C00089) and the rated voltage (C00090) of the motor have to be entered. <p>► V/f control</p>
10	VFCplus: V/f definable	<p>This type of control is used for the speed control of an asynchronous motor via a user-definable characteristic with several interpolation points.</p> <ul style="list-style-type: none"> For setting the V/f characteristic, only the rated frequency (C00089) and the rated voltage (C00090) of the motor have to be entered. <p>► V/f characteristic control</p>
11	VFCplusEco: V/f energy-saving	<p>This control type is used for energy-saving speed control of an asynchronous motor via a linear V/f characteristic.</p> <ul style="list-style-type: none"> For setting the V/f characteristic, only the rated frequency (C00089) and the rated voltage (C00090) of the motor have to be entered. Predestinated application areas of this control type are materials handling technology and pump and fan systems. <p>► V/f characteristic control, energy-saving</p>
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00007

Parameter Name: C00007 Control mode		Data type: UNSIGNED_16 Index: 24568 _d = 5FF8 _h
<p>With this parameter the control mode for the technology application selected under C00005 is defined, i.e. how the inputs and outputs of the technology application are connected to the I/Os of the controller.</p> <ul style="list-style-type: none"> How the inputs and outputs are connected in the individual control modes is described in the corresponding technology application: <ul style="list-style-type: none"> "Actuating drive speed" TA TA "actuating drive speed (AC Drive Profile)" TA "Table positioning" "Switch-off positioning" TA 		
Selection list (Lenze setting printed in bold)		Info
0	Wiring has changed	This is displayed when the FB interconnection has been changed in the I/O level via the FB Editor.
10	Terminals 0	The technology application is controlled via the digital and analog input terminals of the controller. <ul style="list-style-type: none"> For a short overview of the preconfigured terminal assignment see the following section "Terminal assignment of the control modes 10 ... 16".
12	Terminals 2	
14	Terminals 11	
16	Terminal 16	
20	Keypad	The technology application is controlled via the keypad.
21	PC	The technology application is controlled via the "Free parameters" of the controller (PC control).
30	CAN	The technology application is controlled by means of CAN-PDOs via the system bus "CAN on board". <ul style="list-style-type: none"> "CAN on board" system bus
40	MCI	The technology application is controlled by means of MCI-PDOs via the MCI-interface of an attached communication module (e.g. PROFIBUS).
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

Terminal assignment of the control modes 10 ... 16

Note: The following tables only list the connected inputs/outputs.

"Actuating drive speed" TA					
Input/output	10: Terminals 0		12: Terminals 2	14: Terminals 11	16: Terminals 16
RFR	Controller enable / Reset of error message				
DI1	Fixed setpoint 1/3			Change of direction of rotation	Fixed setpoint 1/3
DI2	Fixed setpoint 2/3			Activate manual DC-injection braking (DCB)	Fixed setpoint 2/3
DI3	Activate manual DC-injection braking (DCB)	Quick stop		Motor potentiometer: Increase speed	CW rotation quick stop
DI4	Change of direction of rotation			Motor potentiometer: Decrease speed	CCW rotation quick stop
A1U, A1I	Main speed setpoint (10 V ≡ 100 % reference speed)				
O1U, O1I	Actual speed value (10 V ≡ 100 % reference speed)				
DO1	Status "Drive is ready"				
Relay output	Status "Error is pending"				

TA "actuating drive speed (AC Drive Profile)"				
Input/output	10: Terminals 0	12: Terminals 2	14: Terminals 11	16: Terminals 16
RFR	Controller enable / Reset of error message			
DI1	Fixed setpoint 1/3		Change of direction of rotation	Fixed setpoint 1/3
DI2	Fixed setpoint 2/3		Activate manual DC-injection braking (DCB)	Fixed setpoint 2/3
DI3	Activate manual DC-injection braking (DCB)	Quick stop	Motor potentiometer: Increase speed	CW rotation quick stop
DI4	Change of direction of rotation		Motor potentiometer: Decrease speed	CCW rotation quick stop
A1U, A1I	Local speed/torque setpoint (speed mode: 10 V \equiv 100 % reference speed; torque mode: 10 V \equiv 100 % M_{\max})			
O1U, O1I	Actual speed value (10 V \equiv 100 % reference speed)			
DO1	Status "Drive is ready"			
Relay output	Status "Error is pending"			

TA "Table positioning"				
Input/output	10: Terminals 0	12: Terminals 2	14: Terminals 11	16: Terminals 16
RFR	Controller enable / Reset of error message			
DI1	-	-	Positive limit switch	-
DI2	-	-	Negative limit switch	-
DI3	Positive limit switch	-	-	Manual jog in positive direction
DI4	Negative limit switch	Positioning profile, array bit (valency 4)		Manual jog in negative direction
DI5	Positioning profile, array bit (valency 2)			
DI6	Positioning profile, array bit (valency 1)			
DI7	Start of profile generation			
A1U, A1I	Main speed setpoint (10 V \equiv 100 % reference speed)			
O1U, O1I	Actual speed value (10 V \equiv 100 % reference speed)			
O2U, O2I	Current motor current (10 V \equiv 100 % I_{\max_mot})			
DO1	Status "Drive is ready"			
DO2	Status "Target position (actual value) is in the target window"			
DO3	Status "Home position is known"			
BD1, BD2	Control of the holding brake			
Relay output	Status "Error is pending"			

"Switch-off positioning" TA				
Input/output	10: Terminals 0	12: Terminals 2	14: Terminals 11	16: Terminals 16
RFR	Controller enable	Controller enable / Reset of error message		
DI1	Fixed setpoint 1/3	Stop function 1		Fixed setpoint 1/3
DI2	Fixed setpoint 2/3	Stop function 2	Selection: Pre-switch off 1	Fixed setpoint 2/3
DI3	Reset error message	CW rotation quick stop Selection: Switch-off position 1		CW rotation quick stop
DI4	Change of direction of rotation	CCW rotation quick stop Selection: Switch-off position 2		CCW rotation quick stop
DI5	-	-	Stop function 2	-
DI6	-	-	Selection: Pre-switch off 2	-
A1U	Main speed setpoint (10 V \equiv 100 % reference speed)			
BD1, BD2	Control of the holding brake			

C00008

Parameter Name: C00008 Original application control source		Data type: UNSIGNED_16 Index: 24567 _d = 5FF7 _h
Display of the originally selected technology application and the originally selected control mode. <ul style="list-style-type: none"> • This parameter shows the selection that was set with C00005 and C00007 before a change in the I/O level or the application level was carried out. • For diagnostic purposes, this display serves to determine whether there is a standard interconnection in the controller or a change carried out by the user. 		
Selection list (read only)		Info
0	Free Free	Application: Interconnection has been changed. I/O level: Interconnection has been changed.
10	Free Terminal0	Application: Interconnection has been changed. I/O level: "Terminals 0" control mode
12	Free Terminal2	Application: Interconnection has been changed. I/O level: "Terminal 2" control mode
14	Free Terminal11	Application: Interconnection has been changed. I/O level: "Terminal 11" control mode
16	Free Terminal 16	Application: Interconnection has been changed. I/O level: "Terminal 16" control mode
20	Free Keypad	Application: Interconnection has been changed. I/O level: "Keypad" control mode
21	Free PC	Application: Interconnection has been changed. I/O level: "PC" control mode
30	Free CAN	Application: Interconnection has been changed. I/O level: "CAN" control mode
40	Free MCI	Application: Interconnection has been changed. I/O level: "MCI" control mode
1000	Speed Free	Application: Actuating drive speed I/O level: Interconnection has been changed.
1010	Speed Terminal0	Application: Actuating drive speed I/O level: "Terminals 0" control mode
1012	Speed Terminal2	Application: Actuating drive speed I/O level: "Terminal 2" control mode
1014	Speed Terminal11	Application: Actuating drive speed I/O level: "Terminal 11" control mode
1016	Speed Terminal16	Application: Actuating drive speed I/O level: "Terminal 16" control mode
1020	Speed Keypad	Application: Actuating drive speed I/O level: "Keypad" control mode
1021	Speed PC	Application: Actuating drive speed I/O level: "PC" control mode
1030	Speed CAN	Application: Actuating drive speed I/O level: "CAN" control mode
1040	Speed MCI	Application: Actuating drive speed I/O level: "MCI" control mode
1100	SpeedACdrive Free	Application: Actuating drive speed (AC Drive Profile) I/O level: Interconnection has been changed.
1110	SpeedACdrive Terminal0	Application: Actuating drive speed (AC Drive Profile) I/O level: "Terminals 0" control mode
1112	SpeedACdrive Klemme2	Application: Actuating drive speed (AC Drive Profile) I/O level: "Terminal 2" control mode
1114	SpeedACdrive Klemme11	Application: Actuating drive speed (AC Drive Profile) I/O level: "Terminal 11" control mode

Parameter Name: C00008 Original application control source		Data type: UNSIGNED_16 Index: 24567 _d = 5FF7 _h
1116	SpeedACdrive Klemme16	Application: Actuating drive speed (AC Drive Profile) I/O level: "Terminal 16" control mode
1120	SpeedACdrive Keypad	Application: Actuating drive speed (AC Drive Profile) I/O level: "Keypad" control mode
1121	SpeedACdrive PC	Application: Actuating drive speed (AC Drive Profile) I/O level: "PC" control mode
1130	SpeedACdrive CAN	Application: Actuating drive speed (AC Drive Profile) I/O level: "CAN" control mode
1140	SpeedACdrive MCI	Application: Actuating drive speed (AC Drive Profile) I/O level: "MCI" control mode
2000	TabPos Free	Application: Table positioning I/O level: Interconnection has been changed.
2010	TabPos Terminal0	Application: Table positioning I/O level: "Terminals 0" control mode
2012	TabPos Terminal2	Application: Table positioning I/O level: "Terminal 2" control mode
2014	TabPos Terminal11	Application: Table positioning I/O level: "Terminal 11" control mode
2016	TabPos Terminal16	Application: Table positioning I/O level: "Terminal 16" control mode
2020	TabPos Keypad	Application: Table positioning I/O level: "Keypad" control mode
2021	TabPos PC	Application: Table positioning I/O level: "PC" control mode
2030	TabPos CAN	Application: Table positioning I/O level: "CAN" control mode
2040	TabPos MCI	Application: Table positioning I/O level: "MCI" control mode
3000	SwitchPos Free	Application: Switch-off positioning I/O level: Interconnection has been changed.
3010	SwitchPos Terminal0	Application: Switch-off positioning I/O level: "Terminals 0" control mode
3012	SwitchPos Terminal 2	Application: Switch-off positioning I/O level: "Terminal 2" control mode
3014	SwitchPos Terminal 11	Application: Switch-off positioning I/O level: "Terminal 11" control mode
3016	SwitchPos Terminal 16	Application: Switch-off positioning I/O level: "Terminal 16" control mode
3020	SwitchPos Keypad	Application: Switch-off positioning I/O level: "Keypad" control mode
3021	SwitchPos PC	Application: Switch-off positioning I/O level: "PC" control mode
3030	SwitchPos CAN	Application: Switch-off positioning I/O level: "CAN" control mode
3040	SwitchPos MCI	Application: Switch-off positioning I/O level: "MCI" control mode
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00010

Parameter Name: C00010 AIN1: Characteristic			Data type: INTEGER_16 Index: 24565 _d = 5FF5 _h
			► Analog terminals: Signal adaptation via characteristic
Setting range (min. value unit max. value)			
0.00	%	199.99	
Subcodes	Lenze setting	Info	
C00010/1	0.00 %	AIN1: (+y0) = min	
C00010/2	0.00 %	AIN1: (+x0) = Dead band	
C00010/3	0.00 %	AIN1: (-y0) = (-min)	
C00010/4	0.00 %	AIN1: (-x0) = (-Dead band)	
C00010/5	100.00 %	AIN1: (+ymax)	
C00010/6	100.00 %	AIN1: (+xmax)	
C00010/7	100.00 %	AIN1: (-ymax)	
C00010/8	100.00 %	AIN1: (-xmax)	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00011

Parameter Name: C00011 Appl.: Reference speed			Data type: UNSIGNED_16 Index: 24564 _d = 5FF4 _h
Setting the reference speed <ul style="list-style-type: none"> • In the controller, all speed-related signals are processed to one reference variable in percent. • Set a reference speed here that corresponds to 100 %. • The frequency that corresponds to the set reference speed is displayed in C00059. 			
Note: This is not a maximum limitation! All values in percent in the controller may be in a range of 0 ... 199.99 %.			
Setting range (min. value unit max. value)			Lenze setting
50	rpm	60000	1500 rpm
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00012

Parameter Name: C00012 Accel. time - main setpoint			Data type: UNSIGNED_32 Index: 24563 _d = 5FF3 _h
The L_NSet_1 FB: Acceleration time of the ramp generator for the main speed setpoint <ul style="list-style-type: none"> • Generally, this ramp generator is used for all speed-controlled technology applications. 			
Setting range (min. value unit max. value)			Lenze setting
0.000	s	999.999	2.000 s
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C00013

Parameter Name: C00013 Decel. time - main setpoint			Data type: UNSIGNED_32 Index: 24562 _d = 5FF2 _h	
The L_NSet 1 FB: Deceleration time of the ramp generator for the main speed setpoint • Generally, this ramp generator is used for all speed-controlled technology applications.				
Setting range (min. value unit max. value)			Lenze setting	
0.000	s	999.999	2.000 s	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000				

C00015

Parameter Name: C00015 VFC: V/f base frequency			Data type: UNSIGNED_16 Index: 24560 _d = 5FF0 _h	
V/f base frequency for V/f characteristic control (VFCplus) and V/f control (VFCplus+encoder) <ul style="list-style-type: none">• The motor voltage increases linearly with the frequency until the base frequency is reached. From this value on, the motor voltage remains constant, the speed increases and the maximum torque decreases.• After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically. An automatic detection via the motor parameter identification is possible as well.				
Setting range (min. value unit max. value)			Lenze setting	
7.5	Hz	2600.0	50.0 Hz	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10				

C00016

Parameter Name: C00016 VFC: Vmin boost			Data type: UNSIGNED_16 Index: 24559 _d = 5FEF _h	
<p>Boost of the V/f voltage characteristic in the range of small speeds or frequencies with V/f characteristic control (VFCplus) and V/f control (VFCplus+encoder)</p> <ul style="list-style-type: none">• This may increase the starting torque.• After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically. An automatic detection via the motor parameter identification is possible as well. <p>► Motor control (MCTRL): Setting the Vmin boost</p>				
Setting range (min. value unit max. value)			Lenze setting	
0.00	%	100.00	1.60 %	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100				

C00018

Parameter | Name: **C00018 | Switching frequency**

Data type: UNSIGNED_8
Index: 24557_d = 5FED_h

Selection of the pulse width modulated switching frequency transferred from the inverter to the motor

- Select between an ideal setting for the drive which provides smooth running, and an optimal setting with regard to the inverter which keeps its losses to a minimum (min. Pv).
- Both possibilities offer fixed and variable switching frequencies.
- When a variable switching frequency is selected, the switching frequency may change as a function of the load and rotational frequency.

[▶ Selection of switching frequency](#)

Selection list (Lenze setting printed in bold)	
1	4 kHz var./drive-optimised
2	8 kHz var./drive-optimised
3	16 kHz var./drive-optimised
5	2 kHz constant/drive-optimised
6	4 kHz constant/drive-optimised
7	8 kHz constant/drive-optimised
8	16 kHz constant/drive-optimised
11	4 kHz var./min. Pv
12	8 kHz var./min. Pv
13	16 kHz var./min. Pv
15	2 kHz constant/min. Pv
16	4 kHz constant/min. Pv
17	8 kHz constant/min. Pv
18	16 kHz constant/min. Pv
21	8 kHz var./drive-opt./4 kHz min
22	16 kHz var./drive-opt./4 kHz min
23	16 kHz var./drive-opt./8 kHz min
31	8 kHz var./min. Pv/4 kHz min
32	16 kHz var./min. Pv/4 kHz min
33	16 kHz var./min. Pv/8 kHz min

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☒ MOT Scaling factor: 1

C00019

Parameter Name: C00019 Auto DCB: Threshold			Data type: UNSIGNED_16 Index: 24556 _d = 5FEC _h	
Setpoint speed threshold for automatic DC injection braking <ul style="list-style-type: none">• For speed setpoints with values below the thresholds a DC current is injected or the motor is not supplied with current, depending on the setting. <div>▸ DC-injection braking</div>				
Setting range (min. value unit max. value)			Lenze setting	
0	rpm	60000	3 rpm	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1				

C00020

Parameter Name: C00020 AIN2: Characteristic			Data type: INTEGER_16 Index: 24555 _d = 5FEB _h		
▶ Analog terminals: Signal adaptation via characteristic					
Setting range (min. value unit max. value)					
0.00	%	199.99			
Subcodes	Lenze setting		Info		
C00020/1	0.00 %		AIN2: (+y0) = min		
C00020/2	0.00 %		AIN2: (+x0) = Dead band		
C00020/3	0.00 %		AIN2: (-y0) = (-min)		
C00020/4	0.00 %		AIN2: (-x0) = (-Dead band)		
C00020/5	100.00 %		AIN2: (+ymax)		
C00020/6	100.00 %		AIN2: (+xmax)		
C00020/7	100.00 %		AIN2: (-ymax)		
C00020/8	100.00 %		AIN2: (-xmax)		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00021

Parameter Name: C00021 Slip comp.			Data type: INTEGER_16 Index: 24554 _d = 5FE _h		
<p>Slip compensation for V/f characteristic control (VFCplus) and sensorless vector control (SLVC)</p> <ul style="list-style-type: none">• A higher slip compensation results in a higher increase in frequency and voltage when the machine is under load.• After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically. An automatic detection via the motor parameter identification is possible as well. <p>▶ Motor control (MCTRL): Optimising the operational performance by slip compensation</p>					
Setting range (min. value unit max. value)			Lenze setting		
-100.00	%	100.00	2.67 %		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C00022

Parameter Name: C00022 I_{max} in motor mode			Data type: UNSIGNED_16 Index: 24553 _d = 5FE9 _h		
Maximum current in motor mode for all motor control modes					
Setting range (min. value unit max. value)			Lenze setting		
0.00	A	655.35	47.00 A		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C00023

Parameter Name: C00023 I_{max} in generator mode			Data type: INTEGER_16 Index: 24552 _d = 5FE8 _h		
Maximum current in generator mode for all motor control modes <ul style="list-style-type: none">• 100 % ≡ I_{max} in motor mode (C00022)					
Setting range (min. value unit max. value)			Lenze setting		
0.00	%	100.00	100.00 %		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C00024

Parameter Name: C00024 LS_DriveInterface: bNActCompare			Data type: INTEGER_16 Index: 24551 _d = 5FE7 _h		
Threshold for the actual speed comparison					
<ul style="list-style-type: none">• This parameter serves to set a threshold that is compared with the actual speed value.• If the value falls below this threshold, the <i>bNActCompare</i> output sets the LS_DriveInterface system block to TRUE.• Switching hysteresis = +1 %					
Setting range (min. value unit max. value)			Lenze setting		
0.00	%	199.99	0.00 %		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00026

Parameter Name: C00026 AINx: Offset			Data type: INTEGER_16 Index: 24549 _d = 5FE5 _h		
Offset for analog inputs					
<div>▶ Analog terminals</div>					
Setting range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes	Lenze setting	Info			
C00026/1	0.00 %	AIN1: Offset			
C00026/2	0.00 %	AIN2: Offset			
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 100</div></div>					

C00027

Parameter Name: C00027 AINx: Gain			Data type: INTEGER_32 Index: 24548 _d = 5FE4 _h		
Gain for analog inputs					
<div>▶ Analog terminals</div>					
Setting range (min. value unit max. value)					
-100.0000		100.0000			
Subcodes	Lenze setting		Info		
C00027/1	1.0000		AIN1: Gain		
C00027/2	1.0000		AIN2: Gain		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 10000</div></div>					

C00028

Parameter Name: C00028 AINx: Input voltage			Data type: INTEGER_16 Index: 24547 _d = 5FE3 _h		
Display of the input voltage at the analog inputs					
<div>▶ Analog terminals</div>					
Display range (min. value unit max. value)					
-10.00	V	10.00			
Subcodes			Info		
C00028/1			AIN1: Input voltage		
C00028/2			AIN2: Input voltage		
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 100</div></div>					

C00029

Parameter Name: C00029 AINx: Input current			Data type: INTEGER_16 Index: 24546 _d = 5FE2 _h		
Display of the input current at the analog inputs					
<ul style="list-style-type: none">• When the corresponding analog input is configured for current measurement (C00034/x = 1 or 2).• When C00034/x is set = 2 (4 ... 20 mA), 0 ... 16 mA is displayed.					
<div>▶ Analog terminals</div>					
Display range (min. value unit max. value)					
0.00	mA	20.00			
Subcodes			Info		
C00029/1			AIN1: Input current		
C00029/2			AIN2: Input current		
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 100</div></div>					

C00030

Parameter Name: C00030 LS_DFOut: Const.			Data type: INTEGER_16 Index: 24545 _d = 5FE1 _h		
From version 12.00.00 Settings for the digital frequency output (multi-encoder interface X8)					
▶ Digital frequency coupling					
Setting range (min. value unit max. value)					
16		16384			
Subcodes	Lenze setting		Info		
C00030/1	2048		LS_DFOut : number of increments <ul style="list-style-type: none">• The number of increments determines after how many output increments a zero pulse will be generated. Each zero pulse defines a covered "revolution" of the rotary transducer simulated by the digital frequency output.		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00033

Parameter Name: C00033 AINx: Output value			Data type: INTEGER_16 Index: 24542 _d = 5FDE _h		
Display of the output value in percent of the analog input amplifier <ul style="list-style-type: none">• 100 % ≡ 16384 ≡ +10 V / +20 mA					
<div>▶ Analog terminals</div>					
Display range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes			Info		
C00033/1			AIN1: Output value		
C00033/2			AIN2: Output value		
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 100</div></div>					

C00034

Parameter Name: C00034 AINx: Configuration		Data type: UNSIGNED_8 Index: 24541 _d = 5FDD _h
Configuration of the analog inputs for current or voltage measurement		
▶ Analog terminals		
Selection list		Info
0	-10V..+10V	Input signal is the voltage signal -10 V ... +10 V • -10 V ... +10 V ≡ -100 % ... +100 %
1	0mA..20mA	Input signal is the current signal 0 mA ... 20 mA • 0 mA ... 20 mA ≡ 0 % ... +100 %
2	4mA..20mA	Input signal is the current signal 4 mA ... 20 mA • 4 mA ... 20 mA ≡ 0 % ... +100 % • The current loop is monitored for open circuit (I < 4 mA) by the device.
Subcodes	Lenze setting	Info
C00034/1	0: -10V..+10V	AIN1: Config.
C00034/2	0: -10V..+10V	AIN2: Config.
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00036

Parameter Name: C00036 DC braking: Current			Data type: INTEGER_16 Index: 24539 _d = 5FDB _h
Braking current in [%] based on rated device current (C00098)			
<div>▶ DC-injection braking</div>			
Setting range (min. value unit max. value)			Lenze setting
0.00	%	200.00	50.00 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT			Scaling factor: 100

C00039

Parameter Name:		Data type: INTEGER_16 Index: 24536 _d = 5FD8 _h	
C00039 Fixed setpoint x (L_NSet_1 n-Fix)			
The <u>L_NSet_1</u> FB: Fixed speed setpoints (JOG values) for the setpoint generator			
Setting range (min. value unit max. value)			
-199.99	%		
Subcodes	Lenze setting	Info	
C00039/1	40.00 %	Fixed setpoint 1	
C00039/2	60.00 %	Fixed setpoint 2	
C00039/3	80.00 %	Fixed setpoint 3	
C00039/4	0.00 %	Fixed setpoint 4	
C00039/5	0.00 %	Fixed setpoint 5	
C00039/6	0.00 %	Fixed setpoint 6	
C00039/7	0.00 %	Fixed setpoint 7	
C00039/8	0.00 %	Fixed setpoint 8	
C00039/9	0.00 %	Fixed setpoint 9	
C00039/10	0.00 %	Fixed setpoint 10	
C00039/11	0.00 %	Fixed setpoint 11	
C00039/12	0.00 %	Fixed setpoint 12	
C00039/13	0.00 %	Fixed setpoint 13	
C00039/14	0.00 %	Fixed setpoint 14	
C00039/15	0.00 %	Fixed setpoint 15	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00050

Parameter Name: C00050 MCTRL: Speed setpoint			Data type: INTEGER_32 Index: 24524 _d = 5FCD _h
Display of the speed setpoint at the speed setpoint input of the motor control			
Display range (min. value unit max. value)			
-120000	rpm	120000	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00051

Parameter Name: C00051 MCTRL: Actual speed value			Data type: INTEGER_32 Index: 24524 _d = 5FCD _h
Display of the actual speed value of the motor shaft			
Note: The displayed value only corresponds to the real actual speed value of the motor shaft if an encoder is connected to the motor and the evaluation of the feedback signal has been set correctly ("Closed loop" operation). In case of operation without speed feedback, the signal is calculated from the motor control and thus may not correspond to the real actual speed.			
Display range (min. value unit max. value)			
-120000	rpm	120000	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00052

Parameter Name: C00052 Motor voltage			Data type: UNSIGNED_16 Index: 24523 _d = 5FCB _h		
Display of the current motor voltage/output voltage of the inverter					
Display range (min. value unit max. value)					
0	V	1000			
<input checked="" type="checkbox"/> Read access			<input type="checkbox"/> Write access		
<input type="checkbox"/> CINH			<input type="checkbox"/> PLC STOP		
<input checked="" type="checkbox"/> No transfer			<input type="checkbox"/> COM		
<input type="checkbox"/> MOT			Scaling factor: 1		

C00053

Parameter Name: C00053 DC-bus voltage			Data type: UNSIGNED_16 Index: 24522 _d = 5FCB _h		
Display of the current DC-bus voltage					
Display range (min. value unit max. value)					
0	V	1000			
<input checked="" type="checkbox"/> Read access			<input type="checkbox"/> Write access		
<input type="checkbox"/> CINH			<input type="checkbox"/> PLC STOP		
<input checked="" type="checkbox"/> No transfer			<input type="checkbox"/> COM		
<input type="checkbox"/> MOT			Scaling factor: 1		

C00054

Parameter Name: C00054 Motor current			Data type: UNSIGNED_16 Index: 24521 _d = 5FC9 _h		
Display of the current motor current/output current of the inverter					
Display range (min. value unit max. value)					
0.00	A	300.00			
<input checked="" type="checkbox"/> Read access			<input type="checkbox"/> Write access		
<input type="checkbox"/> CINH			<input type="checkbox"/> PLC STOP		
<input checked="" type="checkbox"/> No transfer			<input type="checkbox"/> COM		
<input type="checkbox"/> MOT			Scaling factor: 100		

C00055

Parameter Name: C00055 Actual values			Data type: INTEGER_16 Index: 24520 _d = 5FC8 _h		
Actual value of the encoder/feedback system					
Note: When a single-track feedback has been selected for the HTL encoder (C00115 = 1 or 3), the sign of the actual speed value is created from the sign of the speed setpoint. In C00055/1 und C00055/2, a positive speed is always displayed.					
<div>► Encoder/feedback system</div>					
Display range (min. value unit max. value)					
-32767	rpm	32767			
Subcodes			Info		
C00055/1			Actual value - HTL encoder FreqIn12		
C00055/2			Actual value - HTL encoder FreqIn67		
C00055/3			Actual value - multi-encoder		
C00055/4			Actual value - resolver		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00056

Parameter Name: C00056 Torque			Data type: INTEGER_32 Index: 24519 _d = 5FC7 _h		
Display of the current torque					
Display range (min. value unit max. value)					
-65000.00	Nm	65000.00			
Subcodes			Info		
C00056/1			Torque demand <ul style="list-style-type: none">• Only in case of sensorless vector control (SLVC) and servo control (SC).		
C00056/2			Actual torque value <ul style="list-style-type: none">• Estimated actual torque for all motor control modes.		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00057

Parameter Name: C00057 Maximum torque			Data type: UNSIGNED_32 Index: 24518 _d = 5FC6 _h		
Display of the maximum torque to be generated by the motor <ul style="list-style-type: none">The maximum torque to be generated by the motor depends on various factors, e.g. on I_{max} in motor mode (C00022) and the motor type used.					
Display range (min. value unit max. value)					
0.00	Nm	65000.00			
<input checked="" type="checkbox"/> Read access			<input type="checkbox"/> Write access		
<input type="checkbox"/> CINH			<input type="checkbox"/> PLC STOP		
<input checked="" type="checkbox"/> No transfer			<input type="checkbox"/> COM		
<input type="checkbox"/> MOT			Scaling factor: 100		

C00058

Parameter Name: C00058 Output frequency			Data type: INTEGER_32 Index: 24517 _d = 5FC5 _h		
Display of the current output frequency					
Display range (min. value unit max. value)					
-1300.00	Hz	1300.00			
<input checked="" type="checkbox"/> Read access			<input type="checkbox"/> Write access		
<input type="checkbox"/> CINH			<input type="checkbox"/> PLC STOP		
<input checked="" type="checkbox"/> No transfer			<input type="checkbox"/> COM		
<input type="checkbox"/> MOT			Scaling factor: 100		

C00059

Parameter Name: C00059 Appl.: Reference frequency C11			Data type: UNSIGNED_32 Index: 24516 _d = 5FC4 _h		
Display of the field frequency which corresponds to the reference speed set in C00011 .					
Display range (min. value unit max. value)					
0.00	Hz	1300.00			
<input checked="" type="checkbox"/> Read access			<input type="checkbox"/> Write access		
<input type="checkbox"/> CINH			<input type="checkbox"/> PLC STOP		
<input checked="" type="checkbox"/> No transfer			<input type="checkbox"/> COM		
<input type="checkbox"/> MOT			Scaling factor: 100		

C00060

Parameter Name: C00060 Motor rotor position			Data type: UNSIGNED_16 Index: 24515 _d = 5FC3 _h		
Display range (min. value unit max. value)					
0		2047			
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C00061

Parameter Name: C00061 Heatsink temperature			Data type: INTEGER_16 Index: 24514 _d = 5FC2 _h		
Display of the current heatsink temperature					
Display range (min. value unit max. value)					
-50	°C	150			
<input checked="" type="checkbox"/> Read access			<input type="checkbox"/> Write access		
<input type="checkbox"/> CINH			<input type="checkbox"/> PLC STOP		
<input checked="" type="checkbox"/> No transfer			<input type="checkbox"/> COM		
<input type="checkbox"/> MOT			Scaling factor: 1		

C00062

Parameter Name: C00062 Temperature inside the controller			Data type: INTEGER_16 Index: 24513 _d = 5FC1 _h		
From version 02.00.00					
Display of the current temperature inside the controller					
Display range (min. value unit max. value)					
-200	°C	200			
Subcodes			Info		
C00062/1			Interior temperature of CU		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00063

Parameter Name: C00063 Motor temperature			Data type: INTEGER_16 Index: 24512 _d = 5FC0 _h		
Display of the current motor temperature					
Display range (min. value unit max. value)					
-200	°C	250			
Subcodes			Info		
C00063/1			Motor temperature		
C00063/2			Motor temperature via resolver		
C00063/3			Motor temperature via MultiEncoder		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00064

Parameter Name: C00064 Device utilisation (lxt)			Data type: INTEGER_16 Index: 24511 _d = 5FBF _h		
Display of the device utilisation lxt in different time resolutions					
• If the value displayed here exceeds the threshold set in C00123 , the fault message "OC5: Device overload (lxt)" is output and the fault response set in C00604 is executed (default setting: "Warning").					
Display range (min. value unit max. value)					
0.00	%	250.00			
Subcodes			Info		
C00064/1			Device utilisation (lxt) • Maximum value of the pulse utilisation (C00064/2) and permanent utilisation (C00064/3).		
C00064/2			Device utilisation (lxt) 15s • Pulse utilisation over the last 15 seconds (only for loads >160 %).		
C00064/3			Device utilisation (lxt) 3 min • Permanent utilisation over the last 3 minutes.		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00065

Parameter Name: C00065 Supply voltage 24V			Data type: INTEGER_16 Index: 24510 _d = 5FBE _h		
Display of the 24V supply voltage for the supply of the control electronics					
Note: The 24 V supply for the control electronics is either provided by an external supply or by the controller itself if it is connected to the mains voltage.					
Display range (min. value unit max. value)					
0.0	V	3276.7			
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10					

C00066

Parameter Name:			Data type: INTEGER_16 Index: 24509 _d = 5FBD _h		
C00066 Thermal motor load (I²xt)					
Display of the thermal motor load, sensorlessly determined using a motor model					
<ul style="list-style-type: none">• If the value displayed here exceeds "100.00 %", the error message "OC6: Thermal motor overload (I2xt)" is output and the fault response set in C00606 is executed (default setting: "Warning").					
<div>▶ Motor overload monitoring (I2xt)</div>					
Display range (min. value unit max. value)					
0.00	%	199.99			
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 100</div></div>					

C00070

Parameter Name: C00070 Vp speed controller			Data type: UNSIGNED_16 Index: 24505 _d = 5FB9 _h
Amplification factor Vp of the speed controller for different motor control modes			
Setting range (min. value unit max. value)			
0.00		600.00	
Subcodes	Lenze setting	Info	
C00070/1	15.00	SLVC : Vp speed controller	
C00070/2	6.00	SC : Vp speed controller	
C00070/3	3.00	SLPSM : Vp speed controller	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C00071

Parameter Name: C00071 Ti speed controller			Data type: UNSIGNED_16 Index: 24504 _d = 5FB8 _h
Reset time Ti of the speed controller for different motor control modes			
Setting range (min. value unit max. value)			
0.0	ms	6000.0	
Subcodes	Lenze setting	Info	
C00071/1	100.0 ms	SLVC : Ti speed controller	
C00071/2	50.0 ms	SC : Ti speed controller	
C00071/3	100.0 ms	SLPSM : Ti speed controller	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10			

C00072

Parameter Name: C00072 SC: Tdn speed controller			Data type: UNSIGNED_16 Index: 24503 _d = 5FB7 _h
Differential time constant Tdn of the speed controller for servo control (SC) and sensorless control for synchronous motors (SLPSM)			
Setting range (min. value unit max. value)			Lenze setting
0.00	ms	3.00	0.00 ms
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C00073

Parameter Name: C00073 I_{max}/M controller gain			Data type: UNSIGNED_16 Index: 24502 _d = 5FB6 _h
Amplification factor V _p of certain controllers for different motor control modes			
Setting range (min. value unit max. value)			
0.00		100.00	
Subcodes	Lenze setting	Info	
C00073/1	0.25	VFC : V _p I _{max} controller • After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically.	
C00073/2	1.25	SLVC : V _p torque controller	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C00074

Parameter Name: C00074 Reset time I_{max}/M controller			Data type: UNSIGNED_16 Index: 24501 _d = 5FB5 _h		
Reset time T _i of certain controllers for different motor control modes					
Setting range (min. value unit max. value)					
0	ms	9990			
Subcodes	Lenze setting		Info		
C00074/1	65 ms		VFC : Ti I _{max} controller		
C00074/2	30 ms		SLVC : Ti torque controller		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C00075

Parameter Name: C00075 Vp current controller			Data type: UNSIGNED_16 Index: 24500 _d = 5FB4 _h		
Gain factor Vp of the current controller for servo control (SC) and certain inverter functions (parameter identification, flying restart circuit) <ul style="list-style-type: none">After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically.					
Setting range (min. value unit max. value)			Lenze setting		
0.00	V/A	500.00	7.00 V/A		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C00076

Parameter Name: C00076 Ti current controller			Data type: UNSIGNED_16 Index: 24499 _d = 5FB3 _h		
Reset time Ti of the current controller for servo control (SC) and certain inverter functions (parameter identification, flying restart circuit) <ul style="list-style-type: none">After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically.					
Setting range (min. value unit max. value)			Lenze setting		
0.00	ms	500.00	10.61 ms		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C00077

Parameter Name: C00077 SC: Vp field controller			Data type: UNSIGNED_16 Index: 24498 _d = 5FB2 _h		
Gain factor Vp of the field controller for servo control (SC) <ul style="list-style-type: none">After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically.					
Setting range (min. value unit max. value)			Lenze setting		
0.00		500.00	12.80		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C00078

Parameter Name: C00078 SC: Tn field controller			Data type: UNSIGNED_16 Index: 24497 _d = 5FB1 _h
Reset time Tn of the field controller for servo control (SC) • After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically.			
Setting range (min. value unit max. value)			Lenze setting
0.0	ms	6000.0	256.0 ms
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10			

C00079

Parameter Name: C00079 SC: Settings		Data type: UNSIGNED_8 Index: 24496 _d = 5FB0 _h
Configuration of different options for servo control (SC) and sensorless control for synchronous motors (SLPSM)		
Selection list		
0	Off	
1	On	
Subcodes	Lenze setting	Info
C00079/1	0: Off	SC : Current controller - feedforward control <ul style="list-style-type: none">Please observe the notes regarding this function in the chapter "Feedforward control of the current controller"!
C00079/2	1: On	SC : Adapt. VP in the field weakening range <ul style="list-style-type: none">Speed-dependent adaptive field weakening controller.
C00079/3	0: Off	SC : n-ctrl anti-wind-up <ul style="list-style-type: none">"Anti-wind-up" effect of the speed controller in case of an output voltage limitation in the field weakening range.
C00079/4	1: On	Field weakening for synchronous motors <ul style="list-style-type: none">From version 02.00.00
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00080

Parameter Name: C00080 Override point of field weakening			Data type: INTEGER_16 Index: 24495 _d = 5FAF _h
Offset of the override point of field weakening • In the V/f characteristic control mode (VFCplus), the stall protection function or the max. permissible current in the field weakening range can be adapted.			
Setting range (min. value unit max. value)			Lenze setting
-500	Hz	500	0 Hz
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00081

Parameter Name: C00081 Rated motor power			Data type: UNSIGNED_16 Index: 24494 _d = 5FAE _h
This value can be obtained from the motor nameplate. After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically.			
Note: It is mandatory to give the rated motor power for the sensorless vector control (SLVC) and the servo control (SC).			
Setting range (min. value unit max. value)			Lenze setting
0.00	kW	500.00	11.00 kW
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C00082

Parameter Name: C00082 Motor rotor resistance			Data type: UNSIGNED_32 Index: 24493 _d = 5FAD _h
After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically. An automatic detection via the motor parameter identification is possible as well.			
Setting range (min. value unit max. value)			Lenze setting
0	mOhm	200000	276 mOhm
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00083

Parameter Name: C00083 Motor rotor time constant			Data type: UNSIGNED_16 Index: 24492 _d = 5FAC _h
Display of the rotor time constant of the motor • This value is calculated from the rotor resistance and the rotor inductance (leakage and magnetising inductance).			
Display range (min. value unit max. value)			
0	ms	32767	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00084

Parameter Name: C00084 Motor stator resistance			Data type: UNSIGNED_32 Index: 24491 _d = 5FAB _h
After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically. An automatic detection via the motor parameter identification is possible as well.			
Setting range (min. value unit max. value)			Lenze setting
0	mOhm	200000	330 mOhm
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00085

Parameter Name: C00085 Motor stator leakage inductance			Data type: UNSIGNED_16 Index: 24490 _d = 5FAA _h
After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically. An automatic detection via the motor parameter identification is possible as well.			
Setting range (min. value unit max. value)			Lenze setting
0.00	mH	650.00	3.50 mH
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C00087

Parameter Name: C00087 Rated motor speed			Data type: UNSIGNED_16 Index: 24488 _d = 5FA8 _h
This value can be obtained from the motor nameplate. After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically.			
Note: It is mandatory to give the rated motor speed for the sensorless vector control (SLVC) and the servo control (SC).			
Setting range (min. value unit max. value)			Lenze setting
50	rpm	60000	1460 rpm
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00088

Parameter Name: C00088 Rated motor current			Data type: UNSIGNED_16 Index: 24487 _d = 5FA7 _h
This value can be obtained from the motor nameplate. After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically.			
Note: It is mandatory to give the rated motor frequency for the sensorless vector control (SLVC) and the servo control (SC).			
Setting range (min. value unit max. value)			Lenze setting
0.20	A	320.00	21.00 A
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C00089

Parameter Name: C00089 Rated motor frequency			Data type: UNSIGNED_16 Index: 24486 _d = 5FA6 _h
This value can be obtained from the motor nameplate. After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically.			
Note: It is mandatory to give the rated motor frequency for the sensorless vector control (SLVC) and the servo control (SC).			
Setting range (min. value unit max. value)			Lenze setting
1	Hz	1000	50 Hz
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00090

Parameter Name: C00090 Rated motor voltage			Data type: UNSIGNED_16 Index: 24485 _d = 5FA5 _h
This value can be obtained from the motor nameplate. After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically.			
Setting range (min. value unit max. value)			Lenze setting
0	V	5000	400 V
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00091

Parameter Name: C00091 Motor cosine phi			Data type: UNSIGNED_8 Index: 24484 _d = 5FA4 _h		
This value can be obtained from the motor nameplate. After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically.					
Setting range (min. value unit max. value)			Lenze setting		
0.40		1.00	0.85		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C00092

Parameter Name: C00092 Motor magnetising inductance			Data type: UNSIGNED_16 Index: 24483 _d = 5FA3 _h		
After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically. An automatic detection via the motor parameter identification is possible as well.					
Setting range (min. value unit max. value)			Lenze setting		
0.0	mH	6500.0	81.0 mH		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C00093

Parameter Name: C00093 Power section identification			Data type: UNSIGNED_16 Index: 24482 _d = 5FA2 _h		
Display of the identification of the detected power section of the controller					
Display range (min. value unit max. value)					
0		65535			
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00095

Parameter Name: C00095 Motor magnetising current			Data type: UNSIGNED_16 Index: 24480 _d = 5FA0 _h		
After the motor to be used has been selected from the motor catalogue, the suitable value can be entered automatically. An automatic detection via the motor parameter identification is possible as well.					
Setting range (min. value unit max. value)			Lenze setting		
0.00	A	320.00	8.50 A		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C00097

Parameter Name: C00097 Rated motor torque			Data type: UNSIGNED_32 Index: 24478 _d = 5F9E _h		
Display of the rated motor torque					
• The value displayed here is calculated from different parameters, e.g. the maximum current set in C00022 .					
Display range (min. value unit max. value)					
0.00	Nm	100000.00			
<input checked="" type="checkbox"/> Read access			<input type="checkbox"/> Write access		
<input type="checkbox"/> CINH			<input type="checkbox"/> PLC STOP		
<input checked="" type="checkbox"/> No transfer			<input type="checkbox"/> COM		
<input type="checkbox"/> MOT			Scaling factor: 100		

C00098

Parameter Name: C00098 Device rated current			Data type: UNSIGNED_16 Index: 24477 _d = 5F9D _h		
Display of the rated inverter current which is defined by the integrated power section.					
Display range (min. value unit max. value)					
0.0	A	6000.0			
<input checked="" type="checkbox"/> Read access			<input type="checkbox"/> Write access		
<input type="checkbox"/> CINH			<input type="checkbox"/> PLC STOP		
<input checked="" type="checkbox"/> No transfer			<input type="checkbox"/> COM		
<input checked="" type="checkbox"/> MOT			Scaling factor: 10		

C00099

Parameter Name: C00099 Firmware version		Data type: VISIBLE_STRING Index: 24476 _d = 5F9C _h					
Display of the firmware version of the device as string							
<input checked="" type="checkbox"/> Read access	<input type="checkbox"/> Write access	<input type="checkbox"/> CINH	<input type="checkbox"/> PLC-STOP	<input checked="" type="checkbox"/> No transfer	<input type="checkbox"/> COM	<input type="checkbox"/> MOT	Character length: 12

C00100

Parameter Name: C00100 Firmware version			Data type: UNSIGNED_8 Index: 24475 _d = 5F9B _h		
Display of the firmware version of the device, divided into subsections.					
Display range (min. value unit max. value)					
0		99			
Subcodes			Info		
C00100/1			Firmware version - main version		
C00100/2			Firmware version - subversion		
C00100/3			Firmware version - release		
C00100/4			Firmware version - build		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00101

Parameter Name: C00101 Add. accel. time x			Data type: UNSIGNED_32 Index: 24474 _d = 5F9A _h		
The L_NSet 1 : FB: Additional acceleration times for the main setpoint					
• The additional acceleration times set here can be selected via the binary inputs <i>bT11</i> ... <i>bT18</i> of the L_NSet 1 FB.					
Setting range (min. value unit max. value)					
0.000	s	999.999			
Subcodes	Lenze setting	Info			
C00101/1	0.000 s	Add. accel. time 1 ... 15			
C00101/...					
C00101/15					
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C00103

Parameter Name: C00103 Add. decel. time x			Data type: UNSIGNED_32 Index: 24472 _d = 5F98 _h
The L_NSet 1 FB: Additional deceleration times for the main setpoint			
• The additional deceleration times set here can be selected via the binary inputs <i>bT1</i> ... <i>bT8</i> of the L_NSet 1 FB.			
Setting range (min. value unit max. value)			
0.000	s	999.999	
Subcodes	Lenze setting	Info	
C00103/1	0.000 s	Add. decel. time 1 ... 15	
C00103/...			
C00103/15			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C00104

Parameter Name: C00104 Quick stop setting		Data type: UNSIGNED_16 Index: 24471 _d = 5F97 _h	
From version 02.00.00			
		► Quick stop: Optional settings	
Setting range (min. hex value max. hex value)			
0x0000		0xFFFF	
Value is bit-coded:		Info	
Bit 0	Standstill position-controlled	1 ≡ At standstill the position control is activated. The basic conditions are shown in the flow diagram for the quick stop function.	
Bit 1	Ramp position-controlled	1 ≡ During the ramp-down phase, the position control is activated. The basic conditions are shown in the flow diagram for the quick stop function.	
Bit 2	Continue following error	From version 15.00.00 1 ≡ The current following error is continued if the quick stop with position control is activated while ramping down.	
Bit 3	Starting value is the setpoint speed	From version 15.00.00 0 ≡ The starting value at quick stop is the actual speed if it derives more than 5 rpm from the setpoint. This serves to prevent a jump to a strongly differing setpoint. 1 ≡ The starting value for quick stop is the setpoint speed .	
Bit 4	Use position encoder	From version 15.00.00 1 ≡ In case of quick stop with position control, the position encoder is used instead of the speed encoder. The basic conditions are shown in the flow diagram for the quick stop function.	
Bit 5	Reserved		
Bit 6	Reserved		
Bit 7	Reserved		
Bit 8	Reserved		
Bit 9	Reserved		
Bit 10	Reserved		
Bit 11	Reserved		
Bit 12	Reserved		
Bit 13	Reserved		
Bit 14	Reserved		
Bit 15	Reserved		
Subcodes	Lenze setting	Info	
C00104/1	0x0000	Quick stop setting	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT			

C00105

Parameter Name: C00105 Decel. time - quick stop			Data type: UNSIGNED_32 Index: 24470 _d = 5F96 _h		
The set deceleration time determines the ramp slope at quick stop					
▶ Activate/deactivate quick stop					
Setting range (min. value unit max. value)			Lenze setting		
0.000	s	999.900	2.000 s		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C00106

Parameter Name: C00106 Auto DCB: Hold time			Data type: UNSIGNED_32 Index: 24469 _d = 5F95 _h		
Hold time of the automatic DC injection brake <ul style="list-style-type: none">The DC injection brake is applied for the time set here if the value falls below the speed setpoint set in C00019. ▶ DC-injection braking					
Setting range (min. value unit max. value)			Lenze setting		
0.000	s	999.000	0.500 s		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C00107

Parameter Name: C00107 DC braking: Hold time			Data type: UNSIGNED_32 Index: 24468 _d = 5F94 _h		
Maximum hold time of the manual DC injection brake					
<ul style="list-style-type: none">• A time can be set here after which the DC injection brake is switched off automatically to prevent the motor from thermal overload.• When "999.000 s" is set, the hold time is infinite.					
<div>▶ DC-injection braking</div>					
Setting range (min. value unit max. value)			Lenze setting		
0.000	s	999.000	999.000 s		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1000</div></div>					

C00114

Parameter | Name: C00114 | DigInX: Inversion

Data type: UNSIGNED_16
Index: 24461_d = 5F8D_h

The polarity of each digital input of the device can be inverted via this bit field.

Digital input terminals

Setting range (min. hex value max. hex value)		Lenze setting
0x0000	0xFFFF	0x0000 (decimal: 0)
Value is bit-coded: (☑ = bit set)		Info
Bit 0 ☐	DI1 inverted	Inversion of digital input 1
Bit 1 ☐	DI2 inverted	Inversion of digital input 2
Bit 2 ☐	DI3 inverted	Inversion of digital input 3
Bit 3 ☐	DI4 inverted	Inversion of digital input 4
Bit 4 ☐	DI5 inverted	Inversion of digital input 5
Bit 5 ☐	DI6 inverted	Inversion of digital input 6
Bit 6 ☐	DI7 inverted	Inversion of digital input 7
Bit 7 ☐	Reserved	
Bit 8 ☐	Reserved	
Bit 9 ☐	Reserved	
Bit 10 ☐	Reserved	
Bit 11 ☐	Reserved	
Bit 12 ☐	Reserved	
Bit 13 ☐	Reserved	
Bit 14 ☐	Reserved	
Bit 15 ☐	Cinh inverted	Inversion of digital input RFR (controller enable)

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT

C00115

Parameter Name: C00115 DI 1/2 & 6/7: Fct.		Data type: UNSIGNED_8 Index: 24460 _d = 5F8C _h	
Function assignment of the digital terminals DI1/2 and DI6/7			
<div>► Digital input terminals: Function assignment</div>			
Selection list		Info	
0	DI1(6)=In / DI2(7)=In	DI1/6 = digital input DI2/7 = digital input	
1	DI1(6)=FreqIn / DI2(7)=In	DI1/6 = 1-track frequency input DI2/7 = digital input	
2	DI1(6)&DI2(7)=FreqIn (2-track)	DI1/6 and DI2/7 = 2-track frequency input	
3	DI1(6)=FreqIn / DI2(7)=direction	DI1/6 = 1-track frequency input DI2/7 = specification of direction	
4	DI1(6)=CountIn / DI2(7)=In	DI1/6 = counter input DI2/7 = digital input	
Subcodes	Lenze setting	Info	
C00115/1	0: DI1(6)=In / DI2(7)=In	Function assignment of DI1 and DI2	
C00115/2	0: DI1(6)=In / DI2(7)=In	Function assignment of DI6 and DI7	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00117

Parameter Name: C00117 Status of brake output BD		Data type: UNSIGNED_8 Index: 24458 _d = 5F8A _h
Status message of brake output		
Selection list (read only)		Info
0	Inactive	Brake output is inactive
1	Active	Brake output is active
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00118

Parameter Name: C00118 DigOutX: Inversion		Data type: UNSIGNED_8 Index: 24457 _d = 5F89 _h
The polarity of each digital output of the device can be inverted via this bit field. ▶ Digital output terminals		
Setting range (min. hex value max. hex value)		Lenze setting
0x00	0xFF	0x00 (decimal: 0)
Value is bit-coded: (<input checked="" type="checkbox"/> = bit set)		Info
Bit 0 <input type="checkbox"/>	Relay inverted	Relay inversion
Bit 1 <input type="checkbox"/>	DO1 inverted	Inversion of digital output 1
Bit 2 <input type="checkbox"/>	DO2 inverted	Inversion of digital output 2
Bit 3 <input type="checkbox"/>	DO3 inverted	Inversion of digital output 3
Bit 4 <input type="checkbox"/>	High current inverted	Inversion of high-current output
Bit 5 <input type="checkbox"/>	Reserved	
Bit 6 <input type="checkbox"/>	Reserved	
Bit 7 <input type="checkbox"/>	Reserved	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C00120

Parameter Name: C00120 Setting of motor overload (I²xt)		Data type: INTEGER_16 Index: 24455 _d = 5F87 _h
Operating threshold for the "OC6: Motor overload (I²xt)" error message <ul style="list-style-type: none"> • The response for reaching the threshold can be selected in C00606. • The current thermal motor load is displayed in C00066. ▶ Motor overload monitoring (I²xt)		
Setting range (min. value unit max. value)		Lenze setting
0.00	%	250.00 100.00 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100		

C00121

Parameter Name: C00121 Warning threshold motor temperature			Data type: UNSIGNED_16 Index: 24454 _d = 5F86 _h
Operating threshold for error message "Motor: Temperature at Res./Enc. > C121" • The response for reaching the threshold can be selected in C00583 . • The current motor temperature is displayed in C00063 . ▶ Encoder/feedback system: Motor temperature monitoring (KTY)			
Setting range (min. value unit max. value)			
0	°C	250	
Subcodes	Lenze setting	Info	
C00121/1	120 °C	Warning threshold motor temperature resolver	
C00121/2	120 °C	Warning threshold motor temperature MultiEncoder	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00122

Parameter Name: C00122 Initial value motor overload (I²xt)			Data type: UNSIGNED_16 Index: 24453 _d = 5F85 _h		
From version 12.00.00 The thermal motor load displayed in C00066 is pre-initialised with the value set here when the device is connected to the mains. <ul style="list-style-type: none">• If "100.00 %" is set, the last value at switching off the device is used for the initialisation.• Recommended setting for operation according to UL: 50.00 % <div>▶ Motor overload monitoring (I2xt)</div>					
Setting range (min. value unit max. value)					
0.00	%	100.00			
Subcodes		Lenze setting	Info		
C00122/1		0.00 %	Initial value motor overload (I²xt)		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT <input type="checkbox"/> Scaling factor: 100</div>					

C00123

Parameter Name: C00123 Device utilisation threshold (Ixt)			Data type: INTEGER_16 Index: 24452 _d = 5F84 _h
Operating threshold for the "OC5: Device overload (Ixt)" error message <ul style="list-style-type: none">• The response for reaching the threshold can be selected in C00604.• The current device utilisation is displayed in C00064.			
Setting range (min. value unit max. value)			Lenze setting
0.00	%	200.00	100.00 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT			Scaling factor: 100

C00129

Parameter Name: C00129 Brake resistance value			Data type: UNSIGNED_16 Index: 24446 _d = 5F7E _h		
Resistance value of the connected brake resistor					
• The value to be entered can be obtained from the nameplate of the brake resistor.					
Setting range (min. value unit max. value)			Lenze setting		
0.0	Ohm	500.0	39.0 Ohm		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C00130

Parameter Name: C00130 Rated power - brake resistor			Data type: UNSIGNED_16 Index: 24445 _d = 5F7D _h
Rated power of the connected brake resistor • The value to be entered can be obtained from the nameplate of the brake resistor.			
Setting range (min. value unit max. value)			Lenze setting
0	W	65535	100 W
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00131

Parameter Name: C00131 Rated heat amount of brake resist.			Data type: UNSIGNED_16 Index: 24444 _d = 5F7C _h
Thermal capacity of the connected brake resistor • The value to be entered can be obtained from the nameplate of the brake resistor.			
Setting range (min. value unit max. value)			Lenze setting
0.0	kWs	6553.5	10.0 kWs
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10			

C00133

Parameter Name: C00133 Brake resistor utilisation			Data type: UNSIGNED_16 Index: 24442 _d = 5F7A _h
Display of the utilisation of the connected brake resistor			
Display range (min. value unit max. value)			
0	%	65535	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00134

Parameter Name: C00134 L_NSet_1: Ramp smoothing			Data type: UNSIGNED_8 Index: 24441 _d = 5F79 _h
The L_NSet_1 FB: Configuration of the ramp rounding for the main setpoint			
Selection list (Lenze setting printed in bold)			Info
0	Off		Ramp rounding deactivated
1	PT1 behaviour		Ramp rounding with PT1 behaviour • The corresponding S-ramp time must be set in C00182 .
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00136

Parameter Name: C00136 Communication control words			Data type: UNSIGNED_16 Index: 24439 _d = 5F77 _h		
Control words of the communication interfaces					
Display area (min. hex value max. hex value)					
0x0000		0xFFFF			
Value is bit-coded:					
Bit 0	SwitchOn				
Bit 1	DisableVoltage				
Bit 2	SetQuickStop				
Bit 3	EnableOperation				
Bit 4	ModeSpecific_1				
Bit 5	ModeSpecific_2				
Bit 6	ModeSpecific_3				
Bit 7	ResetFault				
Bit 8	SetHalt				
Bit 9	Reserved_1				
Bit 10	Reserved_2				
Bit 11	LenzeSpecific_1				
Bit 12	LenzeSpecific_2				
Bit 13	LenzeSpecific_3				
Bit 14	SetFail				
Bit 15	LenzeSpecific_4				
Subcodes			Info		
C00136/1			MCI control word <ul style="list-style-type: none">Control word of the MCI communication interface (communication module)		
C00136/2			CAN control word <ul style="list-style-type: none">Control word of the CAN communication interface (CAN on board)		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT					

C00137

Parameter | Name: **C00137 | Device status**

Data type: UNSIGNED_16
Index: 24438_d = 5F76_h

Display of the current device status

Selection list (read only)	
0	FirmwareUpdate
1	Init
2	Ident
3	ReadyToSwitchON
4	SwitchedON
5	OperationEnable
6	Warning
7	Trouble
8	Fault
9	TroubleQSP
10	SafeTorqueOff
11	SystemFail
12	Reserved_1
13	Reserved_2
14	Reserved_3
15	Reserved_4

☒ Read access ☐ Write access ☐ CINH ☐ PLC STOP ☒ No transfer ☐ COM ☐ MOT Scaling factor: 1

C00138

Parameter Name:			Data type: UNSIGNED_16 Index: 24437 _d = 5F75 _h		
C00138 Internal control signals					
Bit coded display of internal control signals of different sources					
Display area (min. hex value max. hex value)					
0x0000		0xFFFF			
Value is bit-coded:					
Bit 0	Reserved				
Bit 1	DisableVoltage				
Bit 2	SetQuickStop				
Bit 3	EnableOperation				
Bit 4	InitFinishedOK				
Bit 5	ModeSpecific_2				
Bit 6	ModeSpecific_3				
Bit 7	ResetFault				
Bit 8	SetHalt				
Bit 9	FirmwareUpdate				
Bit 10	MotorIdent				
Bit 11	SetMessage				
Bit 12	SetIMP				
Bit 13	SetSystemFail				
Bit 14	SetFail				
Bit 15	SetFailQSP				
Subcodes			Info		
C00138/1			SYS control signals		
C00138/2			MCK control signals		
C00138/3			FWM control signals		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT					

C00142

Parameter | Name: C00142 | Auto-start option

Data type: UNSIGNED_8
Index: 24433_d = 5F71_h

Starting performance of the controller after mains connection, undervoltage, loading of the Lenze setting as well as a reset of "Trouble" or "Fault" can be parameterised individually.

▶ [Automatic restart after mains connection/fault...](#)

Setting range (min. hex value max. hex value)			Lenze setting
0x00		0xFF	0x19 (decimal: 25)
Value is bit-coded: (☑ = bit set)			
Bit 0 ☑	Inhibit at power-on		
Bit 1 ☐	Inhibit at trouble		
Bit 2 ☐	Inhibit at fault		
Bit 3 ☑	Inhibit at undervoltage		
Bit 4 ☑	Inhibit at Lenze setting		
Bit 5 ☐	Reserved		
Bit 6 ☐	Reserved		
Bit 7 ☐	Reserved		

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT

C00144

Parameter Name: C00144 Switching freq. reduct. (Temp.)		Data type: UNSIGNED_8 Index: 24431 _d = 5F6F _h	
Activation of the automatic switching frequency reduction if the temperature is too high			
Selection list (Lenze setting printed in bold)		Info	
0	Off	Automatic switching frequency reduction deactivated	
1	On	Automatic switching frequency reduction activated	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00148

Parameter | Name: C00148 | LS_DriveInterface: Error message config.

Data type: UNSIGNED_16
Index: 24427_d = 5F6B_h

Selection of the device statuses for which the *bCollectedFail* group error output of SB [LS_DriveInterface](#) is to be set to TRUE.

Setting range (min. hex value max. hex value)		Lenze setting
0x0000	0xFFFF	0x0030 (decimal: 48)
Value is bit-coded: (☑ = bit set)		Info
Bit 0 ☐	SafeTorqueOff	
Bit 1 ☐	ReadyToSwitchOn	
Bit 2 ☐	SwitchedOn	
Bit 3 ☐	TroubleQSP	
Bit 4 ☑	Trouble	
Bit 5 ☑	Fault	
Bit 6 ☐	Warning	
Bit 7 ☐	ImplsActive	
Bit 8 ☐	CInHlsActive	
Bit 9 ☐	Fail CAN_Management	
Bit 10 ☐	Reserved	
Bit 11 ☐	Reserved	
Bit 12 ☐	Reserved	
Bit 13 ☐	Reserved	
Bit 14 ☐	Lock bFail at TroubleQSP	From version 02.00.00 1 ≡ The <i>bFail</i> output of the SB LS_DriveInterface is also set in the "TroubleQSP" status. <ul style="list-style-type: none">• Advantage: Even in the "TroubleQSP" status, an error occurred before can still be recognised.
Bit 15 ☐	Use 16BitFailNo.	1 ≡ The short 16-bit error number <i>wStateDetermFailNoShort</i> is provided at the <i>wStateDetermFailNoLow</i> output of the SB LS_DriveInterface . <ul style="list-style-type: none">• In this case, the <i>wStateDetermFailNoHigh</i> output is "0".• Advantage: The bus transfer of the error numbers is possible via a data word without changing the interconnection of the technology application.

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT

C00150

Parameter Name: C00150 Status word			Data type: UNSIGNED_16 Index: 24425 _d = 5F69 _h
Bit coded device status word			
Display area (min. hex value max. hex value)			
0x0000		0xFFFF	
Value is bit-coded:			Info
Bit 0	FreeStatus	Free status bit 0	
Bit 1	PowerDisabled	Power switched off	
Bit 2	FreeStatus	Free status bit 2	
Bit 3	FreeStatus	Free status bit 3	
Bit 4	FreeStatus	Free status bit 4	
Bit 5	FreeStatus	Free status bit 5	
Bit 6	ActSpeedIsZero	Current speed is 0	
Bit 7	ControllerInhibit	Controller is inhibited	
Bit 8	StatusCodeBit0	Status code bit 0	
Bit 9	StatusCodeBit1	Status code bit 1	
Bit 10	StatusCodeBit2	Status code bit 2	
Bit 11	StatusCodeBit3	Status code bit 3	
Bit 12	Warning	Warning	
Bit 13	Trouble	Trouble	
Bit 14	FreeStatus	Free status bit 14	
Bit 15	FreeStatus	Free status bit 15	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT			

C00155

Parameter Name:		Data type: UNSIGNED_16 Index: 24420 _d = 5F64 _h	
C00155 Extended status word			
Bit coded device status word 2			
Display area (min. hex value max. hex value)			
0x0000			
Value is bit-coded:		Info	
Bit 0	Fail	Fault	
Bit 1	M_max	Maximum torque	
Bit 2	I_max	Maximum current	
Bit 3	PowerDisabled	Power switched off	
Bit 4	Ready	Controller is ready for operation	
Bit 5	ControllerInhibit	Controller is inhibited	
Bit 6	Trouble	Trouble	
Bit 7	InitState	Initialisation	
Bit 8	CwCcw	CW/CCW rotation	
Bit 9	TroubleQSP	Quick stop due to fault is active	
Bit 10	SafeTorqueOff	Safe torque off	
Bit 11	AplicationRunning	Application is running	
Bit 12	AplParSetBit0	Application parameter set - bit 0	
Bit 13	AplParSetBit1	Application parameter set - bit 1	
Bit 14	Quick stop	Quick stop active	
Bit 15	Motor parameter identification	Motor parameter identification is active	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT			

C00158

Parameter Name:		Data type: UNSIGNED_16 Index: 24417 _d = 5F61 _h	
C00158 Cause of controller inhibit			
Bit coded display of the cause/source of the controller inhibit			
Display area (min. hex value max. hex value)			
0x0000		0xFFFF	
Value is bit-coded:			
Bit 0	Terminal controller enable		
Bit 1	CAN control word		
Bit 2	MCI control word		
Bit 3	SwitchOn		
Bit 4	Application		
Bit 5	Device command		
Bit 6	Error response		
Bit 7	Internal signal		
Bit 8	Reserved		
Bit 9	Reserved		
Bit 10	AutoStartLock		
Bit 11	Motor parameter identification		
Bit 12	Automatic brake operation		
Bit 13	DCB-IMP		
Bit 14	Reserved		
Bit 15	Reserved		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT			

C00159

Parameter Name: C00159 Cause of quick stop QSP		Data type: UNSIGNED_16 Index: 24416 _d = 5F60 _h	
Bit coded display of the cause/source of the quick stop			
Display area (min. hex value max. hex value)			
0x0000		0xFFFF	
Value is bit-coded:			
Bit 0	Reserved		
Bit 1	CAN control word		
Bit 2	MCI control word		
Bit 3	Reserved		
Bit 4	Application		
Bit 5	Device command		
Bit 6	Error response		
Bit 7	Internal signal		
Bit 8	Reserved		
Bit 9	Reserved		
Bit 10	Operating system		
Bit 11	Reserved		
Bit 12	MCK		
Bit 13	Reserved		
Bit 14	Reserved		
Bit 15	Reserved		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT			

C00160

Parameter Name: C00160 Status determining error (16bit)			Data type: UNSIGNED_16 Index: 24415 _d = 5F5F _h		
Display of the short 16-bit error number of the status determining error					
► Structure of the 16-bit error number (bit coding)					
Display range (min. value unit max. value)					
0		65535			
Subcodes			Info		
C00160/1			Status determining error (16-bit)		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00161

Parameter Name: C00161 LS_SetError_x: Error number			Data type: UNSIGNED_16 Index: 24414 _d = 5F5E _h
Setting of the error number for user error messages			
Setting range (min. value unit max. value)			
0		65535	
Subcodes	Lenze setting	Info	
C00161/1	1	LS_SetError_1 : Error no.1	
C00161/2	2	LS_SetError_1 : Error no.2	
C00161/3	3	LS_SetError_1 : Error no.3	
C00161/4	4	LS_SetError_1 : Error no.4	
C00161/5	1	LS_SetError_2 : Error no.1	
C00161/6	2	LS_SetError_2 : Error no.2	
C00161/7	3	LS_SetError_2 : Error no.3	
C00161/8	4	LS_SetError_2 : Error no.4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00162

Parameter Name: C00162 Error number masked			Data type: UNSIGNED_32 Index: 24413 _d = 5F5D _h		
From version 13.00.00					
Display of the 32-bit error number of the status determining error without error type					
• The error number displayed here only contains the error subject area and error ID (lower 26 bits of the 32-bit error number)					
► Structure of the 32-bit error number (bit coding)					
Display range (min. value unit max. value)					
0		4294967295			
Subcodes			Info		
C00162/1			Subject area + Id statuserror		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00163

Parameter Name: C00163 Logbook - binary elements			Data type: UNSIGNED_16 Index: 24412 _d = 5F5C _h
Selection of two binary signals to be logged in the logbook			
Selection list	Info		
0	No signal		
1	DI1: Input signal		
2	DI2: Input signal		
3	DI3: Input signal		
4	DI4: Input signal		
5	Controller inhibit signal		
6	Digital counter: Comparison bit		
7	CAN1 input bit 0		
8	CAN1 input bit 1		
9	CAN1 input bit 2		
10	CAN1 input bit 3		

Parameter Name: C00163 Logbook - binary elements		Data type: UNSIGNED_16 Index: 24412 _d = 5F5C _h
11	CAN1 input bit 4	
12	CAN1 input bit 5	
13	CAN1 input bit 6	
14	CAN1 input bit 7	
15	CAN1 input bit 8	
16	CAN1 input bit 9	
17	CAN1 input bit 10	
18	CAN1 input bit 11	
19	CAN1 input bit 12	
20	CAN1 input bit 13	
21	CAN1 input bit 14	
22	CAN1 input bit 15	
23	CAN2 input bit 0	
24	CAN2 input bit 1	
25	CAN2 input bit 2	
26	CAN2 input bit 3	
27	CAN2 input bit 4	
28	CAN2 input bit 5	
29	CAN2 input bit 6	
30	CAN2 input bit 7	
31	CAN2 input bit 8	
32	CAN2 input bit 9	
33	CAN2 input bit 10	
34	CAN2 input bit 11	
35	CAN2 input bit 12	
36	CAN2 input bit 13	
37	CAN2 input bit 14	
38	CAN2 input bit 15	
39	CAN3 input bit 0	
40	CAN3 input bit 1	
41	CAN3 input bit 2	
42	CAN3 input bit 3	
43	CAN3 input bit 4	
44	CAN3 input bit 5	
45	CAN3 input bit 6	
46	CAN3 input bit 7	
47	CAN3 input bit 8	
48	CAN3 input bit 9	
49	CAN3 input bit 10	
50	CAN3 input bit 11	
51	CAN3 input bit 12	
52	CAN3 input bit 13	
53	CAN3 input bit 14	
54	CAN3 input bit 15	

Parameter Name: C00163 Logbook - binary elements		Data type: UNSIGNED_16 Index: 24412 _d = 5F5C _h
55	MCI word1 input bit0	
56	MCI word1 input bit1	
57	MCI word1 input bit2	
58	MCI word1 input bit3	
59	MCI Word 1 Input bit 4	
60	MCI word1 input bit5	
61	MCI word1 input bit6	
62	MCI word1 input bit7	
63	MCI word1 input bit8	
64	MCI word1 input bit9	
65	MCI word1 input bit10	
66	MCI word1 input bit11	
67	MCI word1 input bit12	
68	MCI word1 input bit13	
69	MCI word1 input bit14	
70	MCI word1 input bit15	
71	MCI word2 input bit0	
72	MCI word2 input bit1	
73	MCI Word 2 Input bit 2	
74	MCI word2 input bit3	
75	MCI word2 input bit4	
76	MCI word2 input bit5	
77	MCI word2 input bit6	
78	MCI word 2 input bit 7	
79	MCI word2 input bit8	
80	MCI word2 input bit9	
81	MCI word2 input bit10	
82	MCI word2 input bit11	
83	MCI Word 2 Input bit 12	
84	MCI word2 input bit13	
85	MCI word2 input bit14	
86	MCI word2 input bit15	
87	Position controller: Limit	
88	Speed controller: Limit	
89	Speed setpoint: Limit	
90	Torque setpoint: Limit	
91	Current setpoint: Limit	
92	DC injection brake active	
93	Quick stop active	
94	Pulse inhibit active	
95	Controller inhibit active	
96	Safe status active	
97	Direction of rotation ccw	
98	Actual speed = 0	

Parameter Name: C00163 Logbook - binary elements		Data type: UNSIGNED_16 Index: 24412 _d = 5F5C _h
99	L_Or_1: Out	
100	L_DFlipFlop_1: Out	
101	L_DigitalDelay_1: Out	
102	L_Compare_1: Out	
103	L_Compare_2: Out	
104	L_NSet_1: Setpoint reached	
105	L_DigitalLogic_1: Out	
106	L_SignalMonitor_b: Out1	
107	L_SignalMonitor_b: Out2	
108	L_SignalMonitor_b: Out3	
109	L_SignalMonitor_b: Out4	
110	L_PCTRL_1: act=set	
Subcodes	Lenze setting	Info
C00163/1	0: No signal	Logbook - binary element 1
C00163/2	0: No signal	Logbook - binary element 2
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00164

Parameter Name: C00164 Logbook - analog elements		Data type: UNSIGNED_16 Index: 24411 _d = 5F5B _h
Selection of an analog signal to be logged in the logbook		
Selection list		Info
0	No signal	
1	AIN1	
2	CAN1 control word	
3	CAN1 input word 2	
4	CAN1 input word 3	
5	CAN1 input word 4	
6	CAN2 input word 1	
7	CAN2 input word 2	
8	CAN2 input word 3	
9	CAN2 input word 4	
10	CAN3 input word 1	
11	CAN3 input word 2	
12	CAN3 input word 3	
13	CAN3 input word 4	
14	Digital counter LowWord	
15	Digital counter HighWord	
16	MCI word 1	
17	MCI word 2	
18	MCI word 3	
19	MCI word 4	
20	MCI word 5	
21	MCI word 6	

Parameter Name: C00164 Logbook - analog elements		Data type: UNSIGNED_16 Index: 24411 _d = 5F5B _h
22	MCI word 7	
23	MCI word 8	
24	MCI word 9	
25	MCI word 10	
26	MCI word 11	
27	MCI word 12	
28	MCI word 13	
29	MCI word 14	
30	MCI word 15	
31	MCI word 16	
32	Current motor speed	
33	Current motor torque	
34	DC-bus voltage	
35	Current motor current	
36	Current motor voltage	
37	Current motor frequency	
38	Effective speed setpoint	
39	Device utilisation	
40	Motor utilisation	
41	L_OffsetGainPar_1: Out	
42	L_OffsetGainPar_2: Out	
43	L_OffsetGainPar_3: Out	
44	L_Arithmetik_1: Out	
45	L_AnalogSwitch_1: Out	
46	L_NSet_1: Out	
47	L_MotorPoti_1: Out	
48	L_PCTRL_1: Out	
49	L_SignalMonitor_a: Out1	
50	L_SignalMonitor_a: Out2	
51	L_SignalMonitor_a: Out3	
52	L_SignalMonitor_a: Out4	
53	L_MulDiv_1: Out	
54	L_NSet_1: Target setpoint	
Subcodes	Lenze setting	Info
C00164/1	0: No signal	Logbook - analog element 1
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00165

Parameter Name: C00165 Error information		Data type: VISIBLE_STRING Index: 24410 _d = 5F5A _h
Display of the error number divided into sectors in the event of an error		
Subcodes		Info
C00165/1		Status determining error
C00165/2		Current error
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC-STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Character length: 14		

C00166

Parameter Name: C00166 Error information text		Data type: VISIBLE_STRING Index: 24409 _d = 5F59 _h
Display of details on the status determining error and on the currently pending error		
Subcodes	Info	
C00166/1	Resp. to status det. error • Response to the status determining error	
C00166/2	Subj. - status det. error • Subject area of the status determining error	
C00166/3	Mess. - status det. error • Textual message of the status determining error	
C00166/4	Resp. to curr. error • Response of the currently pending error	
C00166/5	Subj. - curr. error • Subject area of the currently pending error	
C00166/6	Mess. - curr. error • Textual message of the currently pending error	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC-STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Character length: 31		

C00167

Parameter Name: C00167 Logbook data		Data type: OCTET_STRING Index: 24408 _d = 5F58 _h
This code is for device-internal use only and must not be written to by the user!		

C00168

Parameter Name: C00168 Status determining error		Data type: UNSIGNED_32 Index: 24407 _d = 5F57 _h
Display of the 32-bit error number of the status determining error ▶ Structure of the 32-bit error number (bit coding)		
Display range (min. value unit max. value)		
0		4294967295
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00169

Parameter Name: C00169 Logbook setting		Data type: UNSIGNED_16 Index: 24406 _d = 5F56 _h	
Configuration which message types are to be logged in the logbook.			
Setting range (min. hex value max. hex value)		Lenze setting	
0x0000		0xFFFF	0x067E (decimal: 1662)
Value is bit-coded: (<input checked="" type="checkbox"/> = bit set)			
Bit 0 <input type="checkbox"/>	Reserved		
Bit 1 <input checked="" type="checkbox"/>	Log entry: Fault		
Bit 2 <input checked="" type="checkbox"/>	Log entry: Trouble		
Bit 3 <input checked="" type="checkbox"/>	Log entry: TroubleQuickstop		
Bit 4 <input checked="" type="checkbox"/>	Log entry: WarningLocked		
Bit 5 <input checked="" type="checkbox"/>	Log entry: Warning		
Bit 6 <input checked="" type="checkbox"/>	Log entry: Information		
Bit 7 <input type="checkbox"/>	Reserved		
Bit 8 <input type="checkbox"/>	Reserved		
Bit 9 <input checked="" type="checkbox"/>	Activation: Error counter		
Bit 10 <input checked="" type="checkbox"/>	Activation: Log line refresh		
Bit 11 <input type="checkbox"/>	Reserved		
Bit 12 <input type="checkbox"/>	Reserved		
Bit 13 <input type="checkbox"/>	Reserved		
Bit 14 <input type="checkbox"/>	Reserved		
Bit 15 <input type="checkbox"/>	Reserved		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT			

C00170

Parameter Name: C00170 Current error		Data type: UNSIGNED_32 Index: 24405 _d = 5F55 _h	
Display of the internal error number of the currently pending error			
Display range (min. value unit max. value)			
0		4294967295	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00171

Parameter Name: C00171 Logbook access index		Data type: UNSIGNED_8 Index: 24404 _d = 5F54 _h	
This code is for device-internal use only and must not be written to by the user!			

C00173

Parameter Name: C00173 Mains voltage		Data type: UNSIGNED_8 Index: 24402 _d = 5F52 _h
If the rated mains voltage differs from 230 V or 400 V, set the mains voltage the drive is operated with. The set mains voltage influences the brake chopper threshold, the monitoring of the device utilisation (Ixt) and the switch-off threshold in case of undervoltage in the DC bus.		
Selection list (Lenze setting printed in bold)		Info
0	3ph 400V / 1ph 230V	3-phase 400 V or 1-phase 230 V
1	3ph 440V / 1ph 230V	3-phase 440 V or 1-phase 230 V
2	3ph 480V / 1ph 230V	3-phase 480 V or 1-phase 230 V
3	3ph 500V / 1ph 230V	3-phase 500 V or 1-phase 230 V
4	Reserved / reserved	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input checked="" type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00174

Parameter Name: C00174 Reduc. brake chopper threshold		Data type: UNSIGNED_8 Index: 24401 _d = 5F51 _h
The threshold from which on the brake chopper is controlled is reduced by the voltage value set here.		
Setting range (min. value unit max. value)		Lenze setting
0	V	150
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00175

Parameter Name: C00175 Brake energy management		Data type: UNSIGNED_8 Index: 24400 _d = 5F50 _h
Selection of the braking procedure		
Select response if the brake resistor is controlled		
Selection list (Lenze setting printed in bold)		Info
0	R_Brems	The brake resistor is used. When the threshold voltage (C00174) is exceeded, the brake resistor is energised.
1	RfgStop	The "Ramp function generator stop" signal (<i>MCTRL_brfgStop</i>) is used. When the threshold voltage is exceeded (C00174), the ramp function generator is stopped.
2	R_Brems + HlgStop	The brake resistor and the "Ramp function generator stop" signal are used. When the threshold voltage is exceeded (C00174), the brake resistor is energised and the ramp function generator is stopped.
3	FI_MotBrk + RfgStop	Braking is performed by a superimposed speed setpoint vibration in conjunction with "Ramp function generator stop".
4	R_Brems + FU_MotBrk + HlgStop	Braking is performed by combining all three braking procedures.
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input checked="" type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00176

Parameter Name: C00176 Undervoltage threshold for mains OFF		Data type: UNSIGNED_16 Index: 24399 _d = 5F4F _h
This code is for device-internal use only and must not be written to by the user!		

C00177

Parameter Name: C00177 Switching cycles			Data type: UNSIGNED_32 Index: 24398 _d = 5F4E _h		
Counter of different switching cycles and stressful situations					
Display range (min. value unit max. value)					
0		2147483647			
Subcodes			Info		
C00177/1			Number of mains switching cycles		
C00177/2			Number of switching cycles of the output relay		
C00177/3			Short circuit counter		
C00177/4			Earth fault counter		
C00177/5			"Clamp" counter		
C00177/6			Counter for "safe torque off" (STO) after power-on • From version 12.00.00		
C00177/7			Counter for controller inhibit via terminal after power-on • From version 12.00.00		
C00177/8			Counter for pulse inhibit (IMP) after power-on • From version 12.00.00		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00178

Parameter Name: C00178 Elapsed-hour meter			Data type: UNSIGNED_32 Index: 24397 _d = 5F4D _h		
Display of operating hours in seconds					
Display range (min. value unit max. value)					
0	s	2147483647			
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00179

Parameter Name: C00179 Power-on time meter			Data type: UNSIGNED_32 Index: 24396 _d = 5F4C _h		
Display of the power-on time in seconds					
Display range (min. value unit max. value)					
0	s	2147483647			
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00180

Parameter Name: C00180 Running time			Data type: UNSIGNED_32 Index: 24395 _d = 5F4B _h		
Display of various running times in seconds					
Display range (min. value unit max. value)					
0	s	2147483647			
Subcodes			Info		
C00180/1			Running time - control card		
C00180/2			Running time - heatsink fan		
C00180/3			Running time - internal fan		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00181

Parameter Name: C00181 Time settings			Data type: UNSIGNED_16 Index: 24394 _d = 5F4A _h		
Time for device search function (optical location)					
<div>▶ Device search function</div>					
Setting range (min. value unit max. value)					
0	s	6000			
Subcodes	Lenze setting		Info		
C00181/1	5 s		Time - device search function		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>					

C00182

Parameter Name: C00182 L_NSet_1: S-ramp time PT1			Data type: INTEGER_16 Index: 24393 _d = 5F49 _h		
FB L_NSet_1 : PT1 S-ramp time for the main setpoint ramp function generator • Only effective with activated ramp rounding (C00134 = "1").					
Setting range (min. value unit max. value)			Lenze setting		
0.01	s	50.00	20.00 s		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00184

Parameter Name:			Data type: UNSIGNED_16 Index: 24391 _d = 5F47 _h		
C00184 AutoFailReset repetition time					
After the time set here has expired, an error message of an error that has occurred will be reset automatically if "AutoFailReset" had been configured correspondingly in C00188 .					
<div>▶ AutoFailReset function</div>					
Setting range (min. value unit max. value)				Lenze setting	
1	s	600	3 s		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00185

Parameter Name:			Data type: UNSIGNED_16 Index: 24390 _d = 5F46 _h		
C00185 AutoFailReset remaining time					
Display of the residual runtime of the "AutoFailReset" function					
<div>▶ AutoFailReset function</div>					
Display range (min. value unit max. value)					
0	s	600			
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>					

C00186

Parameter Name: C00186 Max. number of AutoFailReset processes			Data type: UNSIGNED_8 Index: 24389 _d = 5F45 _h		
Maximum number of "AutoFailReset" procedures					
▶ AutoFailReset function					
Setting range (min. value unit max. value)			Lenze setting		
1		16	4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00187

Parameter Name: C00187 Current AutoFailReset processes		Data type: UNSIGNED_8 Index: 24388 _d = 5F44 _h	
Data of the current number of "AutoFailReset" procedures			
▶ AutoFailReset function			
Display range (min. value unit max. value)			
0		16	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00188

Parameter Name: C00188 AutoFailReset configuration		Data type: UNSIGNED_8 Index: 24387 _d = 5F43 _h	
Setting which error messages are to be reset automatically.			
▸ AutoFailReset function			
Selection list (Lenze setting printed in bold)		Info	
0	Off	No automatic error message reset	
1	Fault + TroubleQSP	Error messages with the response "Fault" and "TroubleQSP" are reset automatically	
2	WarningLocked	Error messages with the response "WarningLocked" are reset automatically	
3	All locking	All "locking" error messages are reset automatically	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00189

Parameter Name: C00189 Resp. to too frequent AutoFailReset		Data type: UNSIGNED_8 Index: 24386 _d = 5F42 _h	
Response to exceeding the maximum number of "AutoFailReset" processes set in C00186 . ▶ AutoFailReset function			
Selection list (Lenze setting printed in bold)			
0	No Reaction		
1	Fault		
2	Trouble		
3	TroubleQuickStop		
4	WarningLocked		
5	Warning		
6	Information		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00190

Parameter Name: C00190 L_NSet_1: Setpoint arithmetic		Data type: UNSIGNED_8 Index: 24385 _d = 5F41 _h	
The L_NSet_1 FB: Selection of arithmetics			
• To be able to influence the main setpoint (NSet) by an additional setpoint (NAdd).			
Selection list (Lenze setting printed in bold)			
0	Out = Set		
1	Out = Set + Add		
2	NOut = NSet - NAdd		
3	NOut = (NSet * NAdd) / 100%		
4	NOut = (NSet * 1%) / NAdd		
5	Out = (Set*100%)/(100%-Add)		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00191

Parameter Name: C00191 Logbook access index User			Data type: UNSIGNED_8 Index: 24384 _d = 5F40 _h	
From version 12.00.00				
<div>► Logbook read interface</div>				
Setting range (min. value unit max. value)				
0		255		
Subcodes	Lenze setting		Info	
C00191/1	255		Logbook access index User	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>				

C00192

Parameter Name: C00192 Logbook data User			Data type: OCTET_STRING Index: 24383 _d = 5F3F _h		
From version 12.00.00					
▸ Logbook read interface					
Display range (min. value unit max. value)					
Subcodes			Info		
C00192/1					
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT					

C00193

Parameter Name: C00193 Logbook element User			Data type: UNSIGNED_32 Index: 24382 _d = 5F3E _h		
From version 12.00.00					
<div>► Logbook read interface</div>					
Display range (min. value unit max. value)					
0		2147483647			
Subcodes				Info	
C00193/1				Response index	
C00193/2				Activity	
C00193/3				Counter	
C00193/4				Error type	
C00193/5				Error number	
C00193/6				Time stamp	
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>					

C00199

Parameter Name: C00199 Description data		Data type: VISIBLE_STRING Index: 24376 _d = 5F38 _h
Parameters for storing decription data for the controller		
<div>▸ Device identification</div>		
Subcodes	Lenze setting	Info
C00199/1		Device name
C00199/2		User text <ul style="list-style-type: none">• From version 12.00.00
C00199/3		User text <ul style="list-style-type: none">• From version 12.00.00
C00199/4		User text <ul style="list-style-type: none">• From version 12.00.00
C00199/5		User text <ul style="list-style-type: none">• From version 12.00.00
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC-STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Character length: 32</div>		

C00200

Parameter Name: C00200 Firmware product type							Data type: VISIBLE_STRING Index: 24375 _d = 5F37 _h	
Display of the firmware product type								
<input checked="" type="checkbox"/> Read access	<input type="checkbox"/> Write access	<input type="checkbox"/> CINH	<input type="checkbox"/> PLC-STOP	<input checked="" type="checkbox"/> No transfer	<input type="checkbox"/> COM	<input type="checkbox"/> MOT	Character length: 19	

C00201

Parameter Name: C00201 Firmware		Data type: VISIBLE_STRING Index: 24374 _d = 5F36 _h
Display of the firmware data of the control card and the power section		
Subcodes	Info	
C00201/1	Firmware type - ctrl card	
C00201/2	Firmware version - ctrl card	
C00201/3	Firmware comp. file - ctrl card	
C00201/4	Firmware type - power section	
C00201/5	Firmware version - power sect.	
C00201/6	Firmw. comp. file - power sect.	
C00201/7	Firmware type CU2	
C00201/8	Firmware version CU2	
C00201/9	Firmware comp. dat. CU2	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC-STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Character length: 22		

C00203

Parameter Name: C00203 Product type code		Data type: VISIBLE_STRING Index: 24372 _d = 5F34 _h
Display of the types of the individual device components		
Subcodes	Info	
C00203/1	Type: Control card	
C00203/2	Type: Power section	
C00203/3	Type: MCI module	
C00203/4	Reserved	
C00203/5	Type: Memory module	
C00203/6	Type: Safety card	
C00203/7	Type: Standard device	
C00203/8	Type: Complete device	
C00203/9	Reserved	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC-STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Character length: 24		

C00204

Parameter Name: C00204 Serial number		Data type: VISIBLE_STRING Index: 24371 _d = 5F33 _h
Display of the serial numbers of the individual device components		
Subcodes	Info	
C00204/1	Serial no.: Control card	
C00204/2	Serial no.: Power section	
C00204/3	Serial no.: MCI module	
C00204/4	Reserved	
C00204/5	Serial no.: Memory module	
C00204/6	Serial no.: Safety card	
C00204/7	Serial no.: Standard device	
C00204/8	Serial no.: Complete device	
C00204/9	Reserved	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC-STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Character length: 24		

C00205

Parameter Name: C00205 Info	Data type: VISIBLE_STRING Index: 24370 _d = 5F32 _h
This code is for device-internal use only and must not be written to by the user!	

C00206

Parameter Name: C00206 Production date	Data type: VISIBLE_STRING Index: 24369 _d = 5F31 _h
This code is for device-internal use only and must not be written to by the user!	

C00210

Parameter Name: C00210 HW version	Data type: VISIBLE_STRING Index: 24365 _d = 5F2D _h
This code is for device-internal use only and must not be written to by the user!	

C00219

Parameter Name: C00219 Identity			Data type: UNSIGNED_32 Index: 24356 _d = 5F24 _h	
From version 12.00.00				
Display range (min. value unit max. value)				
0		4294967295		
Subcodes			Info	
C00219/1			CAN manufacturer no.	
C00219/2			CAN device type	
C00219/3			CAN version	
C00219/4			CAN count no.	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1				

C00220

Parameter Name: C00220 L_NSet_1: Acceleration time - add. setpoint			Data type: UNSIGNED_32 Index: 24355 _d = 5F23 _h
The L_NSet_1 FB: Acceleration time for the additional setpoint <i>nNAdd_a</i>			
Setting range (min. value unit max. value)			Lenze setting
0.000	s	999.999	0.000 s
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C00221

Parameter Name: C00221 L_NSet_1: Deceleration time - add. setpoint			Data type: UNSIGNED_32 Index: 24354 _d = 5F22 _h
The L_NSet_1 FB: Deceleration time for the additional setpoint <i>nNAdd_a</i>			
Setting range (min. value unit max. value)			Lenze setting
0.000	s	999.999	0.000 s
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C00222

Parameter Name: C00222 L_PCTRL_1: Vp			Data type: INTEGER_16 Index: 24353 _d = 5F21 _h
The L_PCTRL_1 FB: Gain factor Vp for the PID process controller			
Setting range (min. value unit max. value)			Lenze setting
0.1		500.0	1.0
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10			

C00223

Parameter Name: C00223 L_PCTRL_1: Tn			Data type: UNSIGNED_16 Index: 24352 _d = 5F20 _h
The L_PCTRL_1 FB: Reset time Tn for the PID process controller			
Setting range (min. value unit max. value)			Lenze setting
20	ms	6000	400 ms
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00224

Parameter Name: C00224 L_PCTRL_1: Kd			Data type: UNSIGNED_16 Index: 24351 _d = 5F1F _h
The L_PCTRL_1 FB: Derivative-action coefficient Kd for the PID process controller			
Setting range (min. value unit max. value)			Lenze setting
0.0		5.0	0.0
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10			

C00225

Parameter Name: C00225 L_PCTRL_1: MaxLimit			Data type: INTEGER_16 Index: 24350 _d = 5F1E _h
The L_PCTRL_1 FB: Maximum output value of the PID process controller			
Setting range (min. value unit max. value)			Lenze setting
-199.99	%	199.99	199.99 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00226

Parameter Name: C00226 L_PCTRL_1: MinLimit			Data type: INTEGER_16 Index: 24349 _d = 5F1D _h
The L_PCTRL_1 FB: Minimum output value of the PID process controller			
Setting range (min. value unit max. value)			Lenze setting
-199.99	%	199.99	-199.99 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00227

Parameter Name: C00227 L_PCTRL_1: Acceleration time			Data type: UNSIGNED_32 Index: 24348 _d = 5F1C _h
The L_PCTRL_1 FB: Acceleration time for the output value of the PID process controller			
Setting range (min. value unit max. value)			Lenze setting
0.000	s	999.999	0.010 s
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C00228

Parameter Name: C00228 L_PCTRL_1: Deceleration time			Data type: UNSIGNED_32 Index: 24347 _d = 5F1B _h
The L_PCTRL_1 FB: Deceleration time for the output value of the PID process controller			
Setting range (min. value unit max. value)			Lenze setting
0.000	s	999.999	0.010 s
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C00231

Parameter Name: C00231 L_PCTRL_1: Operating range			Data type: INTEGER_16 Index: 24344 _d = 5F18 _h
The L_PCTRL_1 FB: Operating range for the PID process controller			
Setting range (min. value unit max. value)			
0.00	%	199.99	
Subcodes	Lenze setting	Info	
C00231/1	199.99 %	L_PCTRL_1 : Pos. maximum	
C00231/2	0.00 %	L_PCTRL_1 : Pos. minimum	
C00231/3	0.00 %	L_PCTRL_1 : Neg. minimum	
C00231/4	199.99 %	L_PCTRL_1 : Neg. maximum	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00233

Parameter Name: C00233 L_PCTRL_1: Root function		Data type: UNSIGNED_8 Index: 24342 _d = 5F16 _h	
The L_PCTRL_1 FB: Use of the root function at the actual value input			
Selection list (Lenze setting printed in bold)		Info	
0	Off	Root function inactive <ul style="list-style-type: none">The actual value <i>nAct_a</i> remains unchanged for further processing	
1	On	Root function active <ul style="list-style-type: none">The root is extracted of the actual value <i>nAct_a</i> for further processing	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00234

Parameter Name: C00234 Oscillation damping influence			Data type: UNSIGNED_16 Index: 24341 _d = 5F15 _h		
<div>► Oscillation damping</div>					
Setting range (min. value unit max. value)			Lenze setting		
0.00	%	250.00	5.00 %		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT <div>Scaling factor: 100</div></div>					

C00235

Parameter Name: C00235 Oscillation damping filter time			Data type: UNSIGNED_8 Index: 24340 _d = 5F14 _h	
<div>▸ Oscillation damping</div>				
Setting range (min. value unit max. value)			Lenze setting	
2	ms	250	32 ms	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT <div>Scaling factor: 1</div></div>				

C00236

Parameter Name: C00236 Field weakening oscillation damping			Data type: UNSIGNED_8 Index: 24339 _d = 5F13 _h	
Oscillation damping for idling machines				
<div>▸ Oscillation damping</div>				
Setting range (min. value unit max. value)			Lenze setting	
0		40	14	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT <div>Scaling factor: 1</div></div>				

C00241

Parameter Name: C00241 L_NSet_1: Hyst. NSet reached			Data type: INTEGER_16 Index: 24334 _d = 5F0E _h	
The L_NSet_1 FB: Hysteresis window for the zero detection of the speed output setpoint <ul style="list-style-type: none">The speed threshold for the zero detection is 1 %				
Setting range (min. value unit max. value)			Lenze setting	
0.00	%	100.00	0.50 %	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100				

C00242

Parameter Name: C00242 L_PCTRL_1: Operating mode		Data type: UNSIGNED_8 Index: 24333 _d = 5F0D _h
The L_PCTRL_1 FB: Selection of the operating mode		
<ul style="list-style-type: none"> Depending on the selection, the blue switches in the displayed signal flow are set accordingly in the Engineer on the Application parameters tab for the L_PCTRL_1 FB. 		
Selection list (Lenze setting printed in bold)		Info
0	Off	The input setpoint <i>nNSet_a</i> is output without any changes at the output <i>nOut_a</i> .
1	nNSet + nNSet_PID	<i>nNSet_a</i> and <i>nAct_a</i> are used as PID input values. The arriving <i>nNSet_a</i> is additively linked to the value output by the PID element.
2	nSet_PID	<i>nSet_a</i> and <i>nAct_a</i> are used as PID input values. The input <i>nNSet_a</i> is not considered.
3	nNSet_PID	<i>nNSet_a</i> and <i>nAct_a</i> are used as PID input values. The input <i>nSet_a</i> is not considered.
4	nNSet + nSet_PID	<i>nSet_a</i> and <i>nAct_a</i> are used as PID input values. The arriving <i>nNSet_a</i> setpoint is additively linked to the value output by the PID element.
5	nNSet nSet_PID	<i>nSet_a</i> and <i>nAct_a</i> are used as PID input values. The setpoint <i>nNSet_a</i> is output at the output <i>nOut_a</i> . The PID output value is output at the output <i>nPIDOut_a</i> .
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00243

Parameter Name: C00243 L_PCTRL_1: Acceleration time influence		Data type: UNSIGNED_32 Index: 24332 _d = 5F0C _h
The L_PCTRL_1 FB: Acceleration time for showing the PID output value		
Setting range (min. value unit max. value)		Lenze setting
0.000	s	999.999 5.000 s
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000		

C00244

Parameter Name: C00244 L_PCTRL_1: Deceleration time influence		Data type: UNSIGNED_32 Index: 24331 _d = 5F0B _h
The L_PCTRL_1 FB: Deceleration time for masking out the PID output value		
Setting range (min. value unit max. value)		Lenze setting
0.000	s	999.999 5.000 s
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000		

C00245

Parameter Name: C00245 L_PCTRL_1: PID output value		Data type: INTEGER_16 Index: 24330 _d = 5F0A _h
The L_PCTRL_1 FB: Display of the output value of the PID process controller		
Display range (min. value unit max. value)		
-199.99	%	199.99
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100		

C00246

Parameter Name: C00246 L_PCTRL_1: nAct_a internal			Data type: INTEGER_16 Index: 24329 _d = 5F09 _h		
FB <u>L_PCTRL_1</u> : Display of the internal actual value					
Display range (min. value unit max. value)					
-199.99	%	199.99			
<input checked="" type="checkbox"/> Read access			<input type="checkbox"/> Write access		
<input type="checkbox"/> CINH			<input type="checkbox"/> PLC STOP		
<input type="checkbox"/> No transfer			<input type="checkbox"/> COM		
<input type="checkbox"/> MOT			Scaling factor: 100		

C00247

Parameter Name: C00247 L_PCTRL_1: Window setpoint reached			Data type: INTEGER_16 Index: 24328 _d = 5F08 _h		
FB <u>L_PCTRL_1</u> : Window for comparison operation "actual value = setpoint"					
Setting range (min. value unit max. value)			Lenze setting		
0.00	%	100.00	2.00 %		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00249

Parameter Name: C00249 L_PT1_1: Time constant			Data type: UNSIGNED_16 Index: 24326 _d = 5F06 _h		
FB L_PT1_1 : Time constant Tn					
Setting range (min. value unit max. value)			Lenze setting		
0	ms	5000	2000 ms		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00250

Parameter Name: C00250 L_PT1 2-3: Time constant			Data type: INTEGER_16 Index: 24325 _d = 5F05 _h		
Setting range (min. value unit max. value)					
0	ms	5000			
Subcodes	Lenze setting		Info		
C00250/1	2000 ms		L_PT1_2 : Time constant		
C00250/2	2000 ms		L_PT1_3 : Time constant		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00251

Parameter Name: C00251 L_DT1_1: Time constant			Data type: INTEGER_16 Index: 24324 _d = 5F04 _h		
FB L_DT1_1 : Time constant Tn					
Setting range (min. value unit max. value)			Lenze setting		
10	ms	5000	1000 ms		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00252

Parameter Name: C00252 L_DT1_1: Gain			Data type: INTEGER_16 Index: 24323 _d = 5F03 _h
FB L_DT1_1 : Gain factor Vp			
Setting range (min. value unit max. value)			Lenze setting
-320.00		320.00	1.00
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00253

Parameter Name: C00253 L_DT1_1: Sensitivity			Data type: UNSIGNED_8 Index: 24322 _d = 5F02 _h
FB L_DT1_1 : Selection of sensitivity			
<ul style="list-style-type: none"> Depending on the selection, the number of indicated higher-order bits is evaluated. 			
Note:			
The most significant bit determines the sign of the value, the remaining bits determine the numerical value.			
Selection list (Lenze setting printed in bold)			Info
1	15 bits		Bit 0 ... bit 14 are evaluated
2	14 bits		Bit 0 ... bit 13 are evaluated
3	13 bits		Bit 0 ... bit 12 are evaluated
4	12 bits		Bit 0 ... bit 11 are evaluated
5	11 Bit		Bit 0 ... bit 10 are evaluated
6	10 Bit		Bit 0 ... bit 9 are evaluated
7	9 Bit		Bit 0 ... bit 8 are evaluated
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00254

Parameter Name: C00254 Kp position controller			Data type: UNSIGNED_16 Index: 24321 _d = 5F01 _h
Gain for following error compensation			
Setting range (min. value unit max. value)			Lenze setting
0.00	1/s	500.00	5.00 1/s
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C00265

Parameter Name: C00265 SLVC: Tn torque controller			Data type: UNSIGNED_8 Index: 24310 _d = 5EF6 _h
This code is for device-internal use only and must not be written to by the user!			

C00270

Parameter Name: C00270 SC: Freq. current setpoint filter			Data type: UNSIGNED_16 Index: 24305 _d = 5EF1 _h
Frequency to be inhibited by the current setpoint filter at servo control (SC) and sensorless control for synchronous motors (SLPSM).			
Setting range (min. value unit max. value)			Lenze setting
40.0	Hz	1000.0	200.0 Hz
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10			

C00271

Parameter Name: C00271 SC: Width of current setpoint filter			Data type: UNSIGNED_16 Index: 24304 _d = 5EF0 _h		
Frequency width of the current setpoint filter at servo control (SC) and sensorless control for synchronous motors (SLPSM) • Width around the frequency to be inhibited (C00270).					
Setting range (min. value unit max. value)			Lenze setting		
0.0	Hz	500.0	0.0 Hz		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C00272

Parameter Name: C00272 SC: Depth of current setpoint filter			Data type: UNSIGNED_16 Index: 24303 _d = 5EEF _h		
Damping of the current setpoint filter at servo control (SC) and sensorless control for synchronous motors (SLPSM)					
Setting range (min. value unit max. value)			Lenze setting		
0	dB	100	0 db		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C00273

Parameter Name:			Data type: UNSIGNED_32 Index: 24302 _d = 5EEF _h		
C00273 Moment of inertia motor					
Moment of inertia for setpoint feedforward control at servo control (SC) and sensorless vector control (SLVC)					
Setting range (min. value unit max. value)			Lenze setting		
0.00	kg cm^2	6000000.00	0.00 kg cm^2		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C00274

Parameter Name: C00274 SC: Max. change in acceleration			Data type: UNSIGNED_16 Index: 24301 _d = 5EED _h		
Limitation of the acceleration change at servo control (SC) and sensorless control for synchronous motors (SLPSM) • Setting in % of M_Nenn per ms.					
Setting range (min. value unit max. value)			Lenze setting		
0.0	%/ms	400.0	400.0 %/ms		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C00275

Parameter Name: C00275 Filter setpoint feedforward control			Data type: UNSIGNED_16 Index: 24300 _d = 5EECh		
Filter time of setpoint feedforward control at servo control (SC) and sensorless vector control (SLVC) • The setpoint feedforward control requires the entry of the moment of inertia in C00273 .					
Setting range (min. value unit max. value)			Lenze setting		
0.0	ms	1000.0	1.0 ms		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C00276

Parameter Name: C00276 SC: Max. output voltage			Data type: UNSIGNED_8 Index: 24299 _d = 5EEB _h	
Maximum output voltage at servo control (SC) • Regarding the current DC-bus voltage.				
Setting range (min. value unit max. value)			Lenze setting	
80	%	99	95 %	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1				

C00280

Parameter Name: C00280 SC: Filter time const. DC detection			Data type: UNSIGNED_16 Index: 24295 _d = 5EE7 _h	
Filter time constant for DC-bus voltage filtering • The filter time constant is e.g. used for field weakening control at servo control (SC).				
Setting range (min. value unit max. value)			Lenze setting	
1	ms	1000	25 ms	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1				

C00290

Parameter Name: C00290 RCOM error counter	Data type: UNSIGNED_16 Index: 24285 _d = 5EDD _h
This code is for device-internal use only and must not be written to by the user!	

C00291

Parameter Name: C00291 Error type RCOM	Data type: UNSIGNED_8 Index: 24284 _d = 5EDC _h
This code is for device-internal use only and must not be written to by the user!	

C00295

Parameter Name: C00295 savezcycle memory modul		Data type: INTEGER_32 Index: 24280 _d = 5ED8 _h
This code is for device-internal use only and must not be written to by the user!		

C00296

Parameter Name: C00296 ICOM error number		Data type: UNSIGNED_16 Index: 24279 _d = 5ED7 _h
This code is for device-internal use only and must not be written to by the user!		

C00297

Parameter Name:		Data type: UNSIGNED_8
C00297 Counter Receive Error Isr		Index: 24278 _d = 5ED6 _h
This code is for device-internal use only and must not be written to by the user!		

C00301

Parameter Name:	Data type: UNSIGNED_16 Index: 24274 _d = 5ED2 _h
C00301 DebugAccess	
This code is for device-internal use only and must not be written to by the user!	

C00302

Parameter Name:	Data type: UNSIGNED_8 Index: 24273 _d = 5ED1 _h
C00302 Internal Commands	
This code is for device-internal use only and must not be written to by the user!	

C00304

Parameter Name:	Data type: UNSIGNED_32 Index: 24271 _d = 5ECF _h
C00304 Password1	
This code is for device-internal use only and must not be written to by the user!	

C00305

Parameter Name:	Data type: UNSIGNED_32 Index: 24270 _d = 5ECF _h
C00305 Password2	
This code is for device-internal use only and must not be written to by the user!	

C00306

Parameter Name:	Data type: UNSIGNED_32 Index: 24269 _d = 5ECD _h
C00306 Debug address	
This code is for device-internal use only and must not be written to by the user!	

C00307

Parameter Name:	Data type: UNSIGNED_16 Index: 24268 _d = 5ECB _h
C00307 Debug value	
This code is for device-internal use only and must not be written to by the user!	

C00308

Parameter Name:	Data type: UNSIGNED_16 Index: 24267 _d = 5ECB _h
C00308 PartitionOffset	
This code is for device-internal use only and must not be written to by the user!	

C00309

Parameter Name:	Data type: UNSIGNED_8 Index: 24266 _d = 5ECA _h
C00309 PartitionSel	
This code is for device-internal use only and must not be written to by the user!	

C00310

Parameter Name:	Data type: UNSIGNED_16 Index: 24265 _d = 5EC9 _h
C00310 PartitionValue	
This code is for device-internal use only and must not be written to by the user!	

C00311

Parameter Name:	Data type: UNSIGNED_32 Index: 24264 _d = 5EC8 _h
C00311 Runtime measurement	
This code is for device-internal use only and must not be written to by the user!	

C00312

Parameter Name:	Data type: UNSIGNED_32 Index: 24263 _d = 5EC7 _h
C00312 System runtimes	
From version 02.00.00	
Setting range (min. value unit max. value)	
0.000	μs 1310.700
Subcodes	Lenze setting Info
C00312/1	0.000 μs System runtime reserve
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000	

C00313

Parameter Name:	Data type: UNSIGNED_8 Index: 24262 _d = 5EC6 _h
C00313 LS_DataAccess: Activation	
This code is for device-internal use only and must not be written to by the user!	

C00314

Parameter Name:	Data type: UNSIGNED_32 Index: 24261 _d = 5EC5 _h
C00314 LS_DataAccess: Address access	
This code is for device-internal use only and must not be written to by the user!	

C00315

Parameter Name:	Data type: UNSIGNED_32 Index: 24260 _d = 5EC4 _h
C00315 SystemFail-Adr	
This code is for device-internal use only and must not be written to by the user!	

C00316

Parameter Name:	Data type: UNSIGNED_16 Index: 24259 _d = 5EC3 _h
C00316 SystemFail-Info	
This code is for device-internal use only and must not be written to by the user!	

C00317

Parameter Name:	Data type: UNSIGNED_16 Index: 24258 _d = 5EC2 _h
C00317 WatchdogTimeMax	
This code is for device-internal use only and must not be written to by the user!	

C00320

Parameter Name:	Data type: UNSIGNED_32 Index: 24255 _d = 5EBF _h
C00320 Debug information	
This code is for device-internal use only and must not be written to by the user!	

C00321

Parameter Name: C00321 Main program runtime			Data type: UNSIGNED_16 Index: 24254 _d = 5EBE _h		
Display of the current and the maximum runtime of the main program in the controller					
Setting range (min. value unit max. value)					
0	ms	65535			
Subcodes	Lenze setting	Info			
C00321/1	0 ms	Curr. runtime of main program			
C00321/2	0 ms	Max. runtime of main program			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00322

Parameter | Name:

C00322 | Transmission mode CAN TxPDOs

Data type: UNSIGNED_8

Index: 24253_d = 5EBD_h

TPDO transmission type according to DS301 V4.02

• The following transmission modes are supported:

• 0: Synchronous and acyclic

• 1 ... 240: Synchronous and cyclic

• 252: Synchronous - RTR only

• 253: Asynchronous - RTR only

• 254: Asynchronous - manufacturer-specific

• 255: Asynchronous - device-profile specific

• The basic setting for all PDOs is "Asynchronous - manufacturer-specific" (254).

• Illustration of the CANopen objects [I-1800/2](#) ... [I-1803/2](#) (see DS301 V4.02).

▶ [System bus "CAN on board"](#)

Setting range (min. value | unit | max. value)

0

255

Subcodes

Lenze setting

Info

C00322/1

254

Transmission mode CAN1 OUT

C00322/2

254

Transmission mode CAN2 OUT

C00322/3

254

Transmission mode CAN3 OUT

C00322/4

254

Transmission mode CAN4 OUT

• [From version 15.00.00](#)

☒ Read access
☒ Write access
☐ CINH
☐ PLC STOP
☐ No transfer
☒ COM
☐ MOT
Scaling factor: 1

C00323

Parameter | Name:
C00323 | Transmission mode CAN Rx PDOs

Data type: UNSIGNED_8
Index: 24252_d = 5EBC_h

RPDO transmission type according to DS301 V4.02

- In the case of the RPDO serves as monitoring setting in the case of sync-controlled PDOs.
- The following transmission modes are supported:
 - 0: Synchronous and acyclic
 - 1 ... 240: Synchronous and cyclic
 - 252: Synchronous - RTR only
 - 253: Asynchronous - RTR only
 - 254: Asynchronous - manufacturer-specific
 - 255: Asynchronous - device-profile specific
- The basic setting for all PDOs is "Asynchronous - manufacturer-specific" (254).
- Illustration of the CANopen objects [I-1400/2](#) ... [I-1403/2](#) (see DS301 V4.02).

[► System bus "CAN on board"](#)

Setting range (min. value unit max. value)		
0		255
Subcodes	Lenze setting	Info
C00323/1	254	Transmission mode CAN1 IN
C00323/2	254	Transmission mode CAN2 IN
C00323/3	254	Transmission mode CAN3 IN
C00323/4	254	Transmission mode CAN4 IN <ul style="list-style-type: none">• From version 15.00.00

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☒ COM ☐ MOT Scaling factor: 1

C00324

Parameter | Name:

C00324 | CAN transmission blocking time

Data type: UNSIGNED_16

Index: 24251_d = 5EBB_h

Blocking time for the transmission of the emergency telegram and the process data

Note:

If the "Asynchronous - manufacturer-specific/device profile-specific" transmission type is set, the transmission cycle timer is reset to 0 if event-controlled transmission has been triggered.

Example: Cycle time (C00356/x) = 500 ms, blocking time = 100 ms, data change sporadically:

- In the case of a sporadic data change < 500 ms, due to the blocking time set, transmission takes place every 100 ms (event-controlled transmission) as quickly as possible.
- In the case of a sporadic data change > 500 ms, due to the cycle time set, transmission takes place every 500 ms (cyclic transmission).

► [System bus "CAN on board"](#)

Setting range (min. value unit max. value)			
0	ms	6500	
Subcodes	Lenze setting	Info	
C00324/1	0 ms	CAN emergency blocking time	
C00324/2	0 ms	CAN1_OUT blocking time	
C00324/3	0 ms	CAN2_OUT blocking time	
C00324/4	0 ms	CAN3_OUT blocking time	
C00324/5	0 ms	CAN4_OUT blocking time <ul style="list-style-type: none">From version 15.00.00	

☒ Read access

☒ Write access

☐ CINH

☐ PLC STOP

☐ No transfer

☒ COM

☐ MOT

Scaling factor: 1

C00338

Parameter Name: C00338 L_Arithmetik_1: Function		Data type: UNSIGNED_8 Index: 24237 _d = 5EAD _h
The L_Arithmetik_1 FB: Selection of internal arithmetics		
Selection list (Lenze setting printed in bold)		
0	Out = In1	
1	Out = In1 + In2	
2	nOut_a = nIn1_a - nIn2_a	
3	Out = (In1 * In2) / 100%	
4	nOut_a = (nIn1_a * 1%) / nIn2_a	
5	nOut_a = (nIn1_a * 100%) / (100% - nIn2_a)	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00339

Parameter Name: C00339 L_Arithmetik_2: Function		Data type: UNSIGNED_8 Index: 24236 _d = 5EAC _h
The L_Arithmetik_2 FB: Selection of internal arithmetics		
Selection list (Lenze setting printed in bold)		
0	nOut_a = nIn1_a	
1	nOut_a = nIn1_a + nIn2_a	
2	nOut_a = nIn1_a - nIn2_a	
3	nOut_a = (nIn1_a * nIn2_a) / 100%	
4	nOut_a = (nIn1_a * 1%) / nIn2_a	
5	nOut_a = (nIn1_a * 100%) / (100% - nIn2_a)	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00341

Parameter Name:			Data type: UNSIGNED_16 Index: 24234 _d = 5EAA _h		
C00341 CAN management - error configuration					
Selection of the events for which the <i>bFail</i> error output of the LS_CANManagement SB must be set to TRUE.					
Setting range (min. hex value max. hex value)			Lenze setting		
0x0000			0xFFFF	0x0000 (decimal: 0)	
Value is bit-coded: (☑ = bit set)			Info		
Bit 0	<input type="checkbox"/>	BusOff_MsgErr			
Bit 1	<input type="checkbox"/>	Warning			
Bit 2	<input type="checkbox"/>	NodeStopped			
Bit 3	<input type="checkbox"/>	HeartBeatEvent			
Bit 4	<input type="checkbox"/>	CAN1_In_Überw.			
Bit 5	<input type="checkbox"/>	CAN2_In_Überw.			
Bit 6	<input type="checkbox"/>	CAN3_In_Überw.			
Bit 7	<input type="checkbox"/>	CAN4_In_Überw.	From version 15.00.00		
Bit 8	<input type="checkbox"/>	Reserved			
Bit 9	<input type="checkbox"/>	Reserved			
Bit 10	<input type="checkbox"/>	Reserved			
Bit 11	<input type="checkbox"/>	Reserved			
Bit 12	<input type="checkbox"/>	Reserved			
Bit 13	<input type="checkbox"/>	Reserved			
Bit 14	<input type="checkbox"/>	Reserved			
Bit 15	<input type="checkbox"/>	Reserved			
☑ Read access ☑ Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT					

C00342

Parameter Name: C00342 CAN decoupling PDOInOut		Data type: UNSIGNED_16 Index: 24233 _d = 5EA9 _h	
Configuration defining the events that lead to a decoupling of the process data words. ▶ Configuring exception handling of the CAN PDOs			
Setting range (min. hex value max. hex value)			
0x0000	0xFFFF		
Value is bit-coded:		Info	
Bit 0	BusOff_MsgErr	From version 15.00.00	
Bit 1	Warning		
Bit 2	NodeStopped		
Bit 3	HeartBeatEvent		
Bit 4	CAN1_In_Überw.		
Bit 5	CAN2_In_Überw.		
Bit 6	CAN3_In_Überw.		
Bit 7	CAN4_In_Überw.		
Bit 8	Reserved		
Bit 9	Reserved		
Bit 10	Reserved		
Bit 11	Reserved		
Bit 12	Reserved		
Bit 13	Reserved		
Bit 14	Trouble		
Bit 15	Fault		
Subcodes	Lenze setting	Info	
C00342/1	0x0000	CAN decoupling PDO_In from the bus	
C00342/2	0x0000	CAN decoupling PDO_Out from the appl.	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT			

C00343

Parameter | Name: C00343 | LP_CanIn decoupling value

Data type: UNSIGNED_16
Index: 24232_d = 5EA8_h

Definition of the value the process data words are to have in the decoupled state.

► [Configuring exception handling of the CAN PDOs](#)

Setting range (min. value unit max. value)		
0		65535
Subcodes	Lenze setting	Info
C00343/1	0	LP_CanIn1 :wCtrl DiscVal
C00343/2	0	LP_CanIn1 :wIn2 DiscVal
C00343/3	0	LP_CanIn1 :wIn3 DiscVal
C00343/4	0	LP_CanIn1 :wIn4 DiscVal
C00343/5	0	LP_CanIn2 :wIn1 DiscVal
C00343/6	0	LP_CanIn2 :wIn2 DiscVal
C00343/7	0	LP_CanIn2 :wIn3 DiscVal
C00343/8	0	LP_CanIn2 :wIn4 DiscVal
C00343/9	0	LP_CanIn3 :wIn1 DiscVal
C00343/10	0	LP_CanIn3 :wIn2 DiscVal
C00343/11	0	LP_CanIn3 :wIn3 DiscVal
C00343/12	0	LP_CanIn3 :wIn4 DiscVal
C00343/13	0	LP_CanIn4 :wIn1 DiscVal • From version 15.00.00
C00343/14	0	LP_CanIn4 :wIn2 DiscVal • From version 15.00.00
C00343/15	0	LP_CanIn4 :wIn3 DiscVal • From version 15.00.00
C00343/16	0	LP_CanIn4 :wIn4 DiscVal • From version 15.00.00

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT Scaling factor: 1

C00344

Parameter | Name:

C00344 | LP_CanOut decoupling value

Data type: UNSIGNED_16

Index: 24231_d = 5EA7_h

Definition of the value the process data words are to have in the decoupled state.

► [Configuring exception handling of the CAN PDOs](#)

Setting range (min. value unit max. value)		
0		65535
Subcodes	Lenze setting	Info
C00344/1	0	LP_CanOut1:wState DiscVal
C00344/2	0	LP_CanOut1:wOut2 DiscVal
C00344/3	0	LP_CanOut1:wOut3 DiscVal
C00344/4	0	LP_CanOut1:wOut4 DiscVal
C00344/5	0	LP_CanOut2:wOut1 DiscVal
C00344/6	0	LP_CanOut2:wOut2 DiscVal
C00344/7	0	LP_CanOut2:wOut3 DiscVal
C00344/8	0	LP_CanOut2:wOut4 DiscVal
C00344/9	0	LP_CanOut3:wOut1 DiscVal
C00344/10	0	LP_CanOut3:wOut2 DiscVal
C00344/11	0	LP_CanOut3:wOut3 DiscVal
C00344/12	0	LP_CanOut3:wOut4 DiscVal
C00344/13	0	LP_CanOut4:wOut1 DiscVal • From version 15.00.00
C00344/14	0	LP_CanOut4:wOut2 DiscVal • From version 15.00.00
C00344/15	0	LP_CanOut4:wOut3 DiscVal • From version 15.00.00
C00344/16	0	LP_CanOut4:wOut4 DiscVal • From version 15.00.00

☒ Read access

☒ Write access

☐ CINH

☐ PLC STOP

☐ No transfer

☐ COM

☐ MOT

Scaling factor: 1

C00345

Parameter Name: C00345 CAN error status		Data type: UNSIGNED_8 Index: 24230 _d = 5EA6 _h	
► "CAN on board" system bus			
Selection list (read only)			
0	No Error		
1	Warning ErrActive		
2	Warning ErrPassive		
3	Bus off		
4	Reserved		
5	Reserved		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00347

Parameter Name: C00347 CAN status HeartBeat producer		Data type: UNSIGNED_8 Index: 24228 _d = 5EA4 _h	
		▶ Heartbeat protocol	
Selection list			
0	Boot-up		
4	Stopped		
5	Operational		
127	Pre-Operat.		
250	Failed		
255	NoResponse		
Subcodes		Info	
C00347/1		Status node 1 ... 15	
C00347/...			
C00347/15			
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00349

Parameter | Name:

C00349 | CAN setting - DIP switch

Data type: UNSIGNED_16

Index: 24226_d = 5EA2_h

DIP switch setting during last mains power-on

▶ ["CAN on board" system bus](#)

Display area (min. hex value | max. hex value)

0x0000

0xFFFF

Value is bit-coded:

Bit 0

Node address 1

Bit 1

Node address 2

Bit 2

Node address 4

Bit 3

Node address 8

Bit 4

Node address 16

Bit 5

Node address 32

Bit 6

Node address 64

Bit 7

Baud rate 1

Bit 8

Baud rate 2

Bit 9

Baud rate 4

Bit 10

Reserved

Bit 11

Reserved

Bit 12

Reserved

Bit 13

Reserved

Bit 14

Reserved

Bit 15

DIP switch at 24V-ON accepted

☒ Read access

☐ Write access

☐ CINH

☐ PLC STOP

☒ No transfer

☐ COM

☐ MOT

C00350

Parameter Name: C00350 CAN node address			Data type: UNSIGNED_8 Index: 24225 _d = 5EA1 _h	
Setting of the node address via parameters <ul style="list-style-type: none">• The node address can only be parameterised if the node address "0" is set via the DIP switches.• A change in the node address will not be effective until a CAN Reset Node is performed. <div>▶ "CAN on board" system bus</div>				
Setting range (min. value unit max. value)			Lenze setting	
1			127	1
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1				

C00351

Parameter Name: C00351 CAN baud rate		Data type: UNSIGNED_8 Index: 24224 _d = 5EA0 _h	
<div>Setting of the baud rate via parameters</div> <div><div><div>The baud rate can only be parameterised if the baud rate "0" is set via the DIP switches.</div><div>A change in the baud rate will not be effective until a CAN Reset Node is performed.</div></div><div><div>▶ "CAN on board" system bus</div></div></div>			
Selection list (Lenze setting printed in bold)			
0	500 kbps		
1	250 kbps		
2	125 kbps		
3	50 kbps		
4	1000 kbps		
5	20 kbps		
<div><div><div><div><input checked="" type="checkbox"/> Read access</div><div><input checked="" type="checkbox"/> Write access</div><div><input type="checkbox"/> CINH</div><div><input type="checkbox"/> PLC STOP</div><div><input type="checkbox"/> No transfer</div><div><input checked="" type="checkbox"/> COM</div><div><input type="checkbox"/> MOT</div></div><div>Scaling factor: 1</div></div></div>			

C00352

Parameter Name:		Data type: UNSIGNED_8	
C00352 CAN slave/master		Index: 24223 _d = 5E9F _h	
The drive starts as CAN master after mains switching if a value of "1" has been entered and saved here.			
▶ "CAN on board" system bus			
Selection list (Lenze setting printed in bold)			
0	Slave		
1	Master		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00353

Parameter | Name: C00353 | CAN IN/OUT COBID source

Data type: UNSIGNED_8
Index: 24222_d = 5E9E_h

Identifier assignment procedure for the CANx In/Out process data

► [System bus "CAN on board": Identifier of the process data objects](#)

Selection list		Info
0	COBID = C0350 + LenzeBaseID	COBID = node address + LenzeBaseID
1	COBID = C0350 + CANBaseID	COBID = node address + CANBaseID (C00354/x)
2	COBID = C0354/x	COBID = direct setting from C00354/x
Subcodes	Lenze setting	Info
C00353/1	1: COBID = C0350 + CANBaseID	COBID source CAN1_IN/OUT
C00353/2	1: COBID = C0350 + CANBaseID	COBID source CAN2_IN/OUT
C00353/3	1: COBID = C0350 + CANBaseID	COBID source CAN3_IN/OUT
C00353/4	1: COBID = C0350 + CANBaseID	COBID source CAN4_IN/OUT • From version 15.00.00

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☒ COM ☐ MOT Scaling factor: 1

C00354

Parameter | Name: **C00354 | COBID**

Data type: UNSIGNED_32
Index: 24221_d = 5E9D_h

Setting of the default COBID according to CANopen

- A change in the COBID will not be effective until a CAN reset node is performed.

[► System bus "CAN on board": Identifier of the process data objects](#)

Setting range (min. hex value max. hex value)		
0x00000000		0xFFFFFFFF
Value is bit-coded:		Info
Bit 0	COBID Bit0	<ul style="list-style-type: none">Bit 0 ... 10: COB-IDBit 11 ... 30: ReservedBit 31: PDO invalid (is not transmitted)
...	...	
Bit 31	PDO invalid	
Subcodes	Lenze setting	Info
C00354/1	0x00000201	COBID CAN1_IN
C00354/2	0x00000181	COBID CAN1_OUT
C00354/3	0x00000301	COBID CAN2_IN
C00354/4	0x00000281	COBID CAN2_OUT
C00354/5	0x00000401	COBID CAN3_IN
C00354/6	0x00000381	COBID CAN3_OUT
C00354/7	0x00000501	COBID CAN4_IN <ul style="list-style-type: none">From version 15.00.00
C00354/8	0x00000481	COBID CAN4_OUT <ul style="list-style-type: none">From version 15.00.00

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☒ COM ☐ MOT

C00355

Parameter Name: C00355 Active COBID			Data type: UNSIGNED_16 Index: 24220 _d = 5E9C _h		
Display of the COBID of the PDOs that is active in the CAN stack ▶ System bus "CAN on board": Identifier of the process data objects					
Display range (min. value unit max. value)					
0		2047			
Subcodes			Info		
C00355/1			Active COBID CAN1_IN		
C00355/2			Active COBID CAN1_OUT		
C00355/3			Active COBID CAN2_IN		
C00355/4			Active COBID CAN2_OUT		
C00355/5			Active COBID CAN3_IN		
C00355/6			Active COBID CAN3_OUT		
C00355/7			Active COBID CAN4_IN • From version 15.00.00		
C00355/8			Active COBID CAN4_OUT • From version 15.00.00		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00356

Parameter Name: C00356 CAN time settings			Data type: UNSIGNED_16 Index: 24219 _d = 5E9B _h		
Different time settings for the CAN interface					
▸ "CAN on board" system bus					
Setting range (min. value unit max. value)					
0	ms	65000			
Subcodes	Lenze setting	Info			
C00356/1	3000 ms	CAN delay boot-up - operat. • Delay time for NMT state change from "Boot-up" to "Operational".			
C00356/2	0 ms	CAN2_OUT cycle time			
C00356/3	0 ms	CAN3_OUT cycle time			
C00356/4	0 ms	CANx_OUT operat. - 1.transmit • When the "Operational" NMT status is reached, the delay time set here is started. After the delay time has been elapsed, the PDOs CAN2_OUT and CAN3_OUT are sent for the first time.			
C00356/5	0 ms	CAN1_OUT cycle time			
C00356/6	0 ms	CAN4_OUT cycle time • From version 15.00.00			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00357

Parameter Name: C00357 CAN monitoring times			Data type: UNSIGNED_16 Index: 24218 _d = 5E9A _h	
Mapping of the RPDO event time (see DS301 V4.02) <ul style="list-style-type: none">• If a value unequal to "0" is entered, the RPDO is not expected before the set time has expired.• If the RPDO is not received within the expected time, the response set in C00593/1...4 will be triggered. <div>▶ "CAN on board" system bus</div>				
Setting range (min. value unit max. value)				
0	ms	65000		
Subcodes	Lenze setting		Info	
C00357/1	3000 ms		CAN1_IN monitoring time	
C00357/2	3000 ms		CAN2_IN monitoring time	
C00357/3	3000 ms		CAN3_IN monitoring time	
C00357/4	3000 ms		CAN4_IN monitoring time <ul style="list-style-type: none">• From version 15.00.00	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>				

C00358

Parameter Name:		Data type: UNSIGNED_8 Index: 24217 _d = 5E99 _h	
C00358 CANx_OUT data length			
Setting of the data length for TX PDOs			
▶ "CAN on board" system bus			
Setting range (min. value unit max. value)			
1		8	
Subcodes	Lenze setting	Info	
C00358/1	8	CAN1_OUT data length	
C00358/2	8	CAN2_OUT data length	
C00358/3	8	CAN3_OUT data length	
C00358/4	8	CAN4_OUT data length • From version 15.00.00	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00359

Parameter | Name: C00359 | CAN status

Data type: UNSIGNED_8
Index: 24216_d = 5E98_h

► ["CAN on board" system bus](#)

Selection list (read only)	
0	Operational
1	Pre-Operat.
2	Reserved
3	Reserved
4	BootUp
5	Stopped
6	Reserved
7	Reset

☒ Read access

☐ Write access

☐ CINH

☐ PLC STOP

☒ No transfer

☒ COM

☐ MOT

Scaling factor: 1

C00360

Parameter | Name: C00360 | CAN telegram counter

Data type: UNSIGNED_16
Index: 24215_d = 5E97_h

▶ "CAN on board" system bus

Display range (min. value unit max. value)		
0		65535
Subcodes		Info
C00360/1		All PDO/SDO sent
C00360/2		All PDO/SDO received
C00360/3		Telegram counter CAN1_OUT
C00360/4		Telegram counter CAN2_OUT
C00360/5		Telegram counter CAN3_OUT
C00360/6		Telegram counter SDO1 OUT
C00360/7		Telegram counter SDO2 OUT
C00360/8		Telegram counter CAN1_IN
C00360/9		Telegram counter CAN2_IN
C00360/10		Telegram counter CAN3_IN
C00360/11		Telegram counter SDO1 IN
C00360/12		Telegram counter SDO2 IN
C00360/13		Telegram counter CAN4_OUT • From version 15.00.00
C00360/14		Telegram counter CAN4_IN • From version 15.00.00

☒ Read access ☐ Write access ☐ CINH ☐ PLC STOP ☒ No transfer ☒ COM ☐ MOT Scaling factor: 1

C00364

Parameter Name:		Data type: UNSIGNED_8	
C00364 CAN MessageError		Index: 24211 _d = 5E93 _h	
▶ "CAN on board" system bus			
Selection list (read only)			
0	No Error		
1	StuffError		
2	FormError		
3	AckError		
4	Bit1Error		
5	Bit0Error		
6	CRCError		
7	Reserved		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00366

Parameter Name: C00366 Number of CAN SDO channels		Data type: UNSIGNED_8 Index: 24209 _d = 5E91 _h	
Selection of the number of active parameter data channels <ul style="list-style-type: none">• In the Lenze setting, only the parameter data channel 1 is activated according to CANopen.• In order to activate both parameter data channels, set the selection "2 SDO Lenze". <div>▶ "CAN on board" system bus</div>			
Selection list (Lenze setting printed in bold)			
0	1 SDO CANOpen		
1	2 SDO Lenze		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C00367

Parameter Name: C00367 CAN SYNC Rx identifier		Data type: UNSIGNED_16 Index: 24208 _d = 5E90 _h	
Identifier by means of which the sync slave is to receive sync telegrams. • Mapping of the CANopen object I-1005 (see DS301 V4.02). <div>▶ "CAN on board" system bus</div>			
Setting range (min. hex value max. hex value)		Lenze setting	
0x0000		0xFFFF	0x0080 (decimal: 128)
Value is bit-coded: (<input checked="" type="checkbox"/> = bit set)			
Bit 0 <input type="checkbox"/>	COBID Bit0		
Bit 1 <input type="checkbox"/>	COBID Bit1		
Bit 2 <input type="checkbox"/>	COBID Bit2		
Bit 3 <input type="checkbox"/>	COBID Bit3		
Bit 4 <input type="checkbox"/>	COBID Bit4		
Bit 5 <input type="checkbox"/>	COBID Bit5		
Bit 6 <input type="checkbox"/>	COBID Bit6		
Bit 7 <input checked="" type="checkbox"/>	COBID Bit7		
Bit 8 <input type="checkbox"/>	COBID Bit8		
Bit 9 <input type="checkbox"/>	COBID Bit9		
Bit 10 <input type="checkbox"/>	COBID Bit10		
Bit 11 <input type="checkbox"/>	Reserved		
Bit 12 <input type="checkbox"/>	Reserved		
Bit 13 <input type="checkbox"/>	Reserved		
Bit 14 <input type="checkbox"/>	Reserved		
Bit 15 <input type="checkbox"/>	Reserved		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT			

C00368

Parameter Name: C00368 CAN SYNC Tx identifier			Data type: UNSIGNED_16 Index: 24207 _d = 5E8F _h		
Identifier by means of which the sync master is to transmit sync telegrams. • Mapping of the CANopen object I-1005 (see DS301 V4.02).					
▶ "CAN on board" system bus					
Setting range (min. hex value max. hex value)			Lenze setting		
0x0000		0xFFFF	0x0080 (decimal: 128)		
Value is bit-coded: (<input checked="" type="checkbox"/> = bit set)					
Bit 0 <input type="checkbox"/>	COBID Bit0				
Bit 1 <input type="checkbox"/>	COBID Bit1				
Bit 2 <input type="checkbox"/>	COBID Bit2				
Bit 3 <input type="checkbox"/>	COBID Bit3				
Bit 4 <input type="checkbox"/>	COBID Bit4				
Bit 5 <input type="checkbox"/>	COBID Bit5				
Bit 6 <input type="checkbox"/>	COBID Bit6				
Bit 7 <input checked="" type="checkbox"/>	COBID Bit7				
Bit 8 <input type="checkbox"/>	COBID Bit8				
Bit 9 <input type="checkbox"/>	COBID Bit9				
Bit 10 <input type="checkbox"/>	COBID Bit10				
Bit 11 <input type="checkbox"/>	Reserved				
Bit 12 <input type="checkbox"/>	Reserved				
Bit 13 <input type="checkbox"/>	Reserved				
Bit 14 <input type="checkbox"/>	Reserved				
Bit 15 <input type="checkbox"/>	Sync-transmit off				
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT					

C00369

Parameter Name: C00369 CAN sync transmission cycle time			Data type: UNSIGNED_16 Index: 24206 _d = 5E8E _h		
<div>Cycle during which the sync master is to transmit sync telegrams.<ul style="list-style-type: none">• If "0 ms" is set (Lenze setting), no sync telegrams are generated.• Mapping of the CANopen object I-1006 (see DS301 V4.02).</div> <div>▶ "CAN on board" system bus</div>					
Setting range (min. value unit max. value)			Lenze setting		
0	ms	65000	0 ms		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>					

C00370

Parameter Name: C00370 SyncTxRxTimes			Data type: INTEGER_16 Index: 24205 _d = 5E8D _h		
▶ System bus "CAN on board"					
Display range (min. value unit max. value)					
-1310	μs	1310			
Subcodes			Info		
C00370/1			CAN Sync instant of transmission		
C00370/2			Sync instant of reception		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00371

Parameter Name: C00371 CAN ErrorCode			Data type: UNSIGNED_16 Index: 24204 _d = 5E8C _h		
From version 13.00.00					
▶ System bus "CAN on board"					
Display range (min. value unit max. value)					
0		65535			
Subcodes			Info		
C00371/1			CAN ErrorCode		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00372

Parameter Name: C00372 CAN_Tx_Rx_Error			Data type: UNSIGNED_8 Index: 24203 _d = 5E8B _h		
▶ "CAN on board" system bus					
Display range (min. value unit max. value)					
0		255			
Subcodes			Info		
C00372/1			CAN Tx_Error		
C00372/2			CAN Rx_Error		
C00372/3			CAN Tx_Overflow		
C00372/4			CAN Rx_Overflow		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00381

Parameter Name:			Data type: UNSIGNED_16 Index: 24194 _d = 5E82 _h		
C00381 CAN Heartbeat producer time					
Time interval for the transmission of the heartbeat telegram to the consumer(s). <ul style="list-style-type: none">• The heartbeat telegram is sent automatically as soon as a time > 0 ms is set.• Mapping of the CANopen object I-1017 (see DS301 V4.02).					
▶ Heartbeat protocol					
Setting range (min. value unit max. value)				Lenze setting	
0	ms	65535	0 ms		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00385

Parameter Name: C00385 CAN node addr. HeartBeat producer			Data type: UNSIGNED_8 Index: 24190 _d = 5E7E _h		
The subcodes represent the nodes to be monitored by heartbeat.					
<div>▶ Heartbeat protocol</div>					
Setting range (min. value unit max. value)					
0		127			
Subcodes	Lenze setting	Info			
C00385/1	0	CAN node address HeartBeat producer 1 ... 15			
C00385/...					
C00385/15					
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>					

C00386

Parameter Name: C00386 CAN HeartBeat ConsumerTime			Data type: UNSIGNED_16 Index: 24189 _d = 5E7D _h		
The subcodes represent the nodes to be monitored by heartbeat.					
<div>▶ Heartbeat protocol</div>					
Setting range (min. value unit max. value)					
0	ms	60000			
Subcodes	Lenze setting	Info			
C00386/1	0 ms	ConsumerTime HeartBeat producer 1 ... 15			
C00386/...					
C00386/15					
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>					

C00387

Parameter Name: C00387 CAN-GatewayAddr			Data type: UNSIGNED_8 Index: 24188 _d = 5E7C _h		
From version 12.00.00					
▸ CAN gateway					
Setting range (min. value unit max. value)					
0		127			
Subcodes	Lenze setting		Info		
C00387/1	0		CAN_Gateway: Addr.		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00400

Parameter | Name: **C00400 | LS_PulseGenerator**

Data type: UNSIGNED_16
Index: 24175_d = 5E6F_h

Time setting of the pulse to be output by the SB [LS_PulseGenerator](#)

Note:

The real length of the low or high level at the *bSquareWave* output is always 1 ms higher than set here in subcode 1 or 2. If "0 ms" is set, a level with a length of 1 ms is created length, for instance, and if "1000 ms" is set, a level with a length of 1001 ms is created.

Setting range (min. value unit max. value)		
0	ms	60000
Subcodes	Lenze setting	Info
C00400/1	1000 ms	Length of the low level (break) + 1 ms
C00400/2	1000 ms	Length of the high level + 1 ms
C00400/3	100 ms	Delay time for status signal <i>bFirstCycleDone</i> <ul style="list-style-type: none">The <i>bFirstCycleDone</i> status signal is set to TRUE when the first task cycle is complete and the time set here has expired.

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT Scaling factor: 1

C00401

Parameter Name: C00401 CANxInOut: Inversion		Data type: UNSIGNED_16 Index: 24174 _d = 5E6E _h		
This parameter serves to invert the control/status bits of the CAN port blocks.				
▶ CAN port block				
Setting range (min. hex value max. hex value)				
0x0000				0xFFFF
Value is bit-coded:				Info
Bit 0	Active	Bit set = bit is inverted		
...	...			
Bit 15	Active			
Subcodes	Lenze setting	Info		
C00401/1	0x0000	Inversion of LP_CanIn1.bCtrl1_B0...15		
C00401/2	0x0000	Inversion of LP_CanOut1.bState1_B0...15		
C00401/3	0x0000	Inversion of LP_CanIn2.bIn1_B0...15		
C00401/4	0x0000	Inversion of LP_CanOut2.bOut1_B0...15		
C00401/5	0x0000	Inversion of LP_CanIn3.bIn1_B0...15		
C00401/6	0x0000	Inversion of LP_CanOut3.bOut1_B0...15		
C00401/7	0x0000	Inversion of LP_CanIn4.bIn1_B0...15 • From version 15.00.00		
C00401/8	0x0000	Inversion of LP_CanOut4.bOut1_B0...15 • From version 15.00.00		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT				

C00407

Parameter | Name: C00407 | LP_CanIn Mapping

Data type: UNSIGNED_32
Index: 24168_d = 5E68_h

From version 12.00.00

Mapping for port blocks LP_CanIn1...4

• These settings are ORed with the mapping settings for the single words in C00409/x.

CAN port block

Setting range (min. value unit max. value)		
0		4294967295
Subcodes	Lenze setting	Info
C00407/1	0	LP_CanIn1:dwIn12 MapVal
C00407/2	0	LP_CanIn1:dwIn34 MapVal
C00407/3	0	LP_CanIn2:dwIn12 MapVal
C00407/4	0	LP_CanIn2:dwIn34 MapVal
C00407/5	0	LP_CanIn3:dwIn12 MapVal
C00407/6	0	LP_CanIn3:dwIn34 MapVal
C00407/7	0	LP_CanIn4:dwIn12 MapVal • From version 15.00.00
C00407/8	0	LP_CanIn4:dwIn34 MapVal • From version 15.00.00

☒ Read access

☒ Write access

☐ CINH

☐ PLC STOP

☐ No transfer

☐ COM

☐ MOT

Scaling factor: 1

C00408

Parameter Name: C00408 LP_CanIn mapping selection		Data type: UNSIGNED_8 Index: 24167 _d = 5E67 _h
Selection of the mapping source for port blocks LP_CanIn1...4		
<div>▸ CAN port block</div>		
Selection list		Info
0	CanIn	CanIn
1	Par.C409 C407	Mapping configured in C00409
Subcodes	Lenze setting	Info
C00408/1	0: CanIn	Mapping selection LP_CanIn1
C00408/2	0: CanIn	Mapping selection LP_CanIn2
C00408/3	0: CanIn	Mapping selection LP_CanIn3
C00408/4	0: CanIn	Mapping selection LP_CanIn4 • From version 15.00.00
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00409

Parameter | Name: C00409 | LP_CanIn Mapping

Data type: UNSIGNED_16
Index: 24166_d = 5E66_h

Mapping for port blocks LP_CanIn1...4

• These settings are ORed with the mapping settings for the double words in C00407/x.

▶ CAN port block

Setting range (min. value unit max. value)			
0		65535	
Subcodes	Lenze setting	Info	
C00409/1	0	LP_CanIn1:wCtrl MapVal	
C00409/2	0	LP_CanIn1:wIn2 MapVal	
C00409/3	0	LP_CanIn1:wIn3 MapVal	
C00409/4	0	LP_CanIn1:wIn4 MapVal	
C00409/5	0	LP_CanIn2:wIn1 MapVal	
C00409/6	0	LP_CanIn2:wIn2 MapVal	
C00409/7	0	LP_CanIn2:wIn3 MapVal	
C00409/8	0	LP_CanIn2:wIn4 MapVal	
C00409/9	0	LP_CanIn3:wIn1MapVal	
C00409/10	0	LP_CanIn3:wIn2 MapVal	
C00409/11	0	LP_CanIn3:wIn3 MapVal	
C00409/12	0	LP_CanIn3:wIn4 MapVal	
C00409/13	0	LP_CanIn4:wIn1 MapVal • From version 15.00.00	
C00409/14	0	LP_CanIn4:wIn2 MapVal • From version 15.00.00	
C00409/15	0	LP_CanIn4:wIn3 MapVal • From version 15.00.00	
C00409/16	0	LP_CanIn4:wIn4 MapVal • From version 15.00.00	

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT Scaling factor: 1

C00410

Parameter Name: C00410 L_SignalMonitor_a: Signal sources		Data type: UNSIGNED_16 Index: 24165 _d = 5E65 _h
The L_SignalMonitor_a FB: Selection of the signal sources		
Selection list		
See selection list - analog signals		
Subcodes	Lenze setting	Info
C00410/1	0: Not connected	Signal source for output <i>nOut1_a</i>
C00410/2	0: Not connected	Signal source for output <i>nOut2_a</i>
C00410/3	0: Not connected	Signal source for output <i>nOut3_a</i>
C00410/4	0: Not connected	Signal source for output <i>nOut4_a</i>
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00411

Parameter Name: C00411 L_SignalMonitor_b: Signal sources		Data type: UNSIGNED_16 Index: 24164 _d = 5E64 _h
The L_SignalMonitor_b FB: Selection of the signal sources		
Selection list		
See selection list - digital signals		
Subcodes	Lenze setting	Info
C00411/1	0: Not connected	Signal source for output <i>bOut1</i>
C00411/2	0: Not connected	Signal source for output <i>bOut2</i>
C00411/3	0: Not connected	Signal source for output <i>bOut3</i>
C00411/4	0: Not connected	Signal source for output <i>bOut4</i>
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00412

Parameter Name: C00412 L_SignalMonitor_b: Inversion			Data type: UNSIGNED_8 Index: 24163 _d = 5E63 _h	
The L_SignalMonitor_b FB: Inversion of the binary outputs				
Setting range (min. hex value max. hex value)			Lenze setting	
0x00			0xFF	0x00 (decimal: 0)
Value is bit-coded: (<input checked="" type="checkbox"/> = bit set)			Info	
Bit 0 <input type="checkbox"/>		bOut1 inverted		Bit set = inversion active
Bit 1 <input type="checkbox"/>		bOut2 inverted		
Bit 2 <input type="checkbox"/>		bOut3 inverted		
Bit 3 <input type="checkbox"/>		bOut4 inverted		
Bit 4 <input type="checkbox"/>		Reserved		
Bit 5 <input type="checkbox"/>		Reserved		
Bit 6 <input type="checkbox"/>		Reserved		
Bit 7 <input type="checkbox"/>		Reserved		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT				

C00413

Parameter Name: C00413 L_SignalMonitor_a: Offs./gain		Data type: INTEGER_16 Index: 24162 _d = 5E62 _h
The L_SignalMonitor_a FB: Gain and offset of the analog signals		
Setting range (min. value unit max. value)		
-199.99	%	199.99
Subcodes	Lenze setting	Info
C00413/1	0.00 %	Offset for output <i>nOut1_a</i>
C00413/2	100.00 %	Gain for output <i>nOut1_a</i>
C00413/3	0.00 %	Offset for output <i>nOut2_a</i>
C00413/4	100.00 %	Gain for output <i>nOut2_a</i>
C00413/5	0.00 %	Offset for output <i>nOut3_a</i>
C00413/6	100.00 %	Gain for output <i>nOut3_a</i>
C00413/7	0.00 %	Offset for output <i>nOut4_a</i>
C00413/8	100.00 %	Gain for output <i>nOut4_a</i>
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100		


C00417

Parameter Name: C00417 Deactivate resolver error comp.		Data type: UNSIGNED_8 Index: 24158 _d = 5E5E _h	
		▸ Encoder/feedback system: Resolver	
Selection list (Lenze setting printed in bold)			
0	Resolver error comp. act.		
1	Resolver error comp. deact.		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00420

Parameter Name: C00420 Number of encoder increments			Data type: UNSIGNED_16 Index: 24155 _d = 5E5B _h
Indication of the encoder constant			
▶ Encoder/feedback system: Multi-Encoder			
Setting range (min. value unit max. value)			
1	Incr./rev.	32767	
Subcodes	Lenze setting	Info	
C00420/1	128 incr./rev.	FreqIn12: Encoder increment	
C00420/2	128 incr./rev.	FreqIn67: Encoder increment	
C00420/3	512 incr./rev.	LS MultiEncoder : Encoder increment	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00421

Parameter Name: C00421 LS_MultiEncoder: Supply voltage		Data type: UNSIGNED_16 Index: 24154 _d = 5E5A _h	
 Stop! Before connecting an encoder, make sure that the encoder supply voltage is set correctly! If the set supply voltage exceeds the permissible supply voltage of the connected encoder, the encoder may be destroyed!		▸ Encoder/feedback system: Multi-Encoder	
Setting range (min. value unit max. value)		Lenze setting	
5.0	V	12.0	5.0 V
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10			

C00422

Parameter Name: C00422 LS_MultiEncoder: Encoder type		Data type: UNSIGNED_8 Index: 24153 _d = 5E59 _h
▸ Encoder/feedback system: Multi-Encoder		
Selection list (Lenze setting printed in bold)		Info
0	Incremental encoder (TTL)	
1	Sin/cos encoder	
2	Absolute value encoder (Hiperface)	
3	Absolute value encoder (external)	
4	Absolute value encoder (SSI)	
5	LF In/Out	From version 12.00.00 ▸ Digital frequency coupling
6	Position encoder (Hiperface)	
7	Position encoder (external)	
8	Position encoder (SSI)	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input checked="" type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00423

Parameter Name: C00423 DOx: Delay times		Data type: UNSIGNED_16 Index: 24152 _d = 5E58 _h
Delay times for the digital output terminals		
▸ Digital output terminals		
Setting range (min. value unit max. value)		
0.000	s	65.000
Subcodes	Lenze setting	Info
C00423/1	0.000 s	Relay ON delay
C00423/2	0.000 s	Relay OFF delay
C00423/3	0.000 s	DO1 ON delay
C00423/4	0.000 s	DO1 OFF delay
C00423/5	0.000 s	DO2 ON delay
C00423/6	0.000 s	DO2 OFF delay
C00423/7	0.000 s	DO3 ON delay
C00423/8	0.000 s	DO3 OFF delay
C00423/9	0.000 s	DO "High Current" ON delay
C00423/10	0.000 s	DO "High Current" OFF delay
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000		

C00424

Parameter Name: C00424 Pulse form TTL encoder		Data type: UNSIGNED_8 Index: 24151 _d = 5E57 _h
▸ Encoder/feedback system: Multi-Encoder		
Selection list (Lenze setting printed in bold)		Info
0	4x evaluation A/B	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00425

Parameter | Name: Data type: UNSIGNED_8
Index: 24150_d = 5E56_h

C00425 | Encoder scanning time

Encoder sample time for the digital input terminals when configured as frequency inputs

► [Using DI1\(6\) and DI2\(7\) as frequency inputs](#)

Selection list	
0	1 ms
1	2 ms
2	5 ms
3	10 ms
4	20 ms
5	50 ms
6	100 ms
7	200 ms
8	500 ms
9	1000 ms

Subcodes	Lenze setting	Info
C00425/1	3: 10 ms	FreqIn12: Encoder scanning time • Only active with edge-counting procedure (C00496 = 3).
C00425/2	3: 10 ms	FreqIn67: Encoder scanning time

☒ Read access ☒ Write access ☒ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☒ MOT Scaling factor: 1

C00426

Parameter | Name:

C00426 | SSI encoder: Data bits

Data type: UNSIGNED_8

Index: 24149_d = 5E55_h

Example: Setting for an SSI encode with the coding "8192x4096":

- 8192 = 2¹³ = 13 bits Multiturn → C00426/4 = 13
- 4096 = 2¹² = 12 bits Singleturn → C00426/2 = 12
- This results in a data word length of 25 bits → C00426/1 = 25
- Start bit Singleturn = bit 0 → C00426/3 = 0
- Start bit Multiturn = bit 12 → C00426/5 = 12

▶ [Encoder/feedback system: SSI encoder](#)

Setting range (min. value unit max. value)		
0		32
Subcodes	Lenze setting	Info
C00426/1	25	SSI encoder: Data word length
C00426/2	13	SSI encoder: Bits SingleTurn
C00426/3	0	SSI encoder: Start bit Singleturn
C00426/4	12	SSI encoder: Bits Multiturn
C00426/5	13	SSI encoder: Start bit Multiturn
C00426/6	0	SSI encoder: Status bit 1 <ul style="list-style-type: none">• From version 02.00.00
C00426/7	0	SSI encoder: Shift of raw value <ul style="list-style-type: none">• From version 02.00.00
C00426/8	0	SSI encoder: Status bit 2 <ul style="list-style-type: none">• From version 14.00.00
C00426/9	0	SSI encoder: Status bit 3 <ul style="list-style-type: none">• From version 14.00.00

☒ Read access ☒ Write access ☒ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☒ MOT Scaling factor: 1

C00427

Parameter Name: C00427 SSI encoder: Bit rate		Data type: UNSIGNED_8 Index: 24148 _d = 5E54 _h	
▶ Encoder/feedback system: SSI encoder			
Selection list (Lenze setting printed in bold)			
1	100 kbps		
2	200 kbps		
3	300 kbps		
4	400 kbps		
5	500 kbps		
6	750 kbps		
7	1000 kbps		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input checked="" type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00428

Parameter Name: C00428 SSI encoder: Coding		Data type: UNSIGNED_8 Index: 24147 _d = 5E53 _h
▸ Encoder/feedback system: SSI encoder		
Selection list (Lenze setting printed in bold)		Info
0	Binary code	
1	Gray code	
2	Position Gray	From version 14.00.00, SSI encoders are supported which transmit the position data with Gray coding and the status bits in binary format.
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input checked="" type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00430

Parameter Name: C00430 LS_MultiEncoder: Max. initialization time		Data type: UNSIGNED_16 Index: 24145 _d = 5E51 _h
From version 12.00.00 ▸ Encoder/feedback system: sin/cos absolute value encoder with HIPERFACE® protocol		
Setting range (min. value unit max. value)		
500	ms	20000
Subcodes	Lenze setting	Info
C00430/1	1500 ms	Maximum time required by the encoder to respond to the read request of the controller.
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input checked="" type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00431

Parameter Name: C00431 LS_MultiEncoder: bFail selection		Data type: UNSIGNED_16 Index: 24144 _d = 5E50 _h
From version 13.00.00 Bit coded setting which events cause the <i>bFail</i> output to be set.		
Setting range (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		Info
Bit 0	Encoder open circuit	
Bit 1	KTY open circuit	
Bit 2	Position beyond C1112/2..3	
Bit 3	Angular drift error	
Bit 4	Communication error	
Bit 5	Hiperface position invalid	From version 14.00.00
Bit 6	Linear data overflow SSI	From version 14.00.00
Bit 7	Max. encoder speed	From version 14.00.00
Bit 8	Hiperface init active	
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	Reserved	
Bit 15	Reserved	
Subcodes	Lenze setting	Info
C00431/1	0x001D	LS_MultiEncoder: bFail selection
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT		

C00432

Parameter Name: C00432 LS_Resolver: bFail selection		Data type: UNSIGNED_16 Index: 24143 _d = 5E4F _h
From version 13.00.00 Bit coded setting which events cause the <i>bFail</i> output to be set.		
Setting range (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		
Bit 0	Resolver wire breakage	
Bit 1	KTY open circuit	
Bit 2	Reserved	
Bit 3	Reserved	
Bit 4	Reserved	
Bit 5	Reserved	
Bit 6	Reserved	
Bit 7	Reserved	
Bit 8	Reserved	
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	Reserved	
Bit 15	Reserved	
Subcodes	Lenze setting	Info
C00432/1	0x0001	LS_Resolver: bFail selection
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT		

C00434

Parameter Name: C00434 O_{xU/I}: Gain		Data type: INTEGER_16 Index: 24141 _d = 5E4D _h
Gain of the analog outputs		
<div> Analog terminals </div>		
Setting range (min. value unit max. value)		
-199.99	%	199.99
Subcodes	Lenze setting	Info
C00434/1	100.00 %	O1U: Gain
C00434/2	100.00 %	O2U: Gain
C00434/3	100.00 %	O1I: Gain
C00434/4	100.00 %	O2I: Gain
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100		

C00435

Parameter Name: C00435 OxU/I: Offset			Data type: INTEGER_16 Index: 24140 _d = 5E4C _h		
Offset of the analog outputs					
▸ Analog terminals					
Setting range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes	Lenze setting		Info		
C00435/1	0.00 %		O1U: Offset		
C00435/2	0.00 %		O2U: Offset		
C00435/3	0.00 %		O1I: Offset		
C00435/4	0.00 %		O2I: Offset		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00436

Parameter Name: C00436 OxU: Voltage			Data type: INTEGER_16 Index: 24139 _d = 5E4B _h		
Display of the voltage at the analog outputs					
<div>▶ Analog terminals</div>					
Display range (min. value unit max. value)					
0.00	V	10.00			
Subcodes			Info		
C00436/1			O1U: Voltage		
C00436/2			O2U: Voltage		
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 100</div></div>					

C00437

Parameter Name: C00437 OxI: Current			Data type: INTEGER_32 Index: 24138 _d = 5E4A _h		
Display of the current at the analog outputs					
<div>▶ Analog terminals</div>					
Display range (min. value unit max. value)					
0.000	mA	20.000			
Subcodes			Info		
C00437/1			O1I: Current		
C00437/2			O2I: Current		
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000</div>					

C00439

Parameter Name: C00439 OxU/I: Input value			Data type: INTEGER_16 Index: 24136 _d = 5E48 _h		
Display of the input values for the analog outputs					
<div>▶ Analog terminals</div>					
Display range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes			Info		
C00439/1			O1U: Input value		
C00439/2			O2U: Input value		
C00439/3			O1I: Input value		
C00439/4			O2I: Input value		
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 100</div></div>					

C00440

Parameter Name: C00440 LS_AnalogIn1: PT1 time constant			Data type: UNSIGNED_16 Index: 24135 _d = 5E47 _h		
PT1 time constant (S-ramp time) for the analog inputs					
<div>▶ Analog terminals</div>					
Setting range (min. value unit max. value)					
0	ms	1000			
Subcodes	Lenze setting	Info			
C00440/1	10 ms	PT1 rounding AnalogIn1			
C00440/2	10 ms	PT1 rounding AnalogIn2			
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>					

C00441

Parameter | Name: C00441 | Decoupling AnalogOut

Data type: UNSIGNED_16
Index: 24134_d = 5E46_h

Configuration defining the events that lead to a decoupling of the analog output terminals.

▶ [Configuring exception handling of the output terminals](#)

Setting range (min. hex value max. hex value)		Lenze setting
0x0000		0xFFFF
0x0000 (decimal: 0)		
Value is bit-coded: (☑ = bit set)		
Bit 0 ☐	SafeTorqueOff	
Bit 1 ☐	ReadyToSwitchOn	
Bit 2 ☐	SwitchedOn	
Bit 3 ☐	Reserved	
Bit 4 ☐	Trouble	
Bit 5 ☐	Fault	
Bit 6 ☐	Reserved	
Bit 7 ☐	Reserved	
Bit 8 ☐	Reserved	
Bit 9 ☐	Fail CAN_Management	
Bit 10 ☐	Reserved	
Bit 11 ☐	Reserved	
Bit 12 ☐	Reserved	
Bit 13 ☐	Reserved	
Bit 14 ☐	Reserved	
Bit 15 ☐	Reserved	

☑ Read access ☑ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT

C00442

Parameter Name: C00442 AOutx: Decoupling value			Data type: INTEGER_16 Index: 24133 _d = 5E45 _h
Definition of the value the analog output terminals are to have in the decoupled state. ▶ Configuring exception handling of the output terminals			
Setting range (min. value unit max. value)			
0.00	%	100.00	
Subcodes	Lenze setting	Info	
C00442/1	0.00 %	AOut1_U: Decoupling value	
C00442/2	0.00 %	AOut2_U: Decoupling value	
C00442/3	0.00 %	AOut1_I: Decoupling value	
C00442/4	0.00 %	AOut2_I: Decoupling value	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00443

Parameter Name: C00443 DIx: Level			Data type: UNSIGNED_16 Index: 24132 _d = 5E44 _h		
Bit coded display of the level of the digital inputs					
► Digital input terminals					
Display area (min. hex value max. hex value)					
0x0000			0xFFFF		
Value is bit-coded:			Info		
Bit 0 DI1			Bit set = HIGH level		
Bit 1 DI2					
Bit 2 DI3					
Bit 3 DI4					
Bit 4 DI5					
Bit 5 DI6					
Bit 6 DI7					
Bit 7 Reserved					
Bit 8 Reserved					
Bit 9 Reserved					
Bit 10 Reserved					
Bit 11 Reserved					
Bit 12 Reserved					
Bit 13 Reserved					
Bit 14 Reserved					
Bit 15 CINH					
Subcodes			Info		
C00443/1			DIx: Terminal level		
C00443/2			DIx: Output level		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT					

C00444

Parameter Name: C00444 DOx: Level			Data type: UNSIGNED_16 Index: 24131 _d = 5E43 _h		
Bit coded display of the level of the digital outputs					
▶ Digital output terminals					
Display area (min. hex value max. hex value)					
0x0000		0xFFFF			
Value is bit-coded:			Info		
Bit 0	Relay		Bit set = HIGH level		
Bit 1	DO1				
Bit 2	DO2				
Bit 3	DO3				
Bit 4	High current				
Bit 5	Reserved				
Bit 6	Reserved				
Bit 7	Reserved				
Bit 8	Reserved				
Bit 9	Reserved				
Bit 10	Reserved				
Bit 11	Reserved				
Bit 12	Reserved				
Bit 13	Reserved				
Bit 14	Reserved				
Bit 15	Reserved				
Subcodes			Info		
C00444/1			DOx: Input level		
C00444/2			DOx: Terminal level		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT					

C00445

Parameter Name: C00445 FreqInxx_nOut_v			Data type: INTEGER_16 Index: 24130 _d = 5E42 _h		
Display of the frequency input signals which are fed into the application. <div>► Using DI1(6) and DI2(7) as frequency inputs</div>					
Display range (min. value unit max. value)					
-32767	Incr/ms	32767			
Subcodes			Info		
C00445/1			FreqIn12_nOut_v		
C00445/2			FreqIn67_nOut_v		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00446

Parameter Name: C00446 FreqInxx_nOut_a			Data type: INTEGER_16 Index: 24129 _d = 5E41 _h		
Display of the frequency input signals which are fed into the application. <div>▶ Using DI1(6) and DI2(7) as frequency inputs</div>					
Display range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes			Info		
C00446/1			FreqIn12_nOut_a		
C00446/2			FreqIn67_nOut_a		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00447

Parameter | Name: C00447 | DigOut decoupling

Data type: UNSIGNED_16
Index: 24128_d = 5E40_h

Configuration defining the events that lead to a decoupling of the digital output terminals.

[► Configuring exception handling of the output terminals](#)

Setting range (min. hex value max. hex value)			Lenze setting
0x0000		0xFFFF	0x0000 (decimal: 0)
Value is bit-coded: (☑ = bit set)			
Bit 0	<input type="checkbox"/>	SafeTorqueOff	
Bit 1	<input type="checkbox"/>	ReadyToSwitchOn	
Bit 2	<input type="checkbox"/>	SwitchedOn	
Bit 3	<input type="checkbox"/>	Reserved	
Bit 4	<input type="checkbox"/>	Trouble	
Bit 5	<input type="checkbox"/>	Fault	
Bit 6	<input type="checkbox"/>	Reserved	
Bit 7	<input type="checkbox"/>	Reserved	
Bit 8	<input type="checkbox"/>	Reserved	
Bit 9	<input type="checkbox"/>	Fail CAN_Management	
Bit 10	<input type="checkbox"/>	Reserved	
Bit 11	<input type="checkbox"/>	Reserved	
Bit 12	<input type="checkbox"/>	Reserved	
Bit 13	<input type="checkbox"/>	Reserved	
Bit 14	<input type="checkbox"/>	Reserved	
Bit 15	<input type="checkbox"/>	Reserved	

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT

C00448

Parameter Name: C00448 DigOut decoupling value		Data type: UNSIGNED_16 Index: 24127 _d = 5E3F _h
Definition of the value the digital output terminals are to have in the decoupled state. • Bit set = HIGH level ► Configuring exception handling of the output terminals		
Setting range (min. hex value max. hex value)		Lenze setting
0x0000	0xFFFF	0x0000 (decimal: 0)
Value is bit-coded: (<input checked="" type="checkbox"/> = bit set)		
Bit 0 <input type="checkbox"/>	Relay_ON	
Bit 1 <input type="checkbox"/>	DigOut1_ON	
Bit 2 <input type="checkbox"/>	DigOut2_ON	
Bit 3 <input type="checkbox"/>	DigOut3_ON	
Bit 4 <input type="checkbox"/>	HighCurrent_ON	
Bit 5 <input type="checkbox"/>	Reserved	
Bit 6 <input type="checkbox"/>	Reserved	
Bit 7 <input type="checkbox"/>	Reserved	
Bit 8 <input type="checkbox"/>	Reserved	
Bit 9 <input type="checkbox"/>	Reserved	
Bit 10 <input type="checkbox"/>	Reserved	
Bit 11 <input type="checkbox"/>	Reserved	
Bit 12 <input type="checkbox"/>	Reserved	
Bit 13 <input type="checkbox"/>	Reserved	
Bit 14 <input type="checkbox"/>	Reserved	
Bit 15 <input type="checkbox"/>	Reserved	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C00449

Parameter Name: C00449 FreqInxx_dnOut_p		Data type: INTEGER_32 Index: 24126 _d = 5E3E _h
► Output of the encoder position of the DI1/DI2 frequency input		
Display range (min. value unit max. value)		
-2147483647	Incr.	2147483647
Subcodes		Info
C00449/1		FreqIn12_dnOut_p
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00451

Parameter Name: C00451 LS_MultiEncoder: bFail information		Data type: UNSIGNED_16 Index: 24124 _d = 5E3C _h		
From version 14.00.00				
Display area (min. hex value max. hex value)				
0x0000				0xFFFF
Value is bit-coded:				
Bit 0	Encoder open circuit			
Bit 1	KTY open circuit			
Bit 2	Position beyond C1112/2..3			
Bit 3	Angular drift error			
Bit 4	Communication error			
Bit 5	Hiperface position invalid			
Bit 6	Linear data overflow SSI			
Bit 7	Max. encoder speed			
Bit 8	Hiperface init active			
Bit 9	Reserved			
Bit 10	Reserved			
Bit 11	Reserved			
Bit 12	Reserved			
Bit 13	Reserved			
Bit 14	Reserved			
Bit 15	Reserved			
Subcodes		Info		
C00451/1		LS_MultiEncoder : bFail information		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT				

C00452

Parameter Name: C00452 LS_Resolver: bFail information			Data type: UNSIGNED_16 Index: 24123 _d = 5E3B _h
From version 14.00.00			
Display area (min. hex value max. hex value)			
0x0000		0xFFFF	
Value is bit-coded:			
Bit 0	Resolver wire breakage		
Bit 1	KTY open circuit		
Bit 2	Reserved		
Bit 3	Reserved		
Bit 4	Reserved		
Bit 5	Reserved		
Bit 6	Reserved		
Bit 7	Reserved		
Bit 8	Reserved		
Bit 9	Reserved		
Bit 10	Reserved		
Bit 11	Reserved		
Bit 12	Reserved		
Bit 13	Reserved		
Bit 14	Reserved		
Bit 15	Reserved		
Subcodes			Info
C00452/1			LS_Resolver : bFail information
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT			

C00453

Parameter Name: C00453 Keypad: Default manual jog			Data type: UNSIGNED_32 Index: 24122 _d = 5E3A _h
From version 14.00.00			
Setting range (min. value unit max. value)			
0.000		16000.000	
Subcodes	Lenze setting	Info	
C00453/1	729.001	Keypad: Speed setpoint	
C00453/2	56.002	Keypad: Display bar	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C00455

Parameter Name: C00455 FB_call table			Data type: UNSIGNED_16 Index: 24120 _d = 5E38 _h
This code is for device-internal use only and must not be written to by the user!			

C00456

Parameter Name: C00456 Editor level	Data type: UNSIGNED_8 Index: 24119 _d = 5E37 _h
This code is for device-internal use only and must not be written to by the user!	

C00458

Parameter Name: C00458 SYS_call table	Data type: UNSIGNED_16 Index: 24117 _d = 5E35 _h
This code is for device-internal use only and must not be written to by the user!	

C00459

Parameter Name: C00459 SYS_Output table	Data type: UNSIGNED_16 Index: 24116 _d = 5E34 _h
This code is for device-internal use only and must not be written to by the user!	

C00460

Parameter Name: C00460 Remote: Local keyswitch	Data type: UNSIGNED_8 Index: 24115 _d = 5E33 _h
This code is for device-internal use only and must not be written to by the user!	

C00461

Parameter Name: C00461 Remote: Acceleration/deceleration time	Data type: UNSIGNED_32 Index: 24114 _d = 5E32 _h
PC manual control	
Setting range (min. value unit max. value)	
0.000	s 999.999
Subcodes	Lenze setting Info
C00461/1	2.000 s Remote: Acceleration/deceleration time
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000	

C00462

Parameter Name: C00462 Remote: Control	Data type: UNSIGNED_16 Index: 24113 _d = 5E31 _h
PC manual control	
Setting range (min. value unit max. value)	
0	65535
Subcodes	Lenze setting Info
C00462/1	0 Remote: Control mode
C00462/2	0 Remote: Monitoring counter
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1	

C00463

Parameter Name: C00463 Remote: MCK control		Data type: UNSIGNED_32 Index: 24112 _d = 5E30 _h
This parameter serves to control the functions of the Motion Control Kernel for PC manual control .		
Setting range (min. hex value max. hex value)		
0x00000000		0xFFFFFFFF
Value is bit-coded:		
Bit 0	OpMode_Bit0	
Bit 1	OpMode_Bit1	
Bit 2	OpMode_Bit2	
Bit 3	OpMode_Bit3	
Bit 4	ManJogPos	
Bit 5	ManJogNeg	
Bit 6	ManExecute2ndSpeed	
Bit 7	ReleaseLimitSwitch	
Bit 8	HomStartStop	
Bit 9	HomSetPos	
Bit 10	HomResetPos	
Bit 11	EnableSpeedOverride	
Bit 12	EnableAccOverride	
Bit 13	EnableSRampOverride	
Bit 14	PosTeachSetPos	
Bit 15	PosTeachActPos	
Bit 16	PosExecute	
Bit 17	PosFinishTarget	
Bit 18	PosDisableFollowProfile	
Bit 19	PosStop	
Bit 20	PosModeBit0	
Bit 21	PosModeBit1	
Bit 22	PosModeBit2	
Bit 23	PosModeBit3	
Bit 24	ProfileNo_Bit0	
Bit 25	ProfileNo_Bit1	
Bit 26	ProfileNo_Bit2	
Bit 27	ProfileNo_Bit3	
Bit 28	ProfileNo_Bit4	
Bit 29	ProfileNo_Bit5	
Bit 30	ProfileNo_Bit6	
Bit 31	ProfileNo_Bit7	
Subcodes	Lenze setting	Info
C00463/1	0x00000000	Remote: MCK control
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C00464

Parameter Name: C00464 Remote: Monitoring timeout			Data type: UNSIGNED_16 Index: 24111 _d = 5E2F _h		
<div>▸ PC manual control</div>					
Setting range (min. value unit max. value)					
200	ms	5000			
Subcodes	Lenze setting		Info		
C00464/1	2000 ms		Remote: Monitoring timeout		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>					

C00465

Parameter Name:		Data type: INTEGER_32 Index: 24110 _d = 5E2E _h	
C00465 Keypad: Timeout welcome screen			
Time setting for the automatic change of the keypad display to the welcome screen			
Selection list (Lenze setting printed in bold)			
0	Never show welcome screen		
5	5 min		
15	15 min		
30	30 min		
60	60 min		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00466

Parameter Name: C00466 Keypad: Default parameter			Data type: INTEGER_32 Index: 24109 _d = 5E2D _h		
Setting of the default parameter for the keypad					
Setting range (min. value unit max. value)			Lenze setting		
0		65535	51		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00467

Parameter Name: C00467 Keypad: Default welcome screen		Data type: INTEGER_32 Index: 24108 _d = 5E2C _h	
Selection of the welcome screen for the keypad			
Selection list (Lenze setting printed in bold)			
0	Main menu		
1	Parameter list		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00468

Parameter Name: C00468 Service code		Data type: INTEGER_32 Index: 24107 _d = 5E2B _h
This code is for device-internal use only and must not be written to by the user!		

C00469

Parameter Name: C00469 Keypad: Fct. STOP key		Data type: INTEGER_32 Index: 24106 _d = 5E2A _h
Selection of the function for the STOP key on the keypad		
Selection list (Lenze setting printed in bold)		Info
0	No response	STOP key does not have any function
1	Inhibit controller	STOP key sets controller inhibit in the drive
2	Activate quick stop	STOP key sets quick stop in the drive
4	Inhibit controller and reset error	From version 14.00.00 STOP key sets controller inhibit in the drive. An error reset is carried out at the same time.
5	Activate quick stop and reset error	From version 14.00.00 STOP key sets quick stop in the drive. An error reset is carried out at the same time.
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input checked="" type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00470

Parameter Name:		Data type: UNSIGNED_8
C00470 LS_ParFree_b		Index: 24105 _d = 5E29 _h
The LS_ParFree_b SB: Setting of the signal level to be output		
Selection list		
0	False	
1	True	
Subcodes	Lenze setting	Info
C00470/1	0: FALSE	Signal level for output <i>bPar1</i> ... <i>bPar32</i>
C00470/...		
C00470/32		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00471

Parameter Name: C00471 LS_ParFree		Data type: UNSIGNED_16 Index: 24104 _d = 5E28 _h		
The LS_ParFree SB: Setting of the words to be output				
Setting range (min. hex value max. hex value)				
0x0000				0xFFFF
Value is bit-coded:				
Bit 0	Bit0			
...	...			
Bit 15	Bit15			
Subcodes	Lenze setting	Info		
C00471/1	0x0000	Value for output <i>wPar1</i> ... <i>wPar32</i>		
C00471/...				
C00471/32				
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT				

C00472

Parameter Name: C00472 LS_ParFree_a			Data type: INTEGER_16 Index: 24103 _d = 5E27 _h		
The LS_ParFree_a SB: Setting of the analog signals to be output					
Setting range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes	Lenze setting		Info		
C00472/1	0.00 %		Value for output <i>nPar1_a</i>		
C00472/2	0.00 %		Value for output <i>nPar2_a</i>		
C00472/3	100.00 %		Value for output <i>nPar3_a</i>		
C00472/4	100.00 %		Value for output <i>nPar4_a</i>		
C00472/5	0.00 %		Value for output <i>nPar5_a</i>		
C00472/6	0.00 %		Value for output <i>nPar6_a</i>		
C00472/7	0.00 %		Value for output <i>nPar7_a</i>		
C00472/8	0.00 %		Value for output <i>nPar8_a</i>		
C00472/9	0.00 %		Value for output <i>nPar9_a</i>		
C00472/10	0.00 %		Value for output <i>nPar10_a</i>		
C00472/11	0.00 %		Value for output <i>nPar11_a</i>		
C00472/12	0.00 %		Value for output <i>nPar12_a</i>		
C00472/13	0.00 %		Value for output <i>nPar13_a</i>		
C00472/14	0.00 %		Value for output <i>nPar14_a</i>		
C00472/15	0.00 %		Value for output <i>nPar15_a</i>		
C00472/16	0.00 %		Value for output <i>nPar16_a</i>		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00473

Parameter Name: C00473 LS_ParFree_v			Data type: INTEGER_16 Index: 24102 _d = 5E26 _h		
The LS_ParFree_v SB: Setting of the speed signals to be output					
Setting range (min. value unit max. value)					
-32767	Incr./ms	32767			
Subcodes	Lenze setting	Info			
C00473/1	0 incr./ms	Values for output <i>nPar1_v</i> ... <i>nPar8_v</i>			
C00473/...					
C00473/8					
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00474

Parameter Name: C00474 LS_ParFree_p			Data type: INTEGER_32 Index: 24101 _d = 5E25 _h		
SB LS_ParFree_p : Setting of the position signals to be output					
Setting range (min. value unit max. value)					
-2147483647	Incr.	2147483647			
Subcodes		Lenze setting		Info	
C00474/1		0 incr.		Values for output <i>dnPar1_p</i> ... <i>dnPar8_p</i>	
C00474/...					
C00474/8					
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00475

Parameter Name: C00475 LS_ParFreeUnit_1_2			Data type: INTEGER_32 Index: 24100 _d = 5E24 _h		
From version 02.00.00					
SB LS_ParFreeUnit / LS_ParFreeUnit_2 : Setting of the position signals to be output					
Setting range (min. value unit max. value)					
-214748.3647	units	214748.3647			
Subcodes		Lenze setting		Info	
C00475/1		0.0000 units		Values for output <i>dnC475_1</i> ... <i>dnC475_32</i>	
C00475/...					
C00475/32					
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000					

C00476

Parameter Name: C00476 LS_ParFree_a_2			Data type: INTEGER_16 Index: 24099 _d = 5E23 _h
From version 02.00.00			
SB <u>LS_ParFree_a_2</u> : Setting of the analog signals to be output			
Setting range (min. value unit max. value)			
-199.99	%	199.99	
Subcodes	Lenze setting	Info	
C00476/1	0.00 %	Value for output <i>nC476_1_a</i>	
C00476/2	0.00 %	Value for output <i>nC476_2_a</i>	
C00476/3	0.00 %	Value for output <i>nC476_3_a</i>	
C00476/4	0.00 %	Value for output <i>nC476_4_a</i>	
C00476/5	0.00 %	Value for output <i>nC476_5_a</i>	
C00476/6	0.00 %	Value for output <i>nC476_6_a</i>	
C00476/7	0.00 %	Value for output <i>nC476_7_a</i>	
C00476/8	0.00 %	Value for output <i>nC476_8_a</i>	
C00476/9	0.00 %	Value for output <i>nC476_9_a</i>	
C00476/10	0.00 %	Value for output <i>nC476_10_a</i>	
C00476/11	0.00 %	Value for output <i>nC476_11_a</i>	
C00476/12	0.00 %	Value for output <i>nC476_12_a</i>	
C00476/13	0.00 %	Value for output <i>nC476_13_a</i>	
C00476/14	0.00 %	Value for output <i>nC476_14_a</i>	
C00476/15	0.00 %	Value for output <i>nC476_15_a</i>	
C00476/16	0.00 %	Value for output <i>nC476_16_a</i>	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00477

Parameter Name: C00477 LS_ParFree_2			Data type: UNSIGNED_16 Index: 24098 _d = 5E22 _h	
From version 02.00.00				
SB LS_ParFree_2 : Setting of the words to be output				
Setting range (min. hex value max. hex value)				
0x0000				0xFFFF
Value is bit-coded:				
Bit 0	Bit0			
...	...			
Bit 15	Bit15			
Subcodes	Lenze setting	Info		
C00477/1	0x0000	Value for output wC477_1 ... wC477_32		
C00477/...				
C00477/32				
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT				

C00478

Parameter Name: C00478 LS_ParFree_v_2			Data type: INTEGER_16 Index: 24097 _d = 5E21 _h		
From version 02.00.00					
SB LS_ParFree_v_2 : Setting of the speed signals to be output					
Setting range (min. value unit max. value)					
-32767	Incr./ms	32767			
Subcodes	Lenze setting	Info			
C00478/1	0 incr./ms	Values for output <i>nC478_1_v</i> ... <i>nC478_8_v</i>			
C00478/...					
C00478/8					
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00479

Parameter Name: C00479 LS_ParFree32			Data type: INTEGER_32 Index: 24096 _d = 5E20 _h		
From version 02.00.00					
SB LS_ParFree32 : Setting of the 32-bit values to be output					
Setting range (min. value unit max. value)					
-2147483647		2147483647			
Subcodes		Lenze setting		Info	
C00479/1	0		Values for output <i>dnC479_1</i> ... <i>dnC479_8</i>		
C00479/...					
C00479/8					
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00480

Parameter Name: C00480 LS_DisFree_b			Data type: UNSIGNED_16 Index: 24095 _d = 5E1F _h		
The LS_DisFree_b SB: Display of the input values					
Display area (min. hex value max. hex value)					
0x0000		0xFFFF			
Value is bit-coded:			Info		
Bit 0	bDis1		Signal level input <i>bDis1</i> ... <i>bDis16</i>		
...	...				
Bit 15	bDis16				
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT					

C00481

Parameter Name: C00481 LS_DisFree			Data type: UNSIGNED_16 Index: 24094 _d = 5E1E _h		
The LS_DisFree SB: Display of the input values					
Display area (min. hex value max. hex value)					
0x0000		0xFFFF			
Value is bit-coded:					
Bit 0	Active				
...	...				
Bit 15	Active				
Subcodes			Info		
C00481/1			Input values <i>wDis1</i> ... <i>wDis8</i>		
C00481/...					
C00481/8					
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT					

C00482

Parameter Name: C00482 LS_DisFree_a			Data type: INTEGER_16 Index: 24093 _d = 5E1D _h		
The LS_DisFree_a SB: Display of the input values					
Display range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes			Info		
C00482/1			Input values <i>nDis1_a</i> ... <i>nDis8_a</i>		
C00482/...					
C00482/8					
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00483

Parameter Name: C00483 LS_DisFree_p			Data type: INTEGER_32 Index: 24092 _d = 5E1C _h		
SB LS_DisFree_p : Display of the input values					
Display range (min. value unit max. value)					
-2147483647	Incr.	2147483647			
Subcodes			Info		
C00483/1			Input values <i>dnDis1_p</i> ... <i>dnDis8_p</i>		
C00483/...					
C00483/8					
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00484

Parameter Name: C00484 Application units: Offset			Data type: INTEGER_16 Index: 24091 _d = 5E1B _h
The LS_DisFree_a SB: Offset for display of the input variables in application unit ▶ Display of internal process factors in application units			
Setting range (min. value unit max. value)			
-199.99	%	199.99	
Subcodes	Lenze setting	Info	
C00484/1	0.00 %	Application unit 1: Offset	
C00484/2	0.00 %	Application unit 2: Offset	
C00484/3	0.00 %	Application unit 3: Offset	
C00484/4	0.00 %	Application unit 4: Offset	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00485

Parameter Name: C00485 Application units: Display factor			Data type: INTEGER_32 Index: 24090 _d = 5E1A _h
The LS_DisFree_a SB: Display factor for display of the input variables in application unit ▶ Display of internal process factors in application units			
Setting range (min. value unit max. value)			
-65536.0000		65536.0000	
Subcodes	Lenze setting	Info	
C00485/1	1.0000	Application unit 1: Display factor	
C00485/2	1.0000	Application unit 2: Display factor	
C00485/3	1.0000	Application unit 3: Display factor	
C00485/4	1.0000	Application unit 4: Display factor	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000			

C00486

Parameter Name: C00486 Application units: Text		Data type: VISIBLE_STRING Index: 24089 _d = 5E19 _h
The LS_DisFree_a SB: Text for the display of the input variables in application unit ▶ Display of internal process factors in application units		
Subcodes	Lenze setting	Info
C00486/1		Application unit 1: Text
C00486/2		Application unit 2: Text
C00486/3		Application unit 3: Text
C00486/4		Application unit 4: Text
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC-STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Character length: 7		

C00487

Parameter Name: C00487 - Application units			Data type: INTEGER_32 Index: 24088 _d = 5E18 _h		
SB LS_DisFree_a : Display of the input values in a configurable application unit ▶ Display of internal process factors in application units					
Display range (min. value unit max. value)					
-21474836.47	units	21474836.47			
Subcodes			Info		
C00487/1			Application units 1		
C00487/2			Application units 2		
C00487/3			Application units 3		
C00487/4			Application units 4		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00488

Parameter | Name:

C00488 | L_JogCtrlEdgeDetect

Data type: UNSIGNED_8

Index: 24087_d = 5E17_h

The [L_JogCtrlExtension_1](#) FB: Signal methodology

• Selection whether the corresponding function is to be activated by edge or level.

Selection list		Info
0	Level	
1	Edge	
Subcodes	Lenze setting	Info
C00488/1	0: Level	InputSens.SlowDown1 • Selection of edge or level for starting slow-down function 1
C00488/2	0: Level	InputSens.Stop1 • Selection of edge or level for stop function 1
C00488/3	0: Level	InputSens.SlowDown2 • Selection of edge or level for starting slow-down function 2
C00488/4	0: Level	InputSens.Stop2 • Selection of edge or level for stop function 2
C00488/5	0: Level	InputSens.SlowDown3 • Selection of edge or level for starting slow-down function 3
C00488/6	0: Level	InputSens.Stop3 • Selection of edge or level for stop function 3

☒ Read access

☒ Write access

☐ CINH

☐ PLC STOP

☐ No transfer

☐ COM

☐ MOT

Scaling factor: 1

C00490

Parameter Name: C00490 Position encoder selection		Data type: UNSIGNED_8 Index: 24085 _d = 5E15 _h
Selection of the feedback system for the generation of the actual position on the load		
Encoder/feedback system		
Selection list (Lenze setting printed in bold)		Info
0	No sensor: nSpeedSetValue_a	No encoder available on the load. The position signal <i>dnMotorPosAct_p</i> is derived from the speed setpoint <i>nSpeedSetValue_a</i> .
1	Sensor signal FreqIn12	Position encoder signal is fed via digital inputs DI1 and DI2
2	Encoder signal FreqIn67	Position encoder signal is fed via digital inputs DI6 and DI7
3	Multi encoder	Position encoder signal is supplied via multi-encoder interface
4	Resolver	Position encoder signal is supplied via resolver interface
5	Encoder signal FreqIn1267	From version 15.00.00 Position encoder signal is fed via digital inputs DI1/DI2 and DI6/DI7 (connection of 4-track HTL encoders)
10	Encoder selection C495 or nVoltageAngleAct_a	From version 12.00.00 The position signal <i>dnMotorPosAct_p</i> is either calculated from the set speed feedback (for C00495 > 0) or from the speed signal <i>nMotorSpeedAct_v</i> (for C00495 = 0).
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00491

Parameter Name: C00491 Hiperface messages			Data type: UNSIGNED_8 Index: 24084 _d = 5E14 _h	
From version 14.00.00				
Display range (min. value unit max. value)				
0		255		
Subcodes			Info	
C00491/1			Hiperface: Status 1	
C00491/2			Hiperface: Status 2	
C00491/3			Hiperface: Status 3	
C00491/4			Hiperface: Status 4	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1				

C00492

Parameter Name: C00492 Hiperface: Detected TypCode		Data type: UNSIGNED_8 Index: 24083 _d = 5E13 _h
From version 02.00.00		
Encoder/feedback system: sin/cos absolute value encoder with HIPERFACE® protocol		
Display range (min. value unit max. value)		
0		255
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00493

Parameter Name: C00493 Hiperface: TypCode			Data type: UNSIGNED_8 Index: 24082 _d = 5E12 _h
From version 02.00.00			► Encoder/feedback system: sin/cos absolute value encoder with HIPERFACE® protocol
Setting range (min. value unit max. value)		Lenze setting	
0		255	0
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00494

Parameter Name: C00494 Hiperface: Resolutions			Data type: UNSIGNED_32 Index: 24081 _d = 5E11 _h
From version 02.00.00			
▶ Encoder/feedback system: sin/cos absolute value encoder with HIPERFACE® protocol			
Setting range (min. value unit max. value)			
0		65536	
Subcodes	Lenze setting	Info	
C00494/1	0	Hiperface: Number of revolutions	
C00494/2	0	Hiperface: Steps per revolution	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00495

Parameter Name: C00495 Speed sensor selection		Data type: UNSIGNED_8 Index: 24080 _d = 5E10 _h
Selection of the feedback system for the actual speed for motor control and display		
<div>► Encoder/feedback system</div>		
Selection list (Lenze setting printed in bold)		Info
0	No sensor	No sensor available for the actual speed detection
1	Sensor signal FreqIn12	Speed sensor signal is fed via the digital DI1 and DI2 inputs
2	Encoder signal FreqIn67	Speed encoder signal is fed via digital inputs DI6 and DI7
3	Multi encoder	Speed encoder signal is supplied via multi-encoder interface
4	Resolver	Speed encoder signal is supplied via resolver interface
5	Encoder signal FreqIn1267	From version 15.00.00 Speed encoder signal is fed via digital inputs DI1/DI2 and DI6/DI7 (connection of 4-track HTL encoders)
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT <div>Scaling factor: 1</div></div>		

C00496

Parameter Name: C00496 Encoder evaluation method DigIn12		Data type: UNSIGNED_8 Index: 24079 _d = 5E0F _h	
▸ Encoder/feedback system			
Selection list (Lenze setting printed in bold)		Info	
0	High-resolution encoders	High-precision procedure for high-resolution encoders (>=512 increments)	
1	Low-resolution encoder (StateLine)	High-precision procedure for low-resolution encoders (<=128 increments)	
2	Comb. encoder procedure	Combination of the first two procedures as a function of the speed (recommended procedure)	
3	Edge-counting procedure	Simple edge counting procedure with adjustable scanning time (C00425)	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input checked="" type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00497

Parameter Name: C00497 Filter time constant			Data type: UNSIGNED_16 Index: 24078 _d = 5E0E _h
			▸ Encoder/feedback system
Setting range (min. value unit max. value)			
0.0	ms	500.0	
Subcodes	Lenze setting	Info	
C00497/1	1.0 ms	FreqIn12: Encoder filter time	
C00497/2	1.0 ms	FreqIn67: Encoder filter time	
C00497/3	1.0 ms	LS MultiEncoder : Encoder filter time	
C00497/4	2.0 ms	LS Resolver : Encoder filter time	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10			

C00498

Parameter Name: C00498 Open-circuit monitoring		Data type: UNSIGNED_8 Index: 24077 _d = 5E0D _h
Configuration of open-circuit monitoring for encoder/feedback system <ul style="list-style-type: none"> • We recommend using the Lenze setting. • The settings 1 ... 3 make sense if the respective encoder is not to be used as speed encoder or position encoder but within the scope of the application. Moreover, a directed disconnection of the monitoring is possible. <p style="text-align: right;">▶ Encoder/feedback system</p>		
Selection list		Info
0	Speed and position encoder	Open-circuit monitoring is active for the speed encoder selected in C00495 and the position encoder selected in C00490 . <ul style="list-style-type: none"> • Depending on whether a speed encoder or position encoder has been selected, the monitoring mode for the resolver and/or encoder is activated. • If no speed encoder and position encoder have been selected, open-circuit monitoring is deactivated.
1	Resolver only	Open-circuit monitoring is only active for the resolver, independent on the selection of the speed encoder and position encoder. <ul style="list-style-type: none"> • Open-circuit monitoring for the encoder is deactivated.
2	Encoder only	Open-circuit monitoring is only active for the encoder, independent on the selection of the speed encoder and position encoder. <ul style="list-style-type: none"> • Open-circuit monitoring for the resolver is deactivated.
3	Resolver and encoder	Open-circuit monitoring is active for the resolver and encoder, independent on the selection of the speed encoder and position encoder.
Subcodes	Lenze setting	Info
C00498/1	0: Speed encoder and position encoder	Open-circuit monitoring
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00499

Parameter Name: C00499 Hiperface: Settings		Data type: UNSIGNED_16 Index: 24076 _d = 5E0C _h	
From version 14.00.00			
Setting range (min. hex value max. hex value)			
0x0000		0xFFFF	
Value is bit-coded:			Info
Bit 0	Manual entry of encoder data		
Bit 1	write defined position		
Bit 2	Also write value directly in case of PSM		
Bit 3	PLI compensation		
Bit 4	Delay open circuit monit.		From version 15.00.00
Bit 5	Reserved		
Bit 6	Reserved		
Bit 7	Reserved		
Bit 8	Reserved		
Bit 9	Reserved		
Bit 10	Reserved		
Bit 11	Reserved		
Bit 12	Reserved		
Bit 13	Reserved		
Bit 14	Reserved		
Bit 15	Reserved		
Subcodes	Lenze setting	Info	
C00499/1	0x0000	Hiperface: Advanced settings	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT			

C00505

Parameter Name: C00505 Password data		Data type: VISIBLE_STRING Index: 24070 _d = 5E06 _h	
<div>▶ Device access protection</div>			
Subcodes	Lenze setting	Info	
C00505/1		MasterPin	
C00505/2		Binding ID	
C00505/3		Password	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC-STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Character length: 16</div>			

C00506

Parameter Name: C00506 PW protection internal config		Data type: UNSIGNED_16 Index: 24069 _d = 5E05 _h
From version 15.00.00 Configuration of the password protection for device-internal parameter access ▶ Individual password protection for single communication channels		
Setting range (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		Info
Bit 0	Only access to user menu	The menus in the keypad are reduced. Only the user menu can be used to change parameters.
Bit 1	Parameter write protection	Via system blocks (LS_ParReadWrite1-6 and LS_WriteParamList), write/read parameters cannot be written.
Bit 2	Parameter read protection	Via system blocks (LS_ParReadWrite1-6 and LS_WriteParamList), write/read parameters cannot be read.
Bit 3	Reserved	
Bit 4	Reserved	
Bit 5	Reserved	
Bit 6	Reserved	
Bit 7	Reserved	
Bit 8	Reserved	
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	Reserved	
Bit 15	Reserved	
Subcodes	Lenze setting	Info
C00506/1	0x0007	PW protection internal config
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C00507

Parameter Name: C00507 Current password protection		Data type: UNSIGNED_16 Index: 24068 _d = 5E04 _h	
Display of the currently active device access protection (password protection and device personalisation)			
Note: As the password protection can be configured individually for each single communication channel from version 15.00.00 bit 1 and bit 2 indicate the active protection always with regard to the communication channel used. <div>▶ Device access protection</div>			
Display area (min. hex value max. hex value)			
0x0000			0xFFFF
Value is bit-coded:			Info
Bit 0	Only access to user menu	1 ≡ The menus in the keypad are reduced. Only the user menu can be used to change parameters. ▶ Password protection	
Bit 1	Parameter write protection	1 ≡ The currently used communication channel cannot be used to write into write/read parameters. ▶ Password protection	
Bit 2	Parameter read protection	1 ≡ The currently used communication channel cannot be used to read write/read parameters. ▶ Password protection	
Bit 3	Reserved		
Bit 4	Reserved		
Bit 5	Reserved		
Bit 6	Reserved		
Bit 7	Reserved		
Bit 8	Reserved		
Bit 9	Reserved		
Bit 10	Reserved		
Bit 11	Reserved		
Bit 12	Reserved		
Bit 13	Reserved		
Bit 14	Reserved		
Bit 15	Memory module binding on	1 ≡ Device personalisation is active. All write/read actions between controller and memory module are only executed if both components have the same binding ID. ▶ Device personalisation	
Subcodes			Info
C00507/1			Password protection - all communication channels
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT			

C00508

Parameter Name: C00508 PW protection config X6(DIAG)		Data type: UNSIGNED_16 Index: 24067 _d = 5E03 _h
From version 15.00.00 Configuration of the password protection for parameter access via diagnostic interface X6 ("DIAG") ▶ Individual password protection for single communication channels		
Setting range (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		Info
Bit 0	Reserved	
Bit 1	Parameter write protection	The diagnostics interface X6 cannot be used to write into write/read parameters.
Bit 2	Parameter read protection	The diagnostics interface X6 cannot be used to read write/read parameters.
Bit 3	Reserved	
Bit 4	Reserved	
Bit 5	Reserved	
Bit 6	Reserved	
Bit 7	Reserved	
Bit 8	Reserved	
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	Reserved	
Bit 15	Reserved	
Subcodes	Lenze setting	Info
C00508/1	0x0006	PW protection config X6(DIAG)
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C00509

Parameter Name: C00509 PW protection config X1(CAN)		Data type: UNSIGNED_16 Index: 24066 _d = 5E02 _h
From version 15.00.00 Configuration of the password protection for parameter access via CANopen interface X1 ("CAN on board") ▶ Individual password protection for single communication channels		
Setting range (min. hex value max. hex value)		
0x0000	0xFFFF	
Value is bit-coded:		Info
Bit 0	Reserved	
Bit 1	Parameter write protection	The CANopen interface X1 cannot be used to write into write/read parameters.
Bit 2	Parameter read protection	The CANopen interface X1 cannot be used to read write/read parameters.
Bit 3	Reserved	
Bit 4	Reserved	
Bit 5	Reserved	
Bit 6	Reserved	
Bit 7	Reserved	
Bit 8	Reserved	
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	Reserved	
Bit 15	Reserved	
Subcodes	Lenze setting	Info
C00509/1	0x0006	PW protection config X1 (CAN)
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C00510

Parameter Name: C00510 PW protection config MCI		Data type: UNSIGNED_16 Index: 24065 _d = 5E01 _h
From version 15.00.00 Configuration of the password protection for parameter access via fieldbus interface ("MCI") ▶ Individual password protection for single communication channels		
Setting range (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		Info
Bit 0	Reserved	
Bit 1	Parameter write protection	The fieldbus interface (MCI) cannot be used to write into write/read parameters.
Bit 2	Parameter read protection	The fieldbus interface (MCI) cannot be used to read write/read parameters.
Bit 3	Reserved	
Bit 4	Reserved	
Bit 5	Reserved	
Bit 6	Reserved	
Bit 7	Reserved	
Bit 8	Reserved	
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	Reserved	
Bit 15	Reserved	
Subcodes	Lenze setting	Info
C00510/1	0x0006	PW protection config. MCI
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C00516

Parameter Name: C00516 Checksums		Data type: UNSIGNED_32 Index: 24059 _d = 5DFB _h
This code is for device-internal use only and must not be written to by the user!		

C00517

Parameter Name: C00517 User menu		Data type: INTEGER_32 Index: 24058 _d = 5DFA _h	
When a system is installed, parameters must be changed time and again until the system runs satisfactorily. The user menu of a device serves to create a selection of frequently used parameters to be able to access and change these parameters quickly.			
• Format: <code number>,<subcode number>			
• If "0.000" is set, no entry will be displayed in the user menu.			
Setting range (min. value unit max. value)			
0.000		16000.000	
Subcodes	Lenze setting	Info	
C00517/1	51.000	C00051 : Display of actual speed value	
C00517/2	53.000	C00053 : Display of DC-bus voltage	
C00517/3	54.000	C00054 : Display of motor current	
C00517/4	61.000	C00061 : Display of heatsink temperature	
C00517/5	137.000	C00137 : Display of device status	
C00517/6	166.003	C00166/3 : Display of current error message	
C00517/7	0.000	User menu: Entry 7	
C00517/8	11.000	C00011 : Reference speed	
C00517/9	39.001	C00039/1 : Fixed setpoint 1	
C00517/10	39.002	C00039/2 : Fixed setpoint 2	
C00517/11	12.000	C00012 : Accel. time - main setpoint	
C00517/12	13.000	C00013 : Decel. time - main setpoint	
C00517/13	15.000	C00015 : V/f base frequency	
C00517/14	16.000	C00016 : Vmin boost	
C00517/15	22.000	C00022 : I _{max} in motor mode	
C00517/16	120.000	C00120 : Setting of motor overload (I ² _{xt})	
C00517/17	87.000	C00087 : Rated motor speed	
C00517/18	99.000	C00099 : Display of firmware version	
C00517/19	200.000	C00200 : Display of firmware product type	
C00517/20	0.000	User menu: Entry 20	
C00517/21	0.000	User menu: Entry 21	
C00517/22	0.000	User menu: Entry 22	
C00517/23	0.000	User menu: Entry 23	
C00517/24	105.000	C00105 : Decel. time - quick stop	
C00517/25	173.000	C00173 : Mains voltage	
C00517/26	0.000	User menu: Entry 26	
C00517/27	0.000	User menu: Entry 27	
C00517/28	0.000	User menu: Entry 28	
C00517/29	0.000	User menu: Entry 29	
C00517/30	0.000	User menu: Entry 30	
C00517/31	0.000	User menu: Entry 31	
C00517/32	0.000	User menu: Entry 32	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C00540

Parameter Name:		Data type: UNSIGNED_8	
C00540 LS_DFOut: Function		Index: 24035 _d = 5DE3 _h	
From version 12.00.00			
Selection of the signal source for the digital frequency output (multi-encoder interface X8)			
<div>► Digital frequency coupling</div>			
Selection list (Lenze setting printed in bold)			
1	Off		
2	DFIn		
3	MotorSpeed		
4	LoadSpeed		
5	Resolver		
6	DigIn 1/2		
7	FB input		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C00545

Parameter Name: C00545 LS_DFOut: Angular offset			Data type: INTEGER_32 Index: 24030 _d = 5DDE _h		
From version 12.00.00					
▸ Digital frequency coupling					
Setting range (min. value unit max. value)					
0	Incr.	65535			
Subcodes	Lenze setting		Info		
C00545/1	0 incr.		LS_DFOut : Angular offset		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00560

Parameter Name: C00560 Fan switching status		Data type: UNSIGNED_8 Index: 24015 _d = 5DCF _h	
Display of the function status of the device fans			
Selection list			
0	Off		
1	On		
2	No fan		
Subcodes		Info	
C00560/1		Switching status - internal fan	
C00560/2		Switching status - heatsink fan	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00561

Parameter Name: C00561 Failure indication		Data type: UNSIGNED_8 Index: 24014 _d = 5DC _{Eh}	
Failure display of device fans and motor phases			
Selection list			
0	No error		
1	Fault		
Subcodes		Info	
C00561/1		Internal fan	
C00561/2		Heatsink fan	
C00561/3		Motor phase U • From version 02.00.00	
C00561/4		Motor phase V • From version 02.00.00	
C00561/5		Motor phase W • From version 02.00.00	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00565

Parameter Name: C00565 Resp. to mains phase failure		Data type: UNSIGNED_8 Index: 24010 _d = 5DCA _h	
Response to the failure of mains phases			
Selection list (Lenze setting printed in bold)			
0	No Reaction		
1	Fault		
5	Warning		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00566

Parameter Name: C00566 Resp. to fan failure		Data type: UNSIGNED_8 Index: 24009 _d = 5DC9 _h	
Response to the detection of a fan failure			
Selection list (Lenze setting printed in bold)			
0	No Reaction		
1	Fault		
5	Warning		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00567

Parameter Name:		Data type: UNSIGNED_8 Index: 24008 _d = 5DC8 _h	
C00567 Resp. to speed controller limited			
Response if speed controller output is limited (<i>bLimSpeedCtrlOut</i> = TRUE)			
Selection list (Lenze setting printed in bold)			
0	No Reaction		
1	Fault		
5	Warning		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00569

Parameter Name: C00569 Resp. to peak current		Data type: UNSIGNED_8 Index: 24006 _d = 5DC6 _h
Configuration of monitoring of the motor control (group 1)		
Selection list		
0	No Reaction	
1	Fault	
5	Warning	
Subcodes	Lenze setting	Info
C00569/1	0: No Reaction	Response for overcurrent detection and clamp operation
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00570

Parameter Name: C00570 Resp. to controller limitations		Data type: UNSIGNED_8 Index: 24005 _d = 5DC5 _h
Configuration of monitoring of the motor control (group 2)		
Selection list		
0	No Reaction	
1	Fault	
5	Warning	
Subcodes	Lenze setting	Info
C00570/1	0: No Reaction	Response if direct-axis current controller is limited • e.g. at servo control (SC)
C00570/2	0: No Reaction	Response if cross current controller is limited • e.g. at servo control (SC)
C00570/3	0: No Reaction	Response if torque setpoint is limited • Limitation of the speed controller output, the differential setpoint precontrol, and of the additive torque at (SC) servo control and (SLVC) sensorless vector control.
C00570/4	0: No Reaction	Response if field controller is limited
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00571

Parameter Name:		Data type: UNSIGNED_8	
C00571 Resp. to wrong controller setting		Index: 24004 _d = 5DC4 _h	
From version 14.00.00			
Selection list			
0	No Reaction		
1	Fault		
2	Trouble		
3	TroubleQuickStop		
4	WarningLocked		
5	Warning		
6	Information		
Subcodes	Lenze setting	Info	
C00571/1	6: Information	Resp. to: Motor control does not match motor data	
C00571/2	1: Fault	Resp. to a non-set speed controller	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00572

Parameter Name:			Data type: UNSIGNED_8
C00572 Brake resistor overload threshold			Index: 24003 _d = 5DC3 _h
Adjustable threshold for monitoring the brake resistor utilisation			
• The response for reaching the threshold can be selected in C00574 .			
Setting range (min. value unit max. value)			Lenze setting
0	%	100	100 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT			Scaling factor: 1

C00574

Parameter Name:		Data type: UNSIGNED_8 Index: 24001 _d = 5DC1 _h	
C00574 Resp. to brake resist. overtemp.			
Response which is triggered if the threshold set in C00572 for monitoring brake resistor utilisation is reached.			
Selection list (Lenze setting printed in bold)			
0	No Reaction		
1	Fault		
5	Warning		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00576

Parameter Name:			Data type: UNSIGNED_16		
C00576 SC: Optimisation of field feedforward control			Index: 23999 _d = 5DBF _h		
Point of action of the direct-axis current setpoint precontrol for an early reduction of the field current. In this way, the acceleration behaviour can be improved in the field weakening range.					
• The entry [%] refers to the slip of the asynchronous motor.					
Setting range (min. value unit max. value)				Lenze setting	
0	%	600	200 %		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C00577

Parameter Name: C00577 SC: Vp field weakening controller			Data type: UNSIGNED_16 Index: 23998 _d = 5DBE _h		
Proportional gain of the field weakening controller <ul style="list-style-type: none">• When "0" is set, the P component of the controller is deactivated.• The recommended setting is in the range between 0 and 0.0020					
Setting range (min. value unit max. value)			Lenze setting		
0.0000			2.0000		0.0010
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000					

C00578

Parameter Name: C00578 SC: Tn field weakening controller			Data type: UNSIGNED_16 Index: 23997 _d = 5DBD _h		
Time constant of the field weakening controller • The recommended setting is in the range between 10 and 30 ms					
Setting range (min. value unit max. value)			Lenze setting		
0.1	ms	6000.0	20.0 ms		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10					

C00579

Parameter Name:		Data type: UNSIGNED_8	
C00579 Resp. to max. speed/output freq. reached		Index: 23996 _d = 5DBC _h	
Response when the max. speed limit (C00909) or output frequency limit (C00910) has been reached.			
Selection list (Lenze setting printed in bold)			
0	No Reaction		
1	Fault		
5	Warning		
<input checked="" type="checkbox"/> Read access		<input checked="" type="checkbox"/> Write access	
<input type="checkbox"/> CINH		<input type="checkbox"/> PLC STOP	
<input type="checkbox"/> No transfer		<input type="checkbox"/> COM	
<input checked="" type="checkbox"/> MOT		Scaling factor: 1	

C00580

Parameter Name:		Data type: UNSIGNED_8	
C00580 Resp. to operating system error		Index: 23995 _d = 5DBB _h	
From version 02.00.00			
Response if the required computing time of the application exceeds the available computing time.			
Selection list			
0	No Reaction		
1	Fault		
5	Warning		
Subcodes	Lenze setting	Info	
C00580/1	0: No Reaction	Resp. to runtime exceedance	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00581

Parameter Name: C00581 Resp. to LS_SetError_x		Data type: UNSIGNED_8 Index: 23994 _d = 5DBA _h
Selection of the error responses for application error messages • An application error message is tripped by a FALSE/TRUE edge at the binary inputs <i>bSetError1...4</i> .		
Selection list		
0	No Reaction	
1	Fault	
2	Trouble	
3	TroubleQuickStop	
4	WarningLocked	
5	Warning	
6	Information	
Subcodes	Lenze setting	Info
C00581/1	0: No Reaction	LS_SetError_1 : Resp. to bSetError1
C00581/2	0: No Reaction	LS_SetError_1 : Resp. to bSetError2
C00581/3	0: No Reaction	LS_SetError_1 : Resp. to bSetError3
C00581/4	0: No Reaction	LS_SetError_1 : Resp. to bSetError4
C00581/5	0: No Reaction	LS_SetError_2 : Resp. to bSetError1
C00581/6	0: No Reaction	LS_SetError_2 : Resp. to bSetError2
C00581/7	0: No Reaction	LS_SetError_2 : Resp. to bSetError3
C00581/8	0: No Reaction	LS_SetError_2 : Resp. to bSetError4
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00582

Parameter Name:		Data type: UNSIGNED_8 Index: 23993 _d = 5DB9 _h
C00582 Resp. to heatsink temp. > shutdown temp. -5°C		
Response if the heatsink temperature has reached the switch-off temperature threshold.		
Selection list (Lenze setting printed in bold)		
0	No Reaction	
1	Fault	
5	Warning	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00583

Parameter Name: C00583 Resp. to motor temperature KTY		Data type: UNSIGNED_8 Index: 23992 _d = 5DB8 _h
Response to motor overtemperature <ul style="list-style-type: none"> The motor temperature is measured via the resolver or encoder cable. <p>► Encoder/feedback system: Motor temperature monitoring (KTY)</p>		
Selection list		
0	No Reaction	
1	Fault	
3	TroubleQuickStop	
4	WarningLocked	
5	Warning	
6	Information	
Subcodes	Lenze setting	Info
C00583/1	1: Fault	Resp. to motor overtemp. KTY resolver
C00583/2	1: Fault	Resp. to motor overtemp. KTY MultiEncoder
C00583/3	5: Warning	Resp. to motor temp. > C00121 resolver
C00583/4	5: Warning	Resp. to motor temp. > C00121 encoder
C00583/5	1: Fault	Resp. to temp. sensor error KTY resolver
C00583/6	1: Fault	Resp. to temp. sensor error KTY MultiEncoder
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00585

Parameter Name: C00585 Resp. to motor overtemp. PTC		Data type: UNSIGNED_8 Index: 23990 _d = 5DB6 _h
Response to motor overtemperature <ul style="list-style-type: none"> The motor temperature is measured by means of a PTC thermistor at terminal X106. 		
Selection list (Lenze setting printed in bold)		
0	No Reaction	
1	Fault	
5	Warning	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00586

Parameter Name: C00586 Resp. to open circuit HTL encoder		Data type: UNSIGNED_8 Index: 23989 _d = 5DB5 _h
Response to encoder feedback system failure or encoder feedback system track failure due to open circuit		
Selection list (Lenze setting printed in bold)		
0	No Reaction	
1	Fault	
5	Warning	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00588

Parameter Name: C00588 Resp. to max. speed at switching freq.		Data type: UNSIGNED_8 Index: 23987 _d = 5DB3 _h
Response if the maximum speed for the set inverter switching frequency is reached (C00018)		
Selection list (Lenze setting printed in bold)		
0	No Reaction	
1	Fault	
5	Warning	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00590

Parameter Name: C00590 Resp. to switching frequency red.		Data type: UNSIGNED_8 Index: 23985 _d = 5DB1 _h
Response to reduction of the inverter switching frequency (C00018)		
Selection list (Lenze setting printed in bold)		
0	No Reaction	
1	Fault	
5	Warning	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00591

Parameter Name: C00591 Resp. to axis bus error		Data type: UNSIGNED_8 Index: 23984 _d = 5DB0 _h
From version 12.00.00 Configuration of axis bus monitoring		
<div> <div></div> <div>► Axis bus</div> </div>		
Selection list		
0	No Reaction	
1	Fault	
2	Trouble	
3	TroubleQuickStop	
4	WarningLocked	
5	Warning	
6	Information	
Subcodes	Lenze setting	Info
C00591/1	0: No Reaction	Resp. to axis bus data error ► Data transfer axis bus
C00591/2	0: No Reaction	Resp. to axis bus IO error ► IO axis bus
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00592

Parameter Name: C00592 Resp. to CAN bus connection		Data type: UNSIGNED_8 Index: 23983 _d = 5DAF _h
Configuration of monitoring of the CAN interface (group 1)		
▶ "CAN on board" system bus		
Selection list		
0	No Reaction	
1	Fault	
2	Trouble	
3	TroubleQuickStop	
4	WarningLocked	
5	Warning	
6	Information	
Subcodes	Lenze setting	Info
C00592/1	0: No Reaction	Response to incorrect telegram for CAN communication
C00592/2	0: No Reaction	Response to "BusOff" (bus system switched off)
C00592/3	0: No Reaction	Response to warnings of the CAN controller
C00592/4	0: No Reaction	Response to communication stop of a CAN bus node
C00592/5	0: No Reaction	Response to an event in the case of monitoring via heartbeat protocol
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00593

Parameter Name: C00593 Resp. to CANx_IN monitoring		Data type: UNSIGNED_8 Index: 23982 _d = 5DAE _h
Configuration of monitoring of the CAN interface (group 2)		
▶ "CAN on board" system bus		
Selection list		
0	No Reaction	
1	Fault	
2	Trouble	
3	TroubleQuickStop	
4	WarningLocked	
5	Warning	
6	Information	
Subcodes	Lenze setting	Info
C00593/1	0: No Reaction	Response if the monitoring time set in C00357/1 for the reception of the PDO CAN1_IN is exceeded.
C00593/2	0: No Reaction	Response if the monitoring time set in C00357/2 for the reception of the PDO CAN2_IN is exceeded.
C00593/3	0: No Reaction	Response if the monitoring time set in C00357/3 for the reception of the PDO CAN3_IN is exceeded.
C00593/4	0: No Reaction	Response if the monitoring time set in C00357/4 for the reception of the PDO CAN4_IN is exceeded. • From version 15.00.00
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00594

Parameter Name:		Data type: UNSIGNED_8 Index: 23981 _d = 5DAD _h	
C00594 Resp. to control word error			
Configuration of device control monitoring			
Selection list			
0	No Reaction		
1	Fault		
2	Trouble		
3	TroubleQuickStop		
5	Warning		
Subcodes	Lenze setting	Info	
C00594/1	1: Fault	Response if error bit 14 in the CAN control word is set.	
C00594/2	1: Fault	Response if error bit 14 in the MCI control word is set.	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00595

Parameter Name:		Data type: UNSIGNED_8
C00595 MCK: Resp. to MCK error		Index: 23980 _d = 5DAC _h
Configuration of monitoring of the Motion Control Kernel		
<div>► Basic drive functions</div>		
Selection list		
0	No Reaction	
1	Fault	
3	TroubleQuickStop	
4	WarningLocked	
5	Warning	
6	Information	
Subcodes	Lenze setting	Info
C00595/1	3: TroubleQuickStop	Response if the input <i>bLimitSwitchPos</i> for travel range monitoring is set to FALSE (fail-safe) by the positive hardware limit switch .
C00595/2	3: TroubleQuickStop	Response if the input <i>bLimitSwitchNeg</i> for travel range monitoring is set to FALSE (fail-safe) by the negative hardware limit switch .
C00595/3	3: TroubleQuickStop	Response for detection that the position is beyond the positive software limit position (C01229/1).
C00595/4	3: TroubleQuickStop	Response for detection that the position is beyond the negative software limit position (C01229/2).
C00595/5	5: Warning	Response if following error limit 1 is exceeded (C01215/1)
C00595/6	5: Warning	Response if following error limit 2 is exceeded (C01215/2)
C00595/7	3: TroubleQuickStop	Response if the maximum travel distance (display in C01213/1) is exceeded
C00595/8	4: WarningLocked	Response to start procedures with reference condition when the reference is not set
C00595/9	4: WarningLocked	Response to a non-supported positioning mode
C00595/10	4: WarningLocked	Response to implausible profile set data
C00595/11	5: Warning	Response to the selection of an invalid operating mode of the MCK
C00595/12	4: WarningLocked	Response to indicating an invalid profile data set
C00595/13	5: Warning	Response to an error of the FB L_MckCtrlInterface_1
C00595/14	4: WarningLocked	Response to a profile start with a target position outside the software limit positions (C01229/1 and C01229/2).
C00595/15	1: Fault	Response to activated connection monitoring in case of PC manual control
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1</div>		

C00597

Parameter Name: C00597 Resp. to motor phase failure		Data type: UNSIGNED_8 Index: 23978 _d = 5DAA _h
Response to motor phase failure <ul style="list-style-type: none"> If a phase current does not exceed the threshold set in C00599 for more than one period, the response set here will be triggered. 		
Selection list (Lenze setting printed in bold)		
0	No Reaction	
1	Fault	
5	Warning	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00598

Parameter Name: C00598 Resp. to open circuit AINx		Data type: UNSIGNED_8 Index: 23977 _d = 5DA9 _h
Configuration of monitoring of the analog inputs ▶ Analog terminals		
Selection list		
0	No Reaction	
1	Fault	
2	Trouble	
3	TroubleQuickStop	
5	Warning	
Subcodes	Lenze setting	Info
C00598/1	3: TroubleQuickStop	Response to open circuit at AIN1 if configured as 4 ... 20 mA current loop
C00598/2	3: TroubleQuickStop	Response to open circuit at AIN2 when being configured as 4 ... 20 mA-current loop
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00599

Parameter Name: C00599 Motor phase failure threshold		Data type: INTEGER_16 Index: 23976 _d = 5DA8 _h
Threshold for motor phase failure monitoring <ul style="list-style-type: none"> 100 % ≡ rated inverter current (C00098) If a phase current does not exceed the threshold set here for more than one period, the response to motor phase failure set in C00597 will be triggered. 		
Setting range (min. value unit max. value)		Lenze setting
0.00	%	100.00 5.00 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100		

C00600

Parameter Name:			Data type: UNSIGNED_8		
C00600 Resp. to DC bus voltage			Index: 23975 _d = 5DA7 _h		
Configuration of monitoring of the motor control (group 3)					
Selection list					
1	Fault				
2	Trouble				
Subcodes		Lenze setting		Info	
C00600/1		2: Trouble		Response to DC bus undervoltage	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C00601

Parameter Name: C00601 Del. resp. to fault: DC bus overvoltage			Data type: UNSIGNED_16 Index: 23974 _d = 5DA6 _h
Error response delay times			
Setting range (min. value unit max. value)			
0.000	s	65.000	
Subcodes	Lenze setting	Info	
C00601/1	2.000 s	Delay time for triggering the "DC-bus overvoltage" error • If a DC-bus overvoltage occurs, an error will not be triggered until the set delay time has elapsed.	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1000			

C00602

Parameter Name:		Data type: UNSIGNED_8	
C00602 Resp. to earth fault		Index: 23973 _d = 5DA5 _h	
Response to earth fault in the motor phase(s)			
Selection list (Lenze setting printed in bold)			
0	No Reaction		
1	Fault		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00603

Parameter Name: C00603 Resp. to feedback		Data type: UNSIGNED_8 Index: 23972 _d = 5DA4 _h
Response of different monitoring modes for the encoder/feedback system		
Encoder/feedback system		
Selection list		
0	No Reaction	
1	Fault	
2	Trouble	
3	TroubleQuickStop	
4	WarningLocked	
5	Warning	
6	Information	
Subcodes	Lenze setting	Info
C00603/1	1: Fault	Resp. to MultiEncoder open circuit
C00603/2	1: Fault	Resp. to resolver open circuit
C00603/3	0: No Reaction	Up to and including version 02.xx.xx: Resp. to encoder communication error From version 12.00.00: Resp. to encoder angular drift monitoring
C00603/4	1: Fault	Up to and including version 02.xx.xx: Resp. to encoder angular drift monitoring From version 12.00.00: Resp. to encoder communication error
C00603/5	6: Information	Resp. to Hiperface status • From version 14.00.00
C00603/6	6: Information	Resp. to invalid Hiperface position • From version 14.00.00
C00603/7	6: Information	Resp. to SinCos inaccuracy • From version 14.00.00
C00603/8	1: Fault	Resp. to Hiperface sin/cos deviation • From version 15.00.00
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00604

Parameter Name: C00604 Resp. to device overload (lxt)		Data type: UNSIGNED_8 Index: 23971 _d = 5DA3 _h
Response if the adjustable device utilisation threshold (C00123) is reached.		
• The current device utilisation is displayed in C00064 .		
Selection list (Lenze setting printed in bold)		
0	No Reaction	
1	Fault	
5	Warning	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00605

Parameter Name: C00605 Resp. to feedback		Data type: UNSIGNED_8 Index: 23970 _d = 5DA2 _h
From version 15.00.00		
Selection list		
0	No Reaction	
1	Fault	
2	Trouble	
3	TroubleQuickStop	
4	WarningLocked	
5	Warning	
6	Information	
Subcodes	Lenze setting	Info
C00605/1	1: Fault	Resp. to open circuit HTL 4-fold
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00606

Parameter Name: C00606 Resp. to motor overload (I²xt)		Data type: UNSIGNED_8 Index: 23969 _d = 5DA1 _h
Response when the motor load displayed in C00066 reaches the value "100.00 %". <div>▶ Motor overload monitoring (I2xt)</div>		
Selection list (Lenze setting printed in bold)		
0	No Reaction	
1	Fault	
5	Warning	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00607

Parameter Name: C00607 Resp. to max freq. feedb. DIG12/67		Data type: UNSIGNED_8 Index: 23968 _d = 5DA0 _h
Response when the maximum input frequency has been reached via the digital inputs.		
Selection list (Lenze setting printed in bold)		
0	No Reaction	
1	Fault	
5	Warning	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00608

Parameter Name: C00608 Resp. to maximum torque		Data type: UNSIGNED_8 Index: 23967 _d = 5D9F _h
Response if the maximum torque (C00057) is reached.		
Selection list (Lenze setting printed in bold)		
0	No Reaction	
1	Fault	
5	Warning	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00609

Parameter Name: C00609 Resp. to maximum current		Data type: UNSIGNED_8 Index: 23966 _d = 5D9E _h
Response if the maximum current (C00022 , C00023) is reached.		
Selection list (Lenze setting printed in bold)		
0	No Reaction	
1	Fault	
5	Warning	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00610

Parameter Name: C00610 16-bit connection table		Data type: UNSIGNED_16 Index: 23965 _d = 5D9D _h
This code is for device-internal use only and must not be written to by the user!		

C00611

Parameter Name: C00611 Bool connection table		Data type: UNSIGNED_16 Index: 23964 _d = 5D9C _h
This code is for device-internal use only and must not be written to by the user!		

C00612

Parameter Name: C00612 32-bit connection table		Data type: UNSIGNED_16 Index: 23963 _d = 5D9B _h
This code is for device-internal use only and must not be written to by the user!		

C00613

Parameter Name: C00613 16-bit connection table AdditionalFBsHL		Data type: UNSIGNED_16 Index: 23962 _d = 5D9A _h
This code is for device-internal use only and must not be written to by the user!		

C00615

Parameter Name: C00615 Bool connection table AdditionalFBsHL		Data type: UNSIGNED_16 Index: 23960 _d = 5D98 _h
This code is for device-internal use only and must not be written to by the user!		

C00617

Parameter Name: C00617 32-bit connection table AdditionalFBsHL		Data type: UNSIGNED_16 Index: 23958 _d = 5D96 _h
This code is for device-internal use only and must not be written to by the user!		

C00620

Parameter Name: C00620 System connection list: 16-bit		Data type: UNSIGNED_16 Index: 23955 _d = 5D93 _h
Connection parameters: 16-bit inputs <ul style="list-style-type: none"> • Selection of the 16 bit output signals to be connected to the 16 bit input signals • The selection list contains all 16 bit output signals which can be assigned to the 16 bit inputs displayed by the subcodes. • Non-listed subcodes are "reserved". 		
Selection list		
See selection list - analog signals		
Subcodes	Lenze setting	Info
C00620/1	1003: LA_NCtrl: nMotorSpeedAct_a	LS_AnalogOutput : nOut1_a (V) Analog output 1: Voltage
C00620/2	0: Not connected	LP_CanOut1 : wState CAN1 output: Status word
C00620/3	0: Not connected	LP_CanOut1 : wOut2 CAN1 output: Data word 2
C00620/4	0: Not connected	LP_CanOut1 : wOut3 CAN1 output: Data word 3
C00620/5	0: Not connected	LP_CanOut1 : wOut4 CAN1 output: Data word 4
C00620/6	0: Not connected	LP_CanOut2 : wOut1 CAN2 output: Data word 1
C00620/7	0: Not connected	LP_CanOut2 : wOut2 CAN2 output: Data word 2
C00620/8	0: Not connected	LP_CanOut2 : wOut3 CAN2 output: Data word 3
C00620/9	0: Not connected	LP_CanOut2 : wOut4 CAN2 output: Data word 4
C00620/10	0: Not connected	LP_CanOut3 : wOut1 CAN3 output: Data word 1
C00620/11	0: Not connected	LP_CanOut3 : wOut2 CAN3 output: Data word 2
C00620/12	0: Not connected	LP_CanOut3 : wOut3 CAN3 output: Data word 3
C00620/13	0: Not connected	LP_CanOut3 : wOut4 CAN3 output: Data word 4
C00620/14	0: Not connected	LS_DisFree_a : nDis1_a Display of analog signal 1
C00620/15	0: Not connected	LS_DisFree_a : nDis2_a Display of analog signal 2
C00620/16	0: Not connected	LS_DisFree_a : nDis3_a Display of analog signal 3
C00620/17	0: Not connected	LS_DisFree_a : nDis4_a Display of analog signal 4
C00620/18	0: Not connected	LS_DisFree : wDis1 Display of 16-bit signal 1
C00620/19	0: Not connected	LS_DisFree : wDis2 Display of 16-bit signal 2
C00620/20	0: Not connected	LS_DisFree : wDis3 Display of 16-bit signal 3

Parameter Name: C00620 System connection list: 16-bit		Data type: UNSIGNED_16 Index: 23955 _d = 5D93 _h
C00620/21	0: Not connected	LS_DisFree : wDis4 Display of 16-bit signal 4
C00620/22	0: Not connected	LP_MciOut : wState MCI output: Status word
C00620/23	0: Not connected	LP_MciOut : wOut2 MCI output: Data word 2
C00620/24	0: Not connected	LP_MciOut : wOut3 MCI output: Data word 3
C00620/25	0: Not connected	LP_MciOut : wOut4 MCI output: Data word 4
C00620/26	0: Not connected	LP_MciOut : wOut5 MCI output: Data word 5
C00620/27	0: Not connected	LP_MciOut : wOut6 MCI output: Data word 6
C00620/28	0: Not connected	LP_MciOut : wOut7 MCI output: Data word 7
C00620/29	0: Not connected	LP_MciOut : wOut8 MCI output: Data word 8
C00620/30	0: Not connected	LP_MciOut : wOut9 MCI output: Data word 9
C00620/31	0: Not connected	LP_MciOut : wOut10 MCI output: Data word 10
C00620/32	0: Not connected	LP_MciOut : wOut11 MCI output: Data word 11
C00620/33	0: Not connected	LP_MciOut : wOut12 MCI output: Data word 12
C00620/34	0: Not connected	LP_MciOut : wOut13 MCI output: Data word 13
C00620/35	0: Not connected	LP_MciOut : wOut14 MCI output: Data word 14
C00620/36	0: Not connected	LP_MciOut : wOut15 MCI output: Data word 15
C00620/37	0: Not connected	LP_MciOut : wOut16 MCI output: Data word 16
C00620/38	0: Not connected	LS_AnalogOutput : nOut2_a (V) Analog output 2: Voltage
C00620/39	0: Not connected	LS_AnalogOutput : nOut1_a (I) Analog output 1: Current
C00620/40	0: Not connected	LS_AnalogOutput : nOut2_a (I) Analog output 2: Current
C00620/41	0: Not connected	LS_DisFree_a : nDis5_a Display of analog signal 5
C00620/42	0: Not connected	LS_DisFree_a : nDis6_a Display of analog signal 6
C00620/43	0: Not connected	LS_DisFree_a : nDis7_a Display of analog signal 7
C00620/44	0: Not connected	LS_DisFree_a : nDis8_a Display of analog signal 8
C00620/45	0: Not connected	LS_DisFree : wDis5 Display of 16-bit signal 5

Parameter Name: C00620 System connection list: 16-bit		Data type: UNSIGNED_16 Index: 23955 _d = 5D93 _h
C00620/46	0: Not connected	LS_DisFree : wDis6 Display of 16-bit signal 6
C00620/47	0: Not connected	LS_DisFree : wDis7 Display of 16-bit signal 7
C00620/48	0: Not connected	LS_DisFree : wDis8 Display of 16-bit signal 8
C00620/49	0: Not connected	LS_ParReadWrite_1 : wParIndex Read/write request 1: Code
C00620/50	0: Not connected	LS_ParReadWrite_1 : wParSubindex Read/write request 1: Subcode
C00620/51	0: Not connected	LS_ParReadWrite_1 : wInHWord Read/write request 1: Value (high word)
C00620/52	0: Not connected	LS_ParReadWrite_1 : wInLWord Read/write request 1: Value (low word)
C00620/53	0: Not connected	LS_ParReadWrite_2 : wParIndex Read/write request 2: Code
C00620/54	0: Not connected	LS_ParReadWrite_2 : wParSubindex Read/write request 2: Subcode
C00620/55	0: Not connected	LS_ParReadWrite_2 : wInHWord Read/write request 2: Value (high word)
C00620/56	0: Not connected	LS_ParReadWrite_2 : wInLWord Read/write request 2: Value (low word)
C00620/57	0: Not connected	LS_ParReadWrite_3 : wParIndex Read/write request 3: Code
C00620/58	0: Not connected	LS_ParReadWrite_3 : wParSubindex Read/write request 3: Subcode
C00620/59	0: Not connected	LS_ParReadWrite_3 : wInHWord Read/write request 3: Value (high word)
C00620/60	0: Not connected	LS_ParReadWrite_3 : wInLWord Read/write request 3: Value (low word)
C00620/61	0: Not connected	LS_ParReadWrite_4 : wParIndex Read/write request 4: Code
C00620/62	0: Not connected	LS_ParReadWrite_4 : wParSubindex Read/write request 4: Subcode
C00620/63	0: Not connected	LS_ParReadWrite_4 : wInHWord Read/write request 4: Value (high word)
C00620/64	0: Not connected	LS_ParReadWrite_4 : wInLWord Read/write request 4: Value (low word)
C00620/65	0: Not connected	LS_ParReadWrite_5 : wParIndex Read/write request 5: Code
C00620/66	0: Not connected	LS_ParReadWrite_5 : wParSubindex Read/write request 5: Subcode
C00620/67	0: Not connected	LS_ParReadWrite_5 : wInHWord Read/write request 5: Value (high word)
C00620/68	0: Not connected	LS_ParReadWrite_5 : wInLWord Read/write request 5: Value (low word)
C00620/69	0: Not connected	LS_ParReadWrite_6 : wParIndex Read/write request 6: Code
C00620/70	0: Not connected	LS_ParReadWrite_6 : wParSubindex Read/write request 6: Subcode

Parameter Name: C00620 System connection list: 16-bit		Data type: UNSIGNED_16 Index: 23955 _d = 5D93 _h
C00620/71	0: Not connected	LS_ParReadWrite_6 : wInHWord Read/write request 6: Value (high word)
C00620/72	0: Not connected	LS_ParReadWrite_6 : wInLWord Read/write request 6: Value (low word)
C00620/89	0: Not connected	LS_RetainData : wIn1 Retain data: 16-bit input value 1
C00620/90	0: Not connected	LS_RetainData : wIn2 Retain data: 16-bit input value 2
C00620/91	0: Not connected	LS_RetainData : wIn3 Retain data: 16-bit input value 3
C00620/92	0: Not connected	LS_RetainData : wIn4 Retain data: 16-bit input value 4
C00620/93	0: Not connected	LS_AxisBusOut : wLine1 Axis bus output: Line data (word 1)
C00620/94	0: Not connected	LS_AxisBusOut : wLine2 Axis bus output: Line data (word 2)
C00620/95	0: Not connected	LS_AxisBusOut : wLine3 Axis bus output: Line data (word 3)
C00620/96	0: Not connected	LS_AxisBusOut : wCas1 Axis bus output: Cascaded data (word 1)
C00620/97	0: Not connected	LS_AxisBusOut : wCas2 Axis bus output: Cascaded data (word 2)
C00620/98	0: Not connected	LS_AxisBusOut : wCas3 Axis bus output: Cascaded data (word 3)
C00620/99	0: Not connected	LS_AxisBusOut : wCas4 Axis bus output: Cascaded data (word 4)
C00620/100	0: Not connected	LS_AxisBusAux : wAuxOut1 Axis bus output: @sel data (word 1)
C00620/101	0: Not connected	LS_AxisBusAux : wAuxOut2 Axis bus output: @sel data (word 2)
C00620/102	0: Not connected	LS_AxisBusAux : wAuxOut3 Axis bus output: @sel data (word 3)
C00620/103	0: Not connected	LS_AxisBusAux : wAuxOut4 Axis bus output: @sel data (word 4)
C00620/104	0: Not connected	LS_AxisBusAux : wSelectSlave Axis bus address of slave
C00620/105	0: Not connected	LS_DFOut : nOut_v Digital frequency output X8: Speed in [increments/ms]
C00620/106	0: Not connected	LS_MultiEncoder : wActPosExternalHW
C00620/107	0: Not connected	LS_MultiEncoder : wActPosExternalLW
C00620/108	0: Not connected	LP_CanOut4 : wOut1 CAN4 output: Data word 1
C00620/109	0: Not connected	LP_CanOut4 : wOut2 CAN4 output: Data word 2
C00620/110	0: Not connected	LP_CanOut4 : wOut3 CAN4 output: Data word 3
C00620/111	0: Not connected	LP_CanOut4 : wOut4 CAN4 output: Data word 4
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00621

Parameter Name: C00621 System connection list: Bool		Data type: UNSIGNED_16 Index: 23954 _d = 5D92 _h
Connection parameters: Binary inputs <ul style="list-style-type: none"> • Selection of the binary output signals to be connected to the binary input signals • The selection list contains all binary output signals which can be assigned to the binary inputs mapped by the subcodes. • Non-listed subcodes are "reserved". 		
Selection list		
See selection list - digital signals		
Subcodes	Lenze setting	Info
C00621/1	1001: LA_NCtrl: bDriveFail	LS_DigitalOutput : bRelay Digital relay output: Input signal
C00621/2	1000: LA_NCtrl: bDriveReady	LS_DigitalOutput : bOut1 Digital output 1: Input signal
C00621/3	0: Not connected	LS_DigitalInput : bCountIn1_Reset Digital input 1: Reset counter
C00621/4	0: Not connected	LS_DigitalInput : bCountIn1_LoadStartValue Digital input 1: Load counter starting value
C00621/5	0: Not connected	LP_CanOut1 : bState_B0 CAN1 output: Status word - bit 0
C00621/6	0: Not connected	LP_CanOut1 : bState_B1 CAN1 output: Status word - bit 1
C00621/7	0: Not connected	LP_CanOut1 : bState_B2 CAN1 output: Status word - bit 2
C00621/8	0: Not connected	LP_CanOut1 : bState_B3 CAN1 output: Status word - bit 3
C00621/9	0: Not connected	LP_CanOut1 : bState_B4 CAN1 output: Status word - bit 4
C00621/10	0: Not connected	LP_CanOut1 : bState_B5 CAN1 output: Status word - bit 5
C00621/11	0: Not connected	LP_CanOut1 : bState_B6 CAN1 output: Status word - bit 6
C00621/12	0: Not connected	LP_CanOut1 : bState_B7 CAN1 output: Status word - bit 7
C00621/13	0: Not connected	LP_CanOut1 : bState_B8 CAN1 output: Status word - bit 8
C00621/14	0: Not connected	LP_CanOut1 : bState_B9 CAN1 output: Status word - bit 9
C00621/15	0: Not connected	LP_CanOut1 : bState_B10 CAN1 output: Status word - bit 10
C00621/16	0: Not connected	LP_CanOut1 : bState_B11 CAN1 output: Status word - bit 11
C00621/17	0: Not connected	LP_CanOut1 : bState_B12 CAN1 output: Status word - bit 12
C00621/18	0: Not connected	LP_CanOut1 : bState_B13 CAN1 output: Status word - bit 13
C00621/19	0: Not connected	LP_CanOut1 : bState_B14 CAN1 output: Status word - bit 14
C00621/20	0: Not connected	LP_CanOut1 : bState_B15 CAN1 output: Status word - bit 15

Parameter Name: C00621 System connection list: Bool		Data type: UNSIGNED_16 Index: 23954 _d = 5D92 _h
C00621/21	0: Not connected	LS_DisFree_b : bDis1 Display of digital signal 1
C00621/22	0: Not connected	LS_DisFree_b : bDis2 Display of digital signal 2
C00621/23	0: Not connected	LS_DisFree_b : bDis3 Display of digital signal 3
C00621/24	0: Not connected	LS_DisFree_b : bDis4 Display of digital signal 4
C00621/25	0: Not connected	LS_DisFree_b : bDis5 Display of digital signal 5
C00621/26	0: Not connected	LS_DisFree_b : bDis6 Display of digital signal 6
C00621/27	0: Not connected	LS_DisFree_b : bDis7 Display of digital signal 7
C00621/28	0: Not connected	LS_DisFree_b : bDis8 Display of digital signal 8
C00621/29	0: Not connected	LP_CanOut2 : bOut1_B0 CAN2 output: Data word 1- bit 0
C00621/30	0: Not connected	LP_CanOut2 : bOut1_B1 CAN2 output: Data word 1- bit 1
C00621/31	0: Not connected	LP_CanOut2 : bOut1_B2 CAN2 output: Data word 1- bit 2
C00621/32	0: Not connected	LP_CanOut2 : bOut1_B3 CAN2 output: Data word 1- bit 3
C00621/33	0: Not connected	LP_CanOut2 : bOut1_B4 CAN2 output: Data word 1- bit 4
C00621/34	0: Not connected	LP_CanOut2 : bOut1_B5 CAN2 output: Data word 1- bit 5
C00621/35	0: Not connected	LP_CanOut2 : bOut1_B6 CAN2 output: Data word 1- bit 6
C00621/36	0: Not connected	LP_CanOut2 : bOut1_B7 CAN2 output: Data word 1- bit 7
C00621/37	0: Not connected	LP_CanOut2 : bOut1_B8 CAN2 output: Data word 1- bit 8
C00621/38	0: Not connected	LP_CanOut2 : bOut1_B9 CAN2 output: Data word 1- bit 9
C00621/39	0: Not connected	LP_CanOut2 : bOut1_B10 CAN2 output: Data word 1- bit 10
C00621/40	0: Not connected	LP_CanOut2 : bOut1_B11 CAN2 output: Data word 1- bit 11
C00621/41	0: Not connected	LP_CanOut2 : bOut1_B12 CAN2 output: Data word 1- bit 12
C00621/42	0: Not connected	LP_CanOut2 : bOut1_B13 CAN2 output: Data word 1- bit 13
C00621/43	0: Not connected	LP_CanOut2 : bOut1_B14 CAN2 output: Data word 1- bit 14
C00621/44	0: Not connected	LP_CanOut2 : bOut1_B15 CAN2 output: Data word 1- bit 15
C00621/45	0: Not connected	LP_CanOut3 : bOut1_B0 CAN3 output: Data word 1- bit 0

Parameter Name: C00621 System connection list: Bool		Data type: UNSIGNED_16 Index: 23954 _d = 5D92 _h
C00621/46	0: Not connected	LP_CanOut3 : bOut1_B1 CAN3 output: Data word 1- bit 1
C00621/47	0: Not connected	LP_CanOut3 : bOut1_B2 CAN3 output: Data word 1- bit 2
C00621/48	0: Not connected	LP_CanOut3 : bOut1_B3 CAN3 output: Data word 1- bit 3
C00621/49	0: Not connected	LP_CanOut3 : bOut1_B4 CAN3 output: Data word 1- bit 4
C00621/50	0: Not connected	LP_CanOut3 : bOut1_B5 CAN3 output: Data word 1- bit 5
C00621/51	0: Not connected	LP_CanOut3 : bOut1_B6 CAN3 output: Data word 1- bit 6
C00621/52	0: Not connected	LP_CanOut3 : bOut1_B7 CAN3 output: Data word 1- bit 7
C00621/53	0: Not connected	LP_CanOut3 : bOut1_B8 CAN3 output: Data word 1- bit 8
C00621/54	0: Not connected	LP_CanOut3 : bOut1_B9 CAN3 output: Data word 1- bit 9
C00621/55	0: Not connected	LP_CanOut3 : bOut1_B10 CAN3 output: Data word 1- bit 10
C00621/56	0: Not connected	LP_CanOut3 : bOut1_B11 CAN3 output: Data word 1- bit 11
C00621/57	0: Not connected	LP_CanOut3 : bOut1_B12 CAN3 output: Data word 1- bit 12
C00621/58	0: Not connected	LP_CanOut3 : bOut1_B13 CAN3 output: Data word 1- bit 13
C00621/59	0: Not connected	LP_CanOut3 : bOut1_B14 CAN3 output: Data word 1- bit 14
C00621/60	0: Not connected	LP_CanOut3 : bOut1_B15 CAN3 output: Data word 1- bit 15
C00621/61	0: Not connected	LP_MciOut : bState_B0 MCI output: Status word - bit 0
C00621/62	0: Not connected	LP_MciOut : bState_B1 MCI output: Status word - bit 1
C00621/63	0: Not connected	LP_MciOut : bState_B2 MCI output: Status word - bit 2
C00621/64	0: Not connected	LP_MciOut : bState_B3 MCI output: Status word - bit 3
C00621/65	0: Not connected	LP_MciOut : bState_B4 MCI output: Status word - bit 4
C00621/66	0: Not connected	LP_MciOut : bState_B5 MCI output: Status word - bit 5
C00621/67	0: Not connected	LP_MciOut : bState_B6 MCI output: Status word - bit 6
C00621/68	0: Not connected	LP_MciOut : bState_B7 MCI output: Status word - bit 7
C00621/69	0: Not connected	LP_MciOut : bState_B8 MCI output: Status word - bit 8
C00621/70	0: Not connected	LP_MciOut : bState_B9 MCI output: Status word - bit 9

Parameter Name: C00621 System connection list: Bool		Data type: UNSIGNED_16 Index: 23954 _d = 5D92 _h
C00621/71	0: Not connected	LP_MciOut : bState_B10 MCI output: Status word - bit 10
C00621/72	0: Not connected	LP_MciOut : bState_B11 MCI output: Status word - bit 11
C00621/73	0: Not connected	LP_MciOut : bState_B12 MCI output: Status word - bit 12
C00621/74	0: Not connected	LP_MciOut : bState_B13 MCI output: Status word - bit 13
C00621/75	0: Not connected	LP_MciOut : bState_B14 MCI output: Status word - bit 14
C00621/76	0: Not connected	LP_MciOut : bState_B15 MCI output: Status word - bit 15
C00621/77	0: Not connected	LP_MciOut : bOut2_B0 MCI output: Data word 2 - bit 0
C00621/78	0: Not connected	LP_MciOut : bOut2_B1 MCI output: Data word 2 - bit 1
C00621/79	0: Not connected	LP_MciOut : bOut2_B2 MCI output: Data word 2 - bit 2
C00621/80	0: Not connected	LP_MciOut : bOut2_B3 MCI output: Data word 2 - bit 3
C00621/81	0: Not connected	LP_MciOut : bOut2_B4 MCI output: Data word 2 - bit 4
C00621/82	0: Not connected	LP_MciOut : bOut2_B5 MCI output: Data word 2 - bit 5
C00621/83	0: Not connected	LP_MciOut : bOut2_B6 MCI output: Data word 2 - bit 6
C00621/84	0: Not connected	LP_MciOut : bOut2_B7 MCI output: Data word 2 - bit 7
C00621/85	0: Not connected	LP_MciOut : bOut2_B8 MCI output: Data word 2 - bit 8
C00621/86	0: Not connected	LP_MciOut : bOut2_B9 MCI output: Data word 2 - bit 9
C00621/87	0: Not connected	LP_MciOut : bOut2_B10 MCI output: Data word 2 - bit 10
C00621/88	0: Not connected	LP_MciOut : bOut2_B11 MCI output: Data word 2 - bit 11
C00621/89	0: Not connected	LP_MciOut : bOut2_B12 MCI output: Data word 2 - bit 12
C00621/90	0: Not connected	LP_MciOut : bOut2_B13 MCI output: Data word 2 - bit 13
C00621/91	0: Not connected	LP_MciOut : bOut2_B14 MCI output: Data word 2 - bit 14
C00621/92	0: Not connected	LP_MciOut : bOut2_B15 MCI output: Data word 2 - bit 15
C00621/93	0: Not connected	LS_SetError_1 : bSetError1 Input for tripping "US01: User error 1"
C00621/94	0: Not connected	LS_SetError_1 : bSetError2 Input for tripping "US02: User error 2"
C00621/95	0: Not connected	LS_SetError_1 : bSetError3 Input for tripping "US03: User error 3"

Parameter Name: C00621 System connection list: Bool		Data type: UNSIGNED_16 Index: 23954 _d = 5D92 _h
C00621/96	0: Not connected	LS_SetError_1 : bSetError4 Input for tripping "US04: User error 4"
C00621/97	0: Not connected	LS_DigitalInput : bCountIn6_Reset Digital input 6: Reset counter
C00621/98	0: Not connected	LS_DigitalInput : bCountIn6_LoadStartValue Digital input 6: Load counter starting value
C00621/99	0: Not connected	LS_DigitalOutput : bOut2 Digital output 2: Input signal
C00621/100	0: Not connected	LS_DigitalOutput : bOut3 Digital output 3: Input signal
C00621/101	0: Not connected	LS_DigitalOutput : bOut HighCurrent Digital output (HC) for brake control: Input signal
C00621/102	0: Not connected	LS_DisFree_b : bDis9 Display of digital signal 9
C00621/103	0: Not connected	LS_DisFree_b : bDis10 Display of digital signal 10
C00621/104	0: Not connected	LS_DisFree_b : bDis11 Display of digital signal 11
C00621/105	0: Not connected	LS_DisFree_b : bDis12 Display of digital signal 12
C00621/106	0: Not connected	LS_DisFree_b : bDis13 Display of digital signal 13
C00621/107	0: Not connected	LS_DisFree_b : bDis14 Display of digital signal 14
C00621/108	0: Not connected	LS_DisFree_b : bDis15 Display of digital signal 15
C00621/109	0: Not connected	LS_DisFree_b : bDis16 Display of digital signal 16
C00621/111	0: Not connected	LS_ParReadWrite_1 : bExecute Read/write request 1: Trigger
C00621/112	0: Not connected	LS_ParReadWrite_1 : bReadWrite Read/write request 1: Selection of reading/writing
C00621/113	0: Not connected	LS_ParReadWrite_2 : bExecute Read/write request 2: Trigger
C00621/114	0: Not connected	LS_ParReadWrite_2 : bReadWrite Read/write request 2: Selection of reading/writing
C00621/115	0: Not connected	LS_ParReadWrite_3 : bExecute Read/write request 3: Trigger
C00621/116	0: Not connected	LS_ParReadWrite_3 : bReadWrite Read/write request 3: Selection of reading/writing
C00621/117	0: Not connected	LS_ParReadWrite_4 : bExecute Read/write request 4: Trigger
C00621/118	0: Not connected	LS_ParReadWrite_4 : bReadWrite Read/write request 4: Selection of reading/writing
C00621/119	0: Not connected	LS_ParReadWrite_5 : bExecute Read/write request 5: Trigger
C00621/120	0: Not connected	LS_ParReadWrite_5 : bReadWrite Read/write request 5: Selection of reading/writing
C00621/121	0: Not connected	LS_ParReadWrite_6 : bExecute Read/write request 6: Trigger

Parameter Name: C00621 System connection list: Bool		Data type: UNSIGNED_16 Index: 23954 _d = 5D92 _h
C00621/122	0: Not connected	LS_ParReadWrite_6 : bReadWrite Read/write request 6: Selection of reading/writing
C00621/123	0: Not connected	LS_WriteParamList : bExecute Writing the parameter list: Activate
C00621/124	0: Not connected	LS_WriteParamList : bSelectWriteValue_1 Writing to parameter list: Selection of value set - 1
C00621/125	0: Not connected	LS_WriteParamList : bSelectWriteValue_2 Writing to parameter list: Selection of value set - 2
C00621/126	0: Not connected	LS_CANManagement : bResetNode Reset CAN node
C00621/127	0: Not connected	LS_CANManagement : bReInitCAN Reinitialise CAN interface
C00621/128	0: Not connected	LS_DigitalInput : bPosIn12_Load Frequency input DI1/DI2: Load angle integrator with starting value and reset status signal
C00621/147	0: Not connected	LS_TouchProbe : bDisableTPDigIn3 TP input DI3: Disable TP function dynamically
C00621/148	0: Not connected	LS_TouchProbe : bDisableTPDigIn4 TP input DI4: Disable TP function dynamically
C00621/149	0: Not connected	LS_TouchProbe : bDisableTPDigIn5 TP input DI5: Disable TP function dynamically
C00621/150	0: Not connected	LS_TouchProbe : bDisableTPDigIn6 TP input DI6: Disable TP function dynamically
C00621/151	0: Not connected	LS_TouchProbe : bDisableTPDigIn7 TP input DI7: Disable TP function dynamically
C00621/152	0: Not connected	LS_TouchProbe : bDisableTPDigIn3_Rising TP input DI3: Disable recognition of rising edges dynamically
C00621/153	0: Not connected	LS_TouchProbe : bDisableTPDigIn3_Falling TP input DI3: Disable recognition of falling edges dynamically
C00621/154	0: Not connected	LS_TouchProbe : bDisableTPDigIn4_Rising TP input DI4: Disable recognition of rising edges dynamically
C00621/155	0: Not connected	LS_TouchProbe : bDisableTPDigIn4_Falling TP input DI4: Disable recognition of falling edges dynamically
C00621/156	0: Not connected	LS_TouchProbe : bDisableTPDigIn5_Rising TP input DI5: Disable recognition of rising edges dynamically
C00621/157	0: Not connected	LS_TouchProbe : bDisableTPDigIn5_Falling TP input DI5: Disable recognition of falling edges dynamically
C00621/158	0: Not connected	LS_TouchProbe : bDisableTPDigIn3Window TP input DI3: Enable acceptance window
C00621/159	0: Not connected	LS_TouchProbe : bDisableTPDigIn4Window TP input DI4: Enable acceptance window
C00621/160	0: Not connected	LS_TouchProbe : bDisableTPDigIn5Window TP input DI5: Enable acceptance window
C00621/161	0: Not connected	LS_AxisBusIO : bSetFail Set IO axis bus into the "error" status / IO data exchange
C00621/162	0: Not connected	LS_AxisBusIO : bResetFail IO axis bus: Reset "error" status

Parameter Name: C00621 System connection list: Bool		Data type: UNSIGNED_16 Index: 23954 _d = 5D92 _h
C00621/164	0: Not connected	LS_MultiEncoder : bSetRef
C00621/165	0: Not connected	LS_RetainData : bSetRetain_1 Retain data: Save input values (selection 1) in retain memory
C00621/166	0: Not connected	LS_RetainData : bSetRetain_2 Retain data: Save input values (selection 2) in retain memory
C00621/167	0: Not connected	LS_RetainData : bSetRetain_3 Retain data: Save input values (selection 3) in retain memory
C00621/168	0: Not connected	LS_RetainData : bLoadParams Retain data: Set selected outputs & retain values to parameter values
C00621/169	0: Not connected	LS_RetainData : bIn1 Retain data: Binary input value 1
C00621/170	0: Not connected	LS_RetainData : bIn2 Retain data: Binary input value 2
C00621/171	0: Not connected	LS_RetainData : bIn3 Retain data: Binary input value 3
C00621/172	0: Not connected	LS_RetainData : bIn4 Retain data: Binary input value 4
C00621/173	0: Not connected	LS_AxisBusAux : bReadWrite Axis bus: Selection of reading/writing
C00621/174	0: Not connected	LS_AxisBusAux : bExecute Axis bus: Data acceptance
C00621/175	0: Not connected	LS_AxisBusAux : bStop Axis bus: Stop data transfer
C00621/176	0: Not connected	LS_DigitalOutput : bUserLED Switch on USER-LED on the controller front panel
C00621/177	0: Not connected	LS_TouchProbe : bDisableTPEncoderWindow
C00621/178	0: Not connected	LS_TouchProbe : bDisableTPResolverWindow
C00621/179	0: Not connected	LS_TouchProbe : bDisableTPEncoder
C00621/180	0: Not connected	LS_TouchProbe : bDisableTPResolver
C00621/181	0: Not connected	LF_DFOut: bSynRdy
C00621/184	0: Not connected	LP_CanOut4 : bOut1_B0 CAN4 output: Data word 1- bit 0
C00621/185	0: Not connected	LP_CanOut4 : bOut1_B1 CAN4 output: Data word 1- bit 1
C00621/186	0: Not connected	LP_CanOut4 : bOut1_B2 CAN4 output: Data word 1- bit 2
C00621/187	0: Not connected	LP_CanOut4 : bOut1_B3 CAN4 output: Data word 1- bit 3
C00621/188	0: Not connected	LP_CanOut4 : bOut1_B4 CAN4 output: Data word 1- bit 4
C00621/189	0: Not connected	LP_CanOut4 : bOut1_B5 CAN4 output: Data word 1- bit 5
C00621/190	0: Not connected	LP_CanOut4 : bOut1_B6 CAN4 output: Data word 1- bit 6
C00621/191	0: Not connected	LP_CanOut4 : bOut1_B7 CAN4 output: Data word 1- bit 7

Parameter Name: C00621 System connection list: Bool		Data type: UNSIGNED_16 Index: 23954 _d = 5D92 _h
C00621/192	0: Not connected	LP_CanOut4 : bOut1_B8 CAN4 output: Data word 1- bit 8
C00621/193	0: Not connected	LP_CanOut4 : bOut1_B9 CAN4 output: Data word 1- bit 9
C00621/194	0: Not connected	LP_CanOut4 : bOut1_B10 CAN4 output: Data word 1- bit 10
C00621/195	0: Not connected	LP_CanOut4 : bOut1_B11 CAN4 output: Data word 1- bit 11
C00621/196	0: Not connected	LP_CanOut4 : bOut1_B12 CAN4 output: Data word 1- bit 12
C00621/197	0: Not connected	LP_CanOut4 : bOut1_B13 CAN4 output: Data word 1- bit 13
C00621/198	0: Not connected	LP_CanOut4 : bOut1_B14 CAN4 output: Data word 1- bit 14
C00621/199	0: Not connected	LP_CanOut4 : bOut1_B15 CAN4 output: Data word 1- bit 15
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00622

Parameter Name: C00622 System connection list: Angle		Data type: UNSIGNED_16 Index: 23953 _d = 5D91 _h
Connection parameters: 32-bit inputs <ul style="list-style-type: none"> • Selection of the 32-bit output signals for connection with the 32-bit input signals. • The selection list contains all 32-bit output signals which can be assigned to the 32-bit inputs mapped by the subcodes. • Non-listed subcodes are "reserved". 		
Selection list		
See selection list - angle signals		
Subcodes	Lenze setting	Info
C00622/1	0: Not connected	LS_DisFree_p : dnDis1_p Display of 32-bit signal 1
C00622/2	0: Not connected	LS_DisFree_p : dnDis2_p Display of 32-bit signal 2
C00622/3	0: Not connected	LS_DisFree_p : dnDis3_p Display of 32-bit signal 3
C00622/4	0: Not connected	LS_DisFree_p : dnDis4_p Display of 32-bit signal 4
C00622/5	0: Not connected	LS_DisFree_p : dnDis5_p Display of 32-bit signal 5
C00622/6	0: Not connected	LS_DisFree_p : dnDis6_p Display of 32-bit signal 6
C00622/7	0: Not connected	LS_DisFree_p : dnDis7_p Display of 32-bit signal 7
C00622/8	0: Not connected	LS_DisFree_p : dnDis8_p Display of 32-bit signal 8
C00622/9	0: Not connected	LP_CanOut1 : dnOut34_p CAN1 output: Data words 3 + 4
C00622/10	0: Not connected	LP_CanOut2 : dnOut34_p CAN2 output: Data words 3 + 4

Parameter Name: C00622 System connection list: Angle		Data type: UNSIGNED_16 Index: 23953 _d = 5D91 _h
C00622/11	0: Not connected	LP_CanOut3 : dnOut34_p CAN3 output: Data words 3 + 4
C00622/12	0: Not connected	LP_MciOut : dnOut34_p MCI output: Data words 3 + 4
C00622/13	0: Not connected	LS_DigitalInput : dnPosIn12_Set_p Frequency input DI1/DI2: Starting value for angle integrator
C00622/16	0: Not connected	LS_RetainData : dnIn1 Retain data: 32-bit input value 1
C00622/17	0: Not connected	LS_RetainData : dnIn2 Retain data: 32-bit input value 2
C00622/18	0: Not connected	LS_RetainData : dnIn3 Retain data: 32-bit input value 3
C00622/19	0: Not connected	LS_RetainData : dnIn4 Retain data: 32-bit input value 4
C00622/20	0: Not connected	LS_AxisBusOut : dnLine12 Axis bus output: Line data (word 1 + 2)
C00622/21	0: Not connected	LS_AxisBusOut : dnCas12 Axis bus output: Cascaded data (word 1 + 2)
C00622/22	0: Not connected	LS_AxisBusOut : dnCas34 Axis bus output: Cascaded data (word 3 + 4)
C00622/23	0: Not connected	LS_AxisBusAux : dnAuxOut12 Axis bus output: @sel data (word 1 + 2)
C00622/24	0: Not connected	LS_AxisBusAux : dnAuxOut34 Axis bus output: @sel data (word 3 + 4)
C00622/25	0: Not connected	LP_CanOut4 : dnOut34_p CAN4 output: Data words 3 + 4
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00630

Parameter Name: C00630 L_Limit 1-2: Min/Max		Data type: INTEGER_16 Index: 23945 _d = 5D89 _h
Setting the limits		
Setting range (min. value unit max. value)		
-199.99	%	199.99
Subcodes	Lenze setting	Info
C00630/1	-199.99 %	L_Limit 1 : Min.Limit
C00630/2	199.99 %	L_Limit 1 : Max.Limit
C00630/3	-199.99 %	L_Limit 2 : Min.Limit
C00630/4	199.99 %	L_Limit 2 : Max.Limit
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100		

C00631

Parameter Name: C00631 L_LimitPhi 1-3: Min/Max			Data type: INTEGER_32 Index: 23944 _d = 5D88 _h
Setting the limits			
Setting range (min. value unit max. value)			
-2147483647	Incr.	2147483647	
Subcodes	Lenze setting	Info	
C00631/1	-2147483647 incr.	L_LimitPhi 1 : Min.Limit	
C00631/2	2147483647 incr.	L_LimitPhi 1 : Max.Limit	
C00631/3	-2147483647 incr.	L_LimitPhi 2 : Min.Limit	
C00631/4	2147483647 incr.	L_LimitPhi 2 : Max.Limit	
C00631/5	-2147483647 incr.	L_LimitPhi 3 : Min.Limit	
C00631/6	2147483647 incr.	L_LimitPhi 3 : Max.Limit	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00632

Parameter Name: C00632 L_NSet_1: Max.SkipFrq.			Data type: INTEGER_16 Index: 23943 _d = 5D87 _h
Maximum limit values for the speed blocking zones			
• Selection of the maximum limit values for the blocking zones in which the speed must not be constant.			
Setting range (min. value unit max. value)			
0.00	%	199.99	
Subcodes	Lenze setting	Info	
C00632/1	0.00 %	L_NSet_1 : Blocking speed1 max	
C00632/2	0.00 %	L_NSet_1 : Blocking speed2 max	
C00632/3	0.00 %	L_NSet_1 : Blocking speed3 max	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00633

Parameter Name: C00633 L_NSet_1: Min.SkipFrq.			Data type: INTEGER_16 Index: 23942 _d = 5D86 _h
Minimum limit values for the speed blocking zones • Selection of the minimum limit values for the blocking zones in which the speed must not be constant.			
Setting range (min. value unit max. value)			
0.00	%	199.99	
Subcodes	Lenze setting	Info	
C00633/1	0.00 %	L_NSet_1 : Blocking speed1 min	
C00633/2	0.00 %	L_NSet_1 : Blocking speed2 min	
C00633/3	0.00 %	L_NSet_1 : Blocking speed3 min	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00634

Parameter Name: C00634 L_NSet_1: wState			Data type: UNSIGNED_16 Index: 23941 _d = 5D85 _h
The L_NSet_1 FB: Bit coded status display			
Display area (min. hex value max. hex value)			
0x0000		0xFFFF	
Value is bit-coded:			Info
Bit 0	No blocking zone active	1 ≡ No blocking zone set for constant speeds	
Bit 1	Blocking zone 1 active	1 ≡ Suppression of constant speed characteristics within the limits of blocking zone 1	
Bit 2	Blocking zone 2 active	1 ≡ Suppression of constant speed characteristics within the limits of blocking zone 2	
Bit 3	Blocking zone 3 active	1 ≡ Suppression of constant speed characteristics within the limits of blocking zone 3	
Bit 4	Jog in blocking zone	1 ≡ A ramp is used to keep the speed setpoint within a speed blocking zone	
Bit 5	MaxLimit active	1 ≡ Speed setpoint is at the maximum speed limit	
Bit 6	MinLimit active	1 ≡ Speed setpoint is at the minimum speed limit	
Bit 7	Reserved		
Bit 8	Reserved		
Bit 9	Reserved		
Bit 10	Reserved		
Bit 11	Reserved		
Bit 12	Reserved		
Bit 13	Reserved		
Bit 14	Reserved		
Bit 15	Reserved		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT			

C00635

Parameter Name: C00635 L_NSet_1: nMaxLimit			Data type: INTEGER_16 Index: 23940 _d = 5D84 _h
The L_NSet_1 FB: Maximum speed setpoint for speed setpoint limitation			
Setting range (min. value unit max. value)			Lenze setting
-199.99	%	199.99	199.99 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00636

Parameter Name: C00636 L_NSet_1: nMinLimit			Data type: INTEGER_16 Index: 23939 _d = 5D83 _h
The L_NSet_1 FB: Minimum speed setpoint for speed setpoint limitation			
Setting range (min. value unit max. value)			Lenze setting
-199.99	%	199.99	-199.99 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00637

Parameter Name: C00637 L_NSet_1: Output blocking zones			Data type: INTEGER_16 Index: 23938 _d = 5D82 _h		
The L_NSet_1 FB: Speed setpoint is displayed after being processed by blocking zone function					
Display range (min. value unit max. value)					
-199.99	%	199.99			
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00638

Parameter Name: C00638 L_NSet_1: Output ramp rounding			Data type: INTEGER_16 Index: 23937 _d = 5D81 _h		
The L_NSet_1 FB: Speed setpoint is displayed after being processed by PT1 filter function					
Display range (min. value unit max. value)					
-199.99	%	199.99			
<input checked="" type="checkbox"/> Read access			<input type="checkbox"/> Write access		
<input type="checkbox"/> CINH			<input type="checkbox"/> PLC STOP		
<input checked="" type="checkbox"/> No transfer			<input type="checkbox"/> COM		
<input type="checkbox"/> MOT			Scaling factor: 100		

C00639

Parameter Name: C00639 L_NSet_1: Output additional value			Data type: INTEGER_16 Index: 23936 _d = 5D80 _h		
The L_NSet_1 FB: Additional speed setpoint is displayed after being processed by the ramp generator					
Display range (min. value unit max. value)					
-199.99	%	199.99			
<input checked="" type="checkbox"/> Read access			<input type="checkbox"/> Write access		
<input type="checkbox"/> CINH			<input type="checkbox"/> PLC STOP		
<input type="checkbox"/> No transfer			<input type="checkbox"/> COM		
<input type="checkbox"/> MOT			Scaling factor: 100		

C00640

Parameter Name: C00640 L_NSet_1: nNOut_a			Data type: INTEGER_16 Index: 23935 _d = 5D7F _h		
The <u>L_NSet_1</u> FB: Display of the generated main speed setpoint at the output <i>nNOut_a</i>					
Display range (min. value unit max. value)					
-199.99	%	199.99			
<input checked="" type="checkbox"/> Read access			<input type="checkbox"/> Write access		
<input type="checkbox"/> CINH			<input type="checkbox"/> PLC STOP		
<input checked="" type="checkbox"/> No transfer			<input type="checkbox"/> COM		
<input type="checkbox"/> MOT			Scaling factor: 100		

C00643

Parameter Name: C00643 Resp. to PLI monitoring		Data type: UNSIGNED_8 Index: 23932 _d = 5D7C _h	
<div>▶ Pole position identification</div>			
Selection list			
0	No Reaction		
1	Fault		
3	TroubleQuickStop		
4	WarningLocked		
5	Warning		
6	Information		
Subcodes	Lenze setting	Info	
C00643/1	1: Fault	Response to PLI monitoring	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C00644

Parameter Name: C00644 PLI traversing direction		Data type: UNSIGNED_8 Index: 23931 _d = 5D7B _h
▶ Pole position identification		
Selection list		
0	right rotating field	
1	left rotating field	
Subcodes	Lenze setting	Info
C00644/1	0: right rotating field	PLI 360° traversing direction
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00645

Parameter Name: C00645 PLI max. permissible deflection		Data type: INTEGER_16 Index: 23930 _d = 5D7A _h
▶ Pole position identification		
Setting range (min. value unit max. value)		
-6.0	°	90.0
Subcodes	Lenze setting	Info
C00645/1	0.0 °	Reserved
C00645/2	0.0 °	PLI 360° max. error tolerance
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10		

C00646

Parameter Name: C00646 PLI current amplitude		Data type: UNSIGNED_16 Index: 23929 _d = 5D79 _h
▶ Pole position identification		
Setting range (min. value unit max. value)		
1	%	1000
Subcodes	Lenze setting	Info
C00646/1	1 %	Reserved
C00646/2	100 %	PLI 360° current amplitude
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00647

Parameter Name: C00647 PLI ramp time		Data type: UNSIGNED_16 Index: 23928 _d = 5D78 _h
▶ Pole position identification		
Setting range (min. value unit max. value)		
5		1000
Subcodes	Lenze setting	Info
C00647/1	5	Reserved
C00647/2	100	PLI 360° ramp time
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00650

Parameter Name: C00650 L_Arithmetik 3-5: Function		Data type: UNSIGNED_8 Index: 23925 _d = 5D75 _h
Selection of the internal arithmetics		
Selection list		
0	nOut_a = nIn1_a	
1	nOut_a = nIn1_a + nIn2_a	
2	nOut_a = nIn1_a - nIn2_a	
3	nOut_a = (nIn1_a * nIn2_a) / 100%	
4	nOut_a = (nIn1_a * 1%) / nIn2_a	
5	nOut_a = (nIn1_a * 100%) / (100% - nIn2_a)	
Subcodes	Lenze setting	Info
C00650/1	0: nOut_a = nIn1_a	L_Arithmetik 3 : Function
C00650/2	0: nOut_a = nIn1_a	L_Arithmetik 4 : Function
C00650/3	0: nOut_a = nIn1_a	L_Arithmetik 5 : Function
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00653

Parameter Name: C00653 Sensibility - Setpoint feedforward control		Data type: UNSIGNED_8 Index: 23922 _d = 5D72 _h
From version 12.00.00 Selection of the sensitivity of the differential setpoint feedforward control <ul style="list-style-type: none"> Depending on the selection, the number of indicated higher-order bits is evaluated. 		
Note: The most significant bit determines the sign of the value, the remaining bits determine the numerical value.		
Selection list		Info
0	Inactive	
1	15 bits	Bit 0 ... bit 14 are evaluated
2	14 bits	Bit 0 ... bit 13 are evaluated
3	13 bits	Bit 0 ... bit 12 are evaluated
4	12 bits	Bit 0 ... bit 11 are evaluated
5	11 Bit	Bit 0 ... bit 10 are evaluated
6	10 Bit	Bit 0 ... bit 9 are evaluated
7	9 Bit	Bit 0 ... bit 8 are evaluated
Subcodes	Lenze setting	Info
C00653/1	0: Inactive	Sensibility - Setpoint feedforward control
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00654

Parameter Name: C00654 Source of diff. setpoint feedforward control		Data type: UNSIGNED_8 Index: 23921 _d = 5D71 _h
From version 12.00.00 Selection of the process signal for the setpoint feedforward control		
Selection list		Info
0	nSpeedSetValue_a	
1	nSpeedSetValueInertia_a	The new process signal <i>nSpeedSetValueInertia_a</i> at SB LS_MotorInterface can be used to define any input value (e.g. position or process controller setpoint) for torque feedforward control.
Subcodes	Lenze setting	Info
C00654/1	0: nSpeedSetValue_a	Source of diff. setpoint feedforward control
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00658

Parameter Name: C00658 PRBS amplitude	Data type: INTEGER_16 Index: 23917 _d = 5D6D _h
This code is for device-internal use only and must not be written to by the user!	

C00659

Parameter Name: C00659 PRBS duration	Data type: UNSIGNED_16 Index: 23916 _d = 5D6C _h
This code is for device-internal use only and must not be written to by the user!	

C00660

Parameter Name: C00660 L_FixSet_a_1: Analog values			Data type: INTEGER_16 Index: 23915 _d = 5D6B _h
FB <u>L_FixSet_a_1</u> : Setting of the fixed values			
Setting range (min. value unit max. value)			
-199.99	%	199.99	
Subcodes	Lenze setting	Info	
C00660/1	0.00 %	Fixed value 0 ... 15	
C00660/...			
C00660/16			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00661

Parameter Name: C00661 L_FixSet_w_1: Fixed values			Data type: UNSIGNED_16 Index: 23914 _d = 5D6A _h
FB L_FixSet_w_1 : Setting of the fixed values			
Setting range (min. value unit max. value)			
0			
Subcodes	Lenze setting	Info	
C00661/1	0	Fixed value 0 ... 15	
C00661/...			
C00661/16			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00662

Parameter Name: C00662 L_FixSet_w_2: Fixed values			Data type: UNSIGNED_16 Index: 23913 _d = 5D69 _h
FB <u>L_FixSet_w_2</u> : Setting of the fixed values			
Setting range (min. value unit max. value)			
0			
Subcodes	Lenze setting	Info	
C00662/1	0	Fixed value 0 ... 15	
C00662/...			
C00662/16			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00670

Parameter Name: C00670 L_OffsetGainP_1: Gain			Data type: INTEGER_32 Index: 23905 _d = 5D61 _h
The L_OffsetGainP_1 FB: Gain as multiplier of the input signal + offset			
Setting range (min. value unit max. value)		Lenze setting	
-100.0000		100.0000	1.0000
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000			

C00671

Parameter Name: C00671 L_OffsetGainP_2: Gain			Data type: INTEGER_32 Index: 23904 _d = 5D60 _h
The L_OffsetGainP_2 FB: Gain as multiplier of the input signal + offset			
Setting range (min. value unit max. value)		Lenze setting	
-100.0000		100.0000	1.0000
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000			

C00672

Parameter Name: C00672 L_OffsetGainP_3: Gain			Data type: INTEGER_32 Index: 23903 _d = 5D5F _h
The L_OffsetGainP_3 FB: Gain as multiplier of the input signal + offset			
Setting range (min. value unit max. value)			Lenze setting
-100.0000		100.0000	1.0000
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000			

C00673

Parameter Name: C00673 L_OffsetGainPhiP 1-2: Offset			Data type: INTEGER_32 Index: 23902 _d = 5D5E _h
Angular offset (is added to the angular input signal)			
Setting range (min. value unit max. value)			
-2147483647	Incr.	2147483647	
Subcodes	Lenze setting	Info	
C00673/1	0 incr.	L_OffsetGainPhiP_1 : Offset	
C00673/2	0 incr.	L_OffsetGainPhiP_2 : Offset	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00674

Parameter Name: C00674 L_OffsetGainPhiP 1-2: Gain			Data type: INTEGER_32 Index: 23901 _d = 5D5D _h
Angular gain as multiplier of the input signal + angular offset			
Setting range (min. value unit max. value)			
-2147483647		2147483647	
Subcodes	Lenze setting	Info	
C00674/1	65536	L_OffsetGainPhiP_1 : Gain	
C00674/2	65536	L_OffsetGainPhiP_2 : Gain	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00677

Parameter Name: C00677 L_GainOffsetP 1-3: Parameter			Data type: INTEGER_16 Index: 23898 _d = 5D5A _h
Gain and offset			
Setting range (min. value unit max. value)			
-199.99	%	199.99	
Subcodes	Lenze setting		Info
C00677/1	100.00 %		L_GainOffsetP_1 : Gain
C00677/2	0.00 %		L_GainOffsetP_1 : Offset
C00677/3	100.00 %		L_GainOffsetP_2 : Gain
C00677/4	0.00 %		L_GainOffsetP_2 : Offset
C00677/5	100.00 %		L_GainOffsetP_3 : Gain
C00677/6	0.00 %		L_GainOffsetP_3 : Offset
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00678

Parameter Name: C00678 L_GainOffsetPhiP 1-2: Parameter			Data type: INTEGER_32 Index: 23897 _d = 5D59 _h
Gain and offset			
Setting range (min. value unit max. value)			
-2147483647		2147483647	
Subcodes	Lenze setting	Info	
C00678/1	65536	L_GainOffsetPhiP 1 : Gain	
C00678/2	0	L_GainOffsetPhiP 1 : Offset	
C00678/3	65536	L_GainOffsetPhiP 2 : Gain	
C00678/4	0	L_GainOffsetPhiP 2 : Offset	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00679

Parameter Name: C00679 L_MulDiv_2: Parameter			Data type: INTEGER_16 Index: 23896 _d = 5D58 _h
The L_MulDiv_2 FB: Numerator and denominator			
Setting range (min. value unit max. value)			
-32767		32767	
Subcodes	Lenze setting	Info	
C00679/1	0	L_MulDiv_2 : Numerator	
C00679/2	10000	L_MulDiv_2 : Denominator	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00680

Parameter | Name: C00680 | L_Compare_1: Fct. Data type: UNSIGNED_8 Index: 23895_d = 5D57_h

The [L_Compare_1](#) FB: Comparison operation

- If the statement of the selected comparison operation is true, the binary *bOut* output will be set to TRUE.

Selection list (Lenze setting printed in bold)	
1	In1 = In2
2	In1 > In2
3	In1 < In2
4	In1 = In2
5	In1 > In2
6	 In1 < In2

☒ Read access☒ Write access☐ CINH☐ PLC STOP☐ No transfer☐ COM☐ MOT

Scaling factor: 1

C00681

Parameter Name: C00681 L_Compare_1: Hysteresis			Data type: INTEGER_16 Index: 23894 _d = 5D56 _h
The L_Compare_1 FB: Hysteresis for the comparison function selected in C00680			
Setting range (min. value unit max. value)			Lenze setting
0.00	%	100.00	0.50 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00682

Parameter Name: C00682 L_Compare_1: Window			Data type: INTEGER_16 Index: 23893 _d = 5D55 _h
The L_Compare_1 FB: Window for the comparison function selected in C00680			
Setting range (min. value unit max. value)			Lenze setting
0.00	%	100.00	2.00 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00685

Parameter Name: C00685 L_Compare_2: Fct.		Data type: UNSIGNED_8 Index: 23890 _d = 5D52 _h
The L_Compare_2 FB: Comparison operation		
• If the statement of the selected comparison operation is true, the binary <i>bOut</i> output will be set to TRUE.		
Selection list (Lenze setting printed in bold)		
1	In1 = In2	
2	In1 > In2	
3	In1 < In2	
4	 In1 = In2 	
5	In1 > In2	
6	In1 < In2	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00686

Parameter Name: C00686 L_Compare_2: Hysteresis			Data type: INTEGER_16 Index: 23889 _d = 5D51 _h
The L_Compare_2 FB: Hysteresis for the comparison function selected in C00685			
Setting range (min. value unit max. value)			Lenze setting
0.00	%	100.00	0.50 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00687

Parameter Name: C00687 L_Compare_2: Window			Data type: INTEGER_16 Index: 23888 _d = 5D50 _h
The L_Compare_2 FB: Window for the comparison function selected in C00685			
Setting range (min. value unit max. value)			Lenze setting
0.00	%	100.00	2.00 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00690

Parameter Name:		Data type: UNSIGNED_8	
C00690 L_Compare_3: Function		Index: 23885 _d = 5D4D _h	
The L_Compare_3 FB: Comparison operation			
• If the statement of the selected comparison operation is true, the binary <i>bOut</i> output will be set to TRUE.			
Selection list (Lenze setting printed in bold)			
1	In1 = In2		
2	In1 > In2		
3	In1 < In2		
4	In1 = In2		
5	In1 > In2		
6	In1 < In2		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00691

Parameter Name: C00691 L_Compare_3: Hysteresis			Data type: INTEGER_16 Index: 23884 _d = 5D4C _h
FB L_Compare_3 : Hysteresis for the comparison operation selected in C00690			
Setting range (min. value unit max. value)		Lenze setting	
0.00	%	100.00	0.00 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00692

Parameter Name: C00692 L_Compare_3: Window			Data type: INTEGER_16 Index: 23883 _d = 5D4B _h
FB L_Compare_3 : window for the comparison operation selected in C00690			
Setting range (min. value unit max. value)		Lenze setting	
0.00	%	100.00	0.00 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00693

Parameter Name: C00693 L_Compare 4-5: Function		Data type: UNSIGNED_8 Index: 23882 _d = 5D4A _h
Comparison operation		
• If the statement of the selected comparison operation is true, the binary <i>bOut</i> output will be set to TRUE.		
Selection list		
1	In1 = In2	
2	In1 > In2	
3	In1 < In2	
4	In1 = In2	
5	In1 > In2	
6	In1 < In2	
Subcodes	Lenze setting	Info
C00693/1	1: In1 = In2	L_Compare_4 : Function
C00693/2	1: In1 = In2	L_Compare_5 : Function
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00694

Parameter Name: C00694 L_Compare 4-5: Hysteresis			Data type: INTEGER_16 Index: 23881 _d = 5D49 _h
Hysteresis for the comparison operation selected in C00693			
Setting range (min. value unit max. value)			
0.00	%	100.00	
Subcodes	Lenze setting	Info	
C00694/1	0.00 %	L_Compare 4 : Hysteresis	
C00694/2	0.00 %	L_Compare 5 : Hysteresis	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00695

Parameter Name: C00695 L_Compare 4-5: Window			Data type: INTEGER_16 Index: 23880 _d = 5D48 _h
Window for the comparison operation selected in C00693			
Setting range (min. value unit max. value)			
0.00	%	100.00	
Subcodes	Lenze setting	Info	
C00695/1	0.00 %	L_Compare 4 : Window	
C00695/2	0.00 %	L_Compare 5 : Window	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00696

Parameter Name: C00696 L_OffsetGainP_1: Offset			Data type: INTEGER_16 Index: 23879 _d = 5D47 _h
The L_OffsetGainP_1 FB: Offset (additive to the input signal)			
Setting range (min. value unit max. value)			Lenze setting
-199.99	%	199.99	0.00 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00697

Parameter Name: C00697 L_OffsetGainP_2: Offset			Data type: INTEGER_16 Index: 23878 _d = 5D46 _h
The L_OffsetGainP_2 FB: Offset (additive to the input signal)			
Setting range (min. value unit max. value)			Lenze setting
-199.99	%	199.99	0.00 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00698

Parameter Name: C00698 L_OffsetGainP_3: Offset			Data type: INTEGER_16 Index: 23877 _d = 5D45 _h
The L_OffsetGainP_3 FB: Offset (additive to the input signal)			
Setting range (min. value unit max. value)			Lenze setting
-199.99	%	199.99	0.00 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00699

Parameter Name: C00699 L_MulDiv_1: Parameter		Data type: INTEGER_16 Index: 23876 _d = 5D44 _h
The L_MulDiv_1 FB: Numerator and denominator		
Setting range (min. value unit max. value)		
-32767		32767
Subcodes	Lenze setting	Info
C00699/1	0	L_MulDiv_1 : Numerator
C00699/2	10000	L_MulDiv_1 : Denominator
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00700

Parameter Name: C00700 LA_NCtrl: Analog connection list		Data type: UNSIGNED_16 Index: 23875 _d = 5D43 _h
Connection parameters for "Actuating drive speed" application: 16-bit inputs <ul style="list-style-type: none"> • Selection of the 16 bit output signals to be connected to the 16 bit input signals • The selection list contains all 16 bit output signals which can be assigned to the 16 bit inputs displayed by the subcodes. 		
Selection list		
See selection list - analog signals		
Subcodes	Lenze setting	Info
C00700/1	20005: LS_ParFix: wDriveCtrl	LA_NCtrl : wCANDriveControl Input for control word from CAN to device control
C00700/2	20005: LS_ParFix: wDriveCtrl	LA_NCtrl : wMCIDriveControl Input for control word from communication interface to device control
C00700/3	20012: LS_ParFree_a: nC472_3_a	LA_NCtrl : nTorqueMotLim_a Input for maximum torque in motor mode
C00700/4	20013: LS_ParFree_a: nC472_4_a	LA_NCtrl : nTorqueGenLim_a Input for maximum torque in generator mode
C00700/5	0: Not connected	LA_NCtrl : nPIDVpAdapt_a Input for adapting the PID controller gain
C00700/6	0: Not connected	LA_NCtrl : nPIDActValue_a Input for actual PID controller value
C00700/7	16000: LS_AnalogInput: nIn1_a	LA_NCtrl : nMainSetValue_a Input for main speed setpoint
C00700/8	0: Not connected	LA_NCtrl : nAuxSetValue_a Input for additional speed setpoint
C00700/9	0: Not connected	LA_NCtrl : nGPAnalogSwitchIn1_a Input for analog switch - analog signal 1
C00700/10	0: Not connected	LA_NCtrl : nGPAnalogSwitchIn2_a Input for analog switch - analog signal 2
C00700/11	0: Not connected	LA_NCtrl : nGPArithmetikIn1_a Input for arithmetic function - analog signal 1
C00700/12	0: Not connected	LA_NCtrl : nGPArithmetikIn2_a Input for arithmetic function - analog signal 2
C00700/13	0: Not connected	LA_NCtrl : nGPMulDivIn_a Input for analog signal for multiplication/division
C00700/14	0: Not connected	LA_NCtrl : nGPCompareIn1_a Input for comparison operation - analog signal 1

Parameter Name: C00700 LA_NCtrl: Analog connection list		Data type: UNSIGNED_16 Index: 23875 _d = 5D43 _h
C00700/15	0: Not connected	LA_NCtrl : nGPCompareIn2_a Input for comparison operation - analog signal 2
C00700/16	0: Not connected	LA_NCtrl : nVoltageAdd_a Input for additive voltage boost
C00700/17	0: Not connected	LA_NCtrl : nPIDInfluence_a Input for influence signal of PID controller correcting variable
C00700/18	0: Not connected	LA_NCtrl : nPIDSetValue_a Input for PID controller setpoint
C00700/19	0: Not connected	LA_NCtrl : nPWMAngleOffset Input for pulse width modulation phase offset
C00700/20	0: Not connected	LA_NCtrl : nBoost_a Input for additional setpoint for motor voltage at speed = 0
C00700/21	0: Not connected	LA_NCtrl : wSMCtrl Interface to the optional safety system
C00700/22	0: Not connected	Reserved
C00700/23	0: Not connected	Reserved
C00700/24	0: Not connected	Reserved
C00700/25	0: Not connected	Reserved
C00700/26	0: Not connected	LA_NCtrl : wFreeIn1 Input for user signal 1
C00700/27	0: Not connected	LA_NCtrl : wFreeIn2 Input for user signal 2
C00700/28	0: Not connected	LA_NCtrl : wFreeIn3 Input for user signal 3
C00700/29	0: Not connected	LA_NCtrl : wFreeIn4 Input for user signal 4
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00701

Parameter Name: C00701 LA_NCtrl: Digital connection list		Data type: UNSIGNED_16 Index: 23874 _d = 5D42 _h
Connection parameters for "Actuating drive speed" application: Binary inputs <ul style="list-style-type: none"> • Selection of the binary output signals to be connected to the binary input signals • The selection list contains all binary output signals which can be assigned to the binary inputs mapped by the subcodes. 		
Selection list See selection list - digital signals		
Subcodes	Lenze setting	Info
C00701/1	0: Not connected	LA_NCtrl : bCInh Control input for setting controller inhibit
C00701/2	16008: LS_DigitalInput: bCInh	LA_NCtrl : bFailReset Control input for error acknowledgement
C00701/3	0: Not connected	LA_NCtrl : bSetQuickstop Control input for quick stop request
C00701/4	16002: LS_DigitalInput: bln3	LA_NCtrl : bSetDCBrake Control input for DC-injection braking request

Parameter Name: C00701 LA_NCtrl: Digital connection list		Data type: UNSIGNED_16 Index: 23874 _d = 5D42 _h
C00701/5	0: Not connected	LA_NCtrl: bRFG_Stop Control input for stopping the speed ramp function generator
C00701/6	0: Not connected	LA_NCtrl: bRFG_0 Control input for setting the speed ramp function generator to 0
C00701/7	0: Not connected	Reserved
C00701/8	16003: LS_DigitalInput: bIn4	LA_NCtrl: bSetSpeedCcw Control input for change of direction of rotation
C00701/9	16000: LS_DigitalInput: bIn1	LA_NCtrl: bJogSpeed1 Selection input for fixed setpoints
C00701/10	16001: LS_DigitalInput: bIn2	LA_NCtrl: bJogSpeed2 Selection input for fixed setpoints
C00701/11	0: Not connected	LA_NCtrl: bJogSpeed4 Selection input for fixed setpoints
C00701/12	0: Not connected	LA_NCtrl: bJogSpeed8 Selection input for fixed setpoints
C00701/13	0: Not connected	LA_NCtrl: bJogRamp1 Selection input for additional acceleration/deceleration times
C00701/14	0: Not connected	LA_NCtrl: bJogRamp2 Selection input for additional acceleration/deceleration times
C00701/15	0: Not connected	LA_NCtrl: bJogRamp4 Selection input for additional acceleration/deceleration times
C00701/16	0: Not connected	LA_NCtrl: bJogRamp8 Selection input for additional acceleration/deceleration times
C00701/17	0: Not connected	LA_NCtrl: bMPOTInAct Control input for deactivation of motor potentiometer
C00701/18	0: Not connected	LA_NCtrl: bMPOTUp Control input for motor potentiometer ramp-up
C00701/19	0: Not connected	LA_NCtrl: bMPOTDown Control input for motor potentiometer ramp-down
C00701/20	0: Not connected	LA_NCtrl: bMBRKRelease Control input for manual holding brake release request
C00701/21	0: Not connected	LA_NCtrl: bGPFree1 Input for binary user signal
C00701/22	0: Not connected	LA_NCtrl: bGPFree2 Input for binary user signal
C00701/23	0: Not connected	LA_NCtrl: bGPAnalogSwitchSet Control input for analog-value selector change-over
C00701/24	0: Not connected	LA_NCtrl: bGPDigitalDelayIn Input for digital signal with time delay
C00701/25	0: Not connected	LA_NCtrl: bGPLogicIn1 Input signal 1 for digital logic
C00701/26	0: Not connected	LA_NCtrl: bGPLogicIn2 Input signal 2 for digital logic
C00701/27	0: Not connected	LA_NCtrl: bGPLogicIn3 Input signal 3 for digital logic

Parameter Name: C00701 LA_NCtrl: Digital connection list		Data type: UNSIGNED_16 Index: 23874 _d = 5D42 _h
C00701/28	0: Not connected	LA_NCtrl: bGPDFlipFlopInD Control input for DFlipFlop setting signal
C00701/29	0: Not connected	LA_NCtrl: bGPDFlipFlopInClk Control input for DFlipFlop clock signal
C00701/30	0: Not connected	LA_NCtrl: bGPDFlipFlopInClr Control input for DFlipFlop reset signal
C00701/31	0: Not connected	LA_NCtrl: bMPotEnable Control input for activation of motor potentiometer
C00701/32	0: Not connected	LA_NCtrl: bPIDEnableInfluenceRamp Control input for activation of influence of output correcting variable of PID controller
C00701/33	0: Not connected	LA_NCtrl: bPIDIOff Control input for deactivation of PID controller I component
C00701/34	20000: LS_ParFix: bTrue	LA_NCtrl: bRLQCw Control input for activation of CW direction of rotation of speed setpoint
C00701/35	0: Not connected	LA_NCtrl: bRLQCcw Control input for activation of CCW direction of rotation of speed setpoint
C00701/36	0: Not connected	Reserved
C00701/37	0: Not connected	Reserved
C00701/38	0: Not connected	Reserved
C00701/39	0: Not connected	Reserved
C00701/40	0: Not connected	Reserved
C00701/41	0: Not connected	LA_NCtrl: bFreeIn1 Input for binary user signal 1
C00701/42	0: Not connected	LA_NCtrl: bFreeIn2 Input for binary user signal 2
C00701/43	0: Not connected	LA_NCtrl: bFreeIn3 Input for binary user signal 3
C00701/44	0: Not connected	LA_NCtrl: bFreeIn4 Input for binary user signal 4
C00701/45	0: Not connected	LA_NCtrl: bFreeIn5 Input for binary user signal 5
C00701/46	0: Not connected	LA_NCtrl: bFreeIn6 Input for binary user signal 6
C00701/47	0: Not connected	LA_NCtrl: bFreeIn7 Input for binary user signal 7
C00701/48	0: Not connected	LA_NCtrl: bFreeIn8 Input for binary user signal 8
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00705

Parameter Name: C00705 LA_NCtrl_Out: Analog signal list		Data type: UNSIGNED_16 Index: 23870 _d = 5D3E _h
This code is for device-internal use only and must not be written to by the user!		

C00706

Parameter Name: C00706 LA_NCtrl_Out digital signal list	Data type: UNSIGNED_16 Index: 23869 _d = 5D3D _h
This code is for device-internal use only and must not be written to by the user!	

C00710

Parameter Name: C00710 LA_TabPos: Analog connection list		Data type: UNSIGNED_16 Index: 23865 _d = 5D3D _h
Connection parameters for "Table positioning" application: 16-bit inputs <ul style="list-style-type: none"> • Selection of the 16 bit output signals to be connected to the 16 bit input signals • The selection list contains all 16 bit output signals which can be assigned to the 16 bit inputs displayed by the subcodes. 		
Selection list		
See selection list - analog signals		
Subcodes	Lenze setting	Info
C00710/1	0: Not connected	LA_TabPos : wCanDriveControl Input for control word from CAN to device control
C00710/2	0: Not connected	LA_TabPos : wMciDriveControl Input for control word from communication interface to device control
C00710/3	0: Not connected	LA_TabPos : nTorqueMotLim_a Input for maximum torque in motor mode
C00710/4	0: Not connected	LA_TabPos : nTorqueGenLim_a Input for maximum torque in generator mode
C00710/5	0: Not connected	LA_TabPos : nMainSetValue_a Input for main speed setpoint
C00710/6	0: Not connected	LA_TabPos : nAuxSetValue_a Input for additional speed setpoint
C00710/7	0: Not connected	LA_TabPos : wMckCtrl1 Input for MCK control word 1
C00710/8	0: Not connected	LA_TabPos : wMckCtrl2 Input for MCK control word 2
C00710/9	0: Not connected	LA_TabPos : wMckOperationMode Input for selection of MCK operating mode
C00710/10	0: Not connected	LA_TabPos : wPosProfileMode Input for selection of MCK positioning mode in positioning mode
C00710/11	0: Not connected	LA_TabPos : wPosProfileNo Input for MCK positioning profile number in positioning mode
C00710/12	0: Not connected	LA_TabPos : nGPAnalogSwitchIn1_a Input for analog switch - analog signal 1
C00710/13	0: Not connected	LA_TabPos : nGPAnalogSwitchIn2_a Input for analog switch - analog signal 2
C00710/14	0: Not connected	LA_TabPos : nGPArithmetikIn1_a Input for arithmetic function - analog signal 1
C00710/15	0: Not connected	LA_TabPos : nGPArithmetikIn2_a Input for arithmetic function - analog signal 2
C00710/16	0: Not connected	LA_TabPos : nGPMulDivIn_a Input for analog signal for multiplication/division
C00710/17	0: Not connected	LA_TabPos : nGPCompareIn1_a Input for comparison operation - analog signal 1

Parameter Name: C00710 LA_TabPos: Analog connection list		Data type: UNSIGNED_16 Index: 23865 _d = 5D39 _h
C00710/18	0: Not connected	LA_TabPos: nGPCompareIn2_a Input for comparison operation - analog signal 2
C00710/19	0: Not connected	LA_TabPos: wGPCounter1LdVal Input for load value for counter module 1
C00710/20	0: Not connected	LA_TabPos: wGPCounter1CmpVal Input for comparison value for counter module 1
C00710/21	0: Not connected	LA_TabPos: nSpeedOverride_a Input for speed override
C00710/22	0: Not connected	LA_TabPos: nAccOverride_a Input for acceleration override
C00710/23	0: Not connected	LA_TabPos: wFreeIn1 Input for user signal 1
C00710/24	0: Not connected	LA_TabPos: wFreeIn2 Input for user signal 2
C00710/25	0: Not connected	LA_TabPos: wFreeIn3 Input for user signal 3
C00710/26	0: Not connected	LA_TabPos: wFreeIn4 Input for user signal 4
C00710/27	0: Not connected	LA_TabPos: nPosCtrlOutLimit Input for correcting variable limitation of position controller
C00710/28	0: Not connected	LA_TabPos: nPosCtrlPAdapt Input for adapting the position controller gain
C00710/29	0: Not connected	LA_TabPos: wSMCtrl Interface to the optional safety system
C00710/30	0: Not connected	LA_TabPos: wPosProfileUnitsLW Input for selecting the target position in [units], Low-Word
C00710/31	0: Not connected	LA_TabPos: wPosProfileUnitsHW Input for selecting the target position in [units], High-Word
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00711

Parameter Name: C00711 LA_TabPos: Digital connection list		Data type: UNSIGNED_16 Index: 23864 _d = 5D38 _h
Connection parameters for "Table positioning" application: Binary inputs <ul style="list-style-type: none"> • Selection of the binary output signals to be connected to the binary input signals • The selection list contains all binary output signals which can be assigned to the binary inputs mapped by the subcodes. 		
Selection list		
See selection list - digital signals		
Subcodes	Lenze setting	Info
C00711/1	0: Not connected	LA_TabPos: bCInh Control input for setting controller inhibit
C00711/2	0: Not connected	LA_TabPos: bFailReset Control input for error acknowledgement
C00711/3	0: Not connected	LA_TabPos: bSetQuickstop Control input for quick stop request
C00711/4	0: Not connected	LA_TabPos: bSetSpeedCcw Control input for negation of speed direction

Parameter Name: C00711 LA_TabPos: Digital connection list		Data type: UNSIGNED_16 Index: 23864 _d = 5D38 _h
C00711/5	0: Not connected	LA_TabPos: bJogSpeed1 Control input for fixed speed selection value 1
C00711/6	0: Not connected	LA_TabPos: bJogSpeed2 Control input for fixed speed selection value 2
C00711/7	0: Not connected	LA_TabPos: bMPotEnable Control input for activation of motor potentiometer
C00711/8	0: Not connected	LA_TabPos: bMPotUp Control input for motor potentiometer ramp-up
C00711/9	0: Not connected	LA_TabPos: bMPotDown Control input for motor potentiometer ramp-down
C00711/10	0: Not connected	LA_TabPos: bMBrakeRelease Control input for manual holding brake release request
C00711/11	0: Not connected	LA_TabPos: bPosCtrlOn Control input for activation of position controller
C00711/12	0: Not connected	LA_TabPos: bLimitSwitchPos Input for positive hardware limit switch signal
C00711/13	0: Not connected	LA_TabPos: bLimitSwitchNeg Input for negative hardware limit switch signal
C00711/14	0: Not connected	LA_TabPos: bReleaseLimitSwitch Control input for hardware limit switch retracting request
C00711/15	0: Not connected	LA_TabPos: bManJogPos Control input for manual jog in positive direction request
C00711/16	0: Not connected	LA_TabPos: bManJogNeg Control input for manual jog in negative direction request
C00711/17	0: Not connected	LA_TabPos: bManEnable2ndSpeed Control input for activation of the second manual speed for manual jog
C00711/18	0: Not connected	LA_TabPos: bEnableSpeedOverride Control input for activation of speed override
C00711/19	0: Not connected	LA_TabPos: bEnableAccOverride Control input for activation of acceleration override
C00711/20	0: Not connected	LA_TabPos: bHomeStartStop Control input for start/stop homing
C00711/21	0: Not connected	LA_TabPos: bHomeSetPosition Control input for setting the home position
C00711/22	0: Not connected	LA_TabPos: bHomeResetPosition Control input for reset of "Home position known"
C00711/23	0: Not connected	LA_TabPos: bHomeMark Input for pre-stop signal for homing
C00711/24	0: Not connected	LA_TabPos: bPosSetProfilePosition Control input for accepting the profile position in the profile data set
C00711/25	0: Not connected	LA_TabPos: bPosSetActualPosition Control input for accepting the current position in the profile data set
C00711/26	0: Not connected	LA_TabPos: bPosExecute Control input for positioning start
C00711/27	0: Not connected	LA_TabPos: bPosFinishTarget Control input for completion of positioning to target position

Parameter Name: C00711 LA_TabPos: Digital connection list		Data type: UNSIGNED_16 Index: 23864 _d = 5D38 _h
C00711/28	0: Not connected	LA_TabPos: bPosDisableFollowProfile Control input for suppression of sequence profile linkage
C00711/29	0: Not connected	LA_TabPos: bPosStop Control input for interruption of profile generation by ramp-down procedure
C00711/30	0: Not connected	LA_TabPos: bGPAnalogSwitchSet Control input for analog-value selector change-over
C00711/31	0: Not connected	LA_TabPos: bGPDigitalDelayIn Input for digital signal with time delay
C00711/32	0: Not connected	LA_TabPos: bGPLogicIn1 Input signal 1 for digital logic
C00711/33	0: Not connected	LA_TabPos: bGPLogicIn2 Input signal 2 for digital logic
C00711/34	0: Not connected	LA_TabPos: bGPLogicIn3 Input signal 3 for digital logic
C00711/35	0: Not connected	LA_TabPos: bGPDFlipFlop_InD Control input for DFlipFlop setting signal
C00711/36	0: Not connected	LA_TabPos: bGPDFlipFlop_InClk Control input for DFlipFlop clock signal
C00711/37	0: Not connected	LA_TabPos: bGPDFlipFlop_InClr Control input for DFlipFlop reset signal
C00711/38	0: Not connected	LA_TabPos: bGPCounter1ClkUp Control input for up-counting counter module 1
C00711/39	0: Not connected	LA_TabPos: bGPCounter1ClkDown Control input for down-counting counter module 1
C00711/40	0: Not connected	LA_TabPos: bGPCounter1Load Control input for load value acceptance in counter module 1
C00711/41	0: Not connected	LA_TabPos: bMckOperationMode_1 Control input for MCK operating mode changeover value 1
C00711/42	0: Not connected	LA_TabPos: bMckOperationMode_2 Control input for MCK operating mode changeover value 2
C00711/43	0: Not connected	LA_TabPos: bMckOperationMode_4 Control input for MCK operating mode changeover value 4
C00711/44	0: Not connected	LA_TabPos: bMckOperationMode_8 Control input for MCK operating mode changeover value 8
C00711/45	0: Not connected	LA_TabPos: bPosProfileNo_1 Control input for selection of profile number value 1
C00711/46	0: Not connected	LA_TabPos: bPosProfileNo_2 Control input for selection of profile number value 2
C00711/47	0: Not connected	LA_TabPos: bPosProfileNo_4 Control input for selection of profile number value 4
C00711/48	0: Not connected	LA_TabPos: bPosProfileNo_8 Control input for selection of profile number value 8
C00711/49	0: Not connected	LA_TabPos: bFreeIn1 Input for binary user signal 1
C00711/50	0: Not connected	LA_TabPos: bFreeIn2 Input for binary user signal 2

Parameter Name: C00711 LA_TabPos: Digital connection list		Data type: UNSIGNED_16 Index: 23864 _d = 5D38 _h
C00711/51	0: Not connected	LA_TabPos: bFreeIn3 Input for binary user signal 3
C00711/52	0: Not connected	LA_TabPos: bFreeIn4 Input for binary user signal 4
C00711/53	0: Not connected	LA_TabPos: bFreeIn5 Input for binary user signal 5
C00711/54	0: Not connected	LA_TabPos: bFreeIn6 Input for binary user signal 6
C00711/55	0: Not connected	LA_TabPos: bFreeIn7 Input for binary user signal 7
C00711/56	0: Not connected	LA_TabPos: bFreeIn8 Input for binary user signal 8
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00712

Parameter Name: C00712 LA_TabPos: phi connection list		Data type: UNSIGNED_16 Index: 23863 _d = 5D37 _h
Connection parameters for "Table positioning" application: 32-bit inputs <ul style="list-style-type: none">• Selection of the 32-bit output signals for connection with the 32-bit input signals• The selection list contains all 32-bit output signals which can be assigned to the 32-bit inputs mapped by the subcodes.		
Selection list		
See selection list - angle signals		
Subcodes	Lenze setting	Info
C00712/1	0: Not connected	LA_TabPos: dnPosProfilePosition Input for selecting the target position in [increments]
C00712/2	0: Not connected	LA_TabPos: dnFreeIn1 Input for 32-bit user signal 1
C00712/3	0: Not connected	LA_TabPos: dnFreeIn2 Input for 32-bit user signal 2
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00715

Parameter Name: C00715 LA_TabPos_Out: Analog signal list		Data type: UNSIGNED_16 Index: 23860 _d = 5D34 _h
This code is for device-internal use only and must not be written to by the user!		

C00716

Parameter Name: C00716 LA_TabPos_Out: Digital signal list		Data type: UNSIGNED_16 Index: 23859 _d = 5D33 _h
This code is for device-internal use only and must not be written to by the user!		

C00717

Parameter Name: C00717 LA_TabPos_Out: phi signal list		Data type: UNSIGNED_16 Index: 23858 _d = 5D32 _h
This code is for device-internal use only and must not be written to by the user!		

C00720

Parameter Name: C00720 L_DigitalDelay_1: Delay			Data type: UNSIGNED_32 Index: 23855 _d = 5D2F _h		
Switch-on/off delay time					
Setting range (min. value unit max. value)					
0.000	s	3600.000			
Subcodes	Lenze setting		Info		
C00720/1	0.000 s		L_DigitalDelay_1 : ON delay		
C00720/2	0.000 s		L_DigitalDelay_1 : OFF delay		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C00721

Parameter Name: C00721 L_DigitalDelay 2..3: Delay			Data type: UNSIGNED_32 Index: 23854 _d = 5D2E _h		
Switch-on/off delay time					
Setting range (min. value unit max. value)					
0.000	s	3600.000			
Subcodes	Lenze setting		Info		
C00721/1	0.000 s		L_DigitalDelay_2 : ON delay		
C00721/2	0.000 s		L_DigitalDelay_2 : OFF delay		
C00721/3	0.000 s		L_DigitalDelay_3 : ON delay		
C00721/4	0.000 s		L_DigitalDelay_3 : OFF delay		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C00725

Parameter Name:		Data type: UNSIGNED_8 Index: 23850 _d = 5D2A _h	
C00725 Current switching frequency			
Display of the current switching frequency			
<ul style="list-style-type: none">• In C00018 you can choose between a drive-optimised setting for good smooth-running characteristics and an inverter loss-optimised setting (min. Pv).• Both possibilities offer fixed and variable switching frequencies.• When a variable switching frequency is selected in C00018, the switching frequency may change as a function of the load and rotational frequency.			
Selection list (read only)			
1	4 kHz var./drive-optimised		
2	8 kHz var./drive-optimised		
3	16 kHz var./drive-optimised		
5	2 kHz constant/drive-optimised		
6	4 kHz constant/drive-optimised		
7	8 kHz constant/drive-optimised		
8	16 kHz constant/drive-optimised		
11	4 kHz var./min. Pv		
12	8 kHz var./min. Pv		
13	16 kHz var./min. Pv		
14	Reserved		
15	2 kHz constant/min. Pv		
16	4 kHz constant/min. Pv		
17	8 kHz constant/min. Pv		
18	16 kHz constant/min. Pv		
21	8 kHz var./drive-opt./4 kHz min		
22	16 kHz var./drive-opt./4 kHz min		
23	16 kHz var./drive-opt./8 kHz min		
31	8 kHz var./min. Pv/4 kHz min		
32	16 kHz var./min. Pv/4 kHz min		
33	16 kHz var./min. Pv/8 kHz min		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00726

Parameter Name:	Data type: UNSIGNED_8
C00726 Current limit values	Index: 23849 _d = 5D29 _h
This code is for device-internal use only and must not be written to by the user!	

C00727

Parameter Name: C00727 LS_Keypad digital values			Data type: UNSIGNED_8 Index: 23848 _d = 5D28 _h
Execution of control commands for keypad operation			
Setting range (min. value unit max. value)			
0		1	
Subcodes	Lenze setting	Info	
C00727/1	0	1 ≡ request quick stop	
C00727/2	0	1 ≡ request DC-injection braking	
C00727/3	0	1 ≡ request change of direction of rotation	
C00727/4	0	1 ≡ request fixed speed setpoint 1	
C00727/5	0	1 ≡ request fixed speed setpoint 2	
C00727/6	0	1 ≡ motor potentiometer: request activation	
C00727/7	0	1 ≡ motor potentiometer: request pos. acceleration	
C00727/8	0	1 ≡ motor potentiometer: request neg. acceleration	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00728

Parameter Name: C00728 Keypad analog values			Data type: INTEGER_16 Index: 23847 _d = 5D27 _h
Selection of different setpoints when operating via keypad			
Setting range (min. value unit max. value)			
-199.99	%	199.99	
Subcodes	Lenze setting	Info	
C00728/1	100.00 %	Torque limit in motor mode	
C00728/2	100.00 %	Torque limit in generator mode	
C00728/3	0.00 %	Setpoint speed	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00729

Parameter Name: C00729 Remote: Setpoint selection			Data type: INTEGER_16 Index: 23846 _d = 5D26 _h
Setting range (min. value unit max. value)			
-199.99		199.99	
Subcodes	Lenze setting	Info	
C00729/1	0.00	Remote: Setpoint keypad	
C00729/2	0.00	Remote: Setpoint PC	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00730

Parameter Name: C00730 Oscilloscope scanning interval			Data type: UNSIGNED_32 Index: 23845 _d = 5D25 _h
This code is for device-internal use only and must not be written to by the user!			

C00731

Parameter Name:	Data type: UNSIGNED_32 Index: 23844 _d = 5D24 _h
C00731 Oscilloscope recording length	
This code is for device-internal use only and must not be written to by the user!	

C00732

Parameter Name:	Data type: UNSIGNED_8 Index: 23843 _d = 5D23 _h
C00732 Oscilloscope command	
This code is for device-internal use only and must not be written to by the user!	

C00734

Parameter Name:	Data type: UNSIGNED_16 Index: 23841 _d = 5D21 _h
C00734 Oscilloscope trigger channel selection	
This code is for device-internal use only and must not be written to by the user!	

C00735

Parameter Name:	Data type: UNSIGNED_8 Index: 23840 _d = 5D20 _h
C00735 Oscilloscope channel source type	
This code is for device-internal use only and must not be written to by the user!	

C00736

Parameter Name:	Data type: UNSIGNED_16 Index: 23839 _d = 5D1F _h
C00736 Oscilloscope data type/data width	
This code is for device-internal use only and must not be written to by the user!	

C00740

Parameter Name:	Data type: UNSIGNED_32 Index: 23835 _d = 5D1B _h
C00740 Oscilloscope offset variables	
This code is for device-internal use only and must not be written to by the user!	

C00741

Parameter Name:	Data type: UNSIGNED_8 Index: 23834 _d = 5D1A _h
C00741 Oscilloscope trigger mode	
This code is for device-internal use only and must not be written to by the user!	

C00742

Parameter Name:	Data type: INTEGER_16 Index: 23833 _d = 5D19 _h
C00742 Oscilloscope trigger delay	
This code is for device-internal use only and must not be written to by the user!	

C00743

Parameter Name:	Data type: UNSIGNED_32 Index: 23832 _d = 5D18 _h
C00743 Oscilloscope trigger level	
This code is for device-internal use only and must not be written to by the user!	

C00744

Parameter Name:	Data type: UNSIGNED_32 Index: 23831 _d = 5D17 _h
C00744 Oscilloscope trigger mask	
This code is for device-internal use only and must not be written to by the user!	

C00746

Parameter Name:	Data type: UNSIGNED_32 Index: 23829 _d = 5D15 _h
C00746 Oscilloscope trigger counter	
This code is for device-internal use only and must not be written to by the user!	

C00747

Parameter Name:	Data type: UNSIGNED_16 Index: 23828 _d = 5D14 _h
C00747 Oscilloscope status word	
This code is for device-internal use only and must not be written to by the user!	

C00748

Parameter Name:	Data type: UNSIGNED_32 Index: 23827 _d = 5D13 _h
C00748 Oscilloscope no. of measured values	
This code is for device-internal use only and must not be written to by the user!	

C00749

Parameter Name:	Data type: UNSIGNED_32 Index: 23826 _d = 5D12 _h
C00749 Oscilloscope recording	
This code is for device-internal use only and must not be written to by the user!	

C00750

Parameter Name:	Data type: UNSIGNED_8 Index: 23825 _d = 5D11 _h
C00750 Select. of MCTRL oscillos. channels	
This code is for device-internal use only and must not be written to by the user!	

C00751

Parameter Name:	Data type: UNSIGNED_32 Index: 23824 _d = 5D10 _h
C00751 Oscilloscope data memory	
This code is for device-internal use only and must not be written to by the user!	

C00753

Parameter Name:	Data type: OCTET_STRING Index: 23822 _d = 5D0E _h
C00753 Oscilloscope data memory octet string	
This code is for device-internal use only and must not be written to by the user!	

C00760

Parameter Name: C00760 LA_SwitchPos: Analog connection list		Data type: UNSIGNED_16 Index: 23815 _d = 5D07 _h
Connection parameters for "Switch-off positioning" application: 16-bit inputs <ul style="list-style-type: none"> • Selection of the 16 bit output signals to be connected to the 16 bit input signals • The selection list contains all 16 bit output signals which can be assigned to the 16 bit inputs displayed by the subcodes. 		
Selection list		
See selection list - analog signals		
Subcodes	Lenze setting	Info
C00760/1	0: Not connected	LA_SwitchPos : wCANDriveControl Input for control word from CAN to device control
C00760/2	0: Not connected	LA_SwitchPos : wMCIDriveControl Input for control word from communication interface to device control
C00760/3	0: Not connected	LA_SwitchPos : nVoltageAdd_a Input for additive voltage impression
C00760/4	0: Not connected	LA_SwitchPos : nBoost_a Input for additional setpoint for motor voltage at speed = 0
C00760/5	0: Not connected	LA_SwitchPos : nPWMAngleOffset Input for additional offset for the electrical angle of rotation
C00760/6	0: Not connected	LA_SwitchPos : nTorqueMotLim_a Input for maximum torque in motor mode
C00760/7	0: Not connected	LA_SwitchPos : nTorqueGenLim_a Input for maximum torque in generator mode
C00760/8	0: Not connected	LA_SwitchPos : nMainSetValue_a Input for main speed setpoint
C00760/9	0: Not connected	LA_SwitchPos : nAuxSetValue_a Input for additional speed setpoint
C00760/10	0: Not connected	LA_SwitchPos : nGPAnalogSwitchIn1_a Input for analog switch - analog signal 1
C00760/11	0: Not connected	LA_SwitchPos : nGPAnalogSwitchIn2_a Input for analog switch - analog signal 2
C00760/12	0: Not connected	LA_SwitchPos : nGPArithmetikIn1_a Input for arithmetic function - analog signal 1
C00760/13	0: Not connected	LA_SwitchPos : nGPArithmetikIn2_a Input for arithmetic function - analog signal 2
C00760/14	0: Not connected	LA_SwitchPos : nGPMulDivIn_a Input for analog signal for multiplication/division
C00760/15	0: Not connected	LA_SwitchPos : nGPCompareIn1_a Input for comparison operation - analog signal 1
C00760/16	0: Not connected	LA_SwitchPos : nGPCompareIn2_a Input for comparison operation - analog signal 2
C00760/17	0: Not connected	LA_SwitchPos : wSMCtrl Interface to the optional safety system
C00760/18	0: Not connected	Reserved
C00760/19	0: Not connected	Reserved
C00760/20	0: Not connected	Reserved
C00760/21	0: Not connected	Reserved

Parameter Name: C00760 LA_SwitchPos: Analog connection list		Data type: UNSIGNED_16 Index: 23815 _d = 5D07 _h
C00760/22	0: Not connected	LA_SwitchPos : wFreeIn1 Input for user signal 1
C00760/23	0: Not connected	LA_SwitchPos : wFreeIn2 Input for user signal 2
C00760/24	0: Not connected	LA_SwitchPos : wFreeIn3 Input for user signal 3
C00760/25	0: Not connected	LA_SwitchPos : wFreeIn4 Input for user signal 4
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00761

Parameter Name: C00761 LA_SwitchPos: Digital connection list		Data type: UNSIGNED_16 Index: 23814 _d = 5D06 _h
Connection parameters for "Switch-off positioning" application: Binary inputs <ul style="list-style-type: none"> • Selection of the binary output signals to be connected to the binary input signals • The selection list contains all binary output signals which can be assigned to the binary inputs mapped by the subcodes. 		
Selection list		
See selection list - digital signals		
Subcodes	Lenze setting	Info
C00761/1	0: Not connected	LA_SwitchPos : bCInh Control input for setting controller inhibit
C00761/2	0: Not connected	LA_SwitchPos : bFailReset Control input for error acknowledgement
C00761/3	0: Not connected	LA_SwitchPos : bSetQuickstop Control input for quick stop request
C00761/4	0: Not connected	LA_SwitchPos : bSetDCBrake Control input for DC-injection braking request
C00761/5	0: Not connected	LA_SwitchPos : bRFG_Stop Control input for stopping the speed ramp function generator
C00761/6	0: Not connected	LA_SwitchPos : bSetSpeedCcw Control input for change of direction of rotation
C00761/7	0: Not connected	LA_SwitchPos : bRLQCw Control input for activation of CW rotation (fail-safe)
C00761/8	0: Not connected	LA_SwitchPos : bRLQCcw Control input for activation of CCW rotation (fail-safe)
C00761/9	0: Not connected	LA_SwitchPos : bJogCtrlInputSel1 Selection input 1 for binary coded selection of the switch-off position 1 ... 3
C00761/10	0: Not connected	LA_SwitchPos : bJogCtrlInputSel2 Selection input 2 for binary coded selection of the switch-off position 1 ... 3
C00761/11	0: Not connected	LA_SwitchPos : bJogCtrlRfgIn Control input for setpoint generator ramp-down
C00761/12	0: Not connected	LA_SwitchPos : bJogCtrlJog1 Selection input 1 for overriding fixed setpoints (JOG setpoints) for the main setpoint
C00761/13	0: Not connected	LA_SwitchPos : bJogCtrlJog2 Selection input 2 for overriding fixed setpoints (JOG setpoints) for the main setpoint

Parameter Name: C00761 LA_SwitchPos: Digital connection list		Data type: UNSIGNED_16 Index: 23814 _d = 5D06 _h
C00761/14	0: Not connected	LA_SwitchPos : bJogCtrlSlowDown1 Control input for selection of pre-switch off 1
C00761/15	0: Not connected	LA_SwitchPos : bJogCtrlStop1 Control input for stop function 1
C00761/16	0: Not connected	LA_SwitchPos : bJogCtrlSlowDown2 Control input for selection of pre-switch off 2
C00761/17	0: Not connected	LA_SwitchPos : bJogCtrlStop2 Control input for stop function 2
C00761/18	0: Not connected	LA_SwitchPos : bJogCtrlSlowDown3 Control input for selection of pre-switch off 3
C00761/19	0: Not connected	LA_SwitchPos : bJogCtrlStop3 Control input for stop function 3
C00761/20	0: Not connected	LA_SwitchPos : bJogSpeed4 Selection input for fixed setpoints
C00761/21	0: Not connected	LA_SwitchPos : bJogSpeed8 Selection input for fixed setpoints
C00761/22	0: Not connected	LA_SwitchPos : bJogRamp1 Selection input for additional acceleration/deceleration times
C00761/23	0: Not connected	LA_SwitchPos : bJogRamp2 Selection input for additional acceleration/deceleration times
C00761/24	0: Not connected	LA_SwitchPos : bJogRamp4 Selection input for additional acceleration/deceleration times
C00761/25	0: Not connected	LA_SwitchPos : bJogRamp8 Selection input for additional acceleration/deceleration times
C00761/26	0: Not connected	LA_SwitchPos : bMBrkRelease Control input for manual holding brake release request
C00761/27	0: Not connected	LA_SwitchPos : bGPAnalogSwitchSet Control input for analog-value selector change-over
C00761/28	0: Not connected	LA_SwitchPos : bGPDigitalDelayIn Input for digital signal with time delay
C00761/29	0: Not connected	LA_SwitchPos : bGPLogicIn1 Input signal 1 for digital logic
C00761/30	0: Not connected	LA_SwitchPos : bGPLogicIn2 Input signal 2 for digital logic
C00761/31	0: Not connected	LA_SwitchPos : bGPLogicIn3 Input signal 3 for digital logic
C00761/32	0: Not connected	LA_SwitchPos : bGPDFlipFlop_InD Control input for DFlipFlop setting signal
C00761/33	0: Not connected	LA_SwitchPos : bGPDFlipFlop_InClk Control input for DFlipFlop clock signal
C00761/34	0: Not connected	LA_SwitchPos : bGPDFlipFlop_InClr Control input for DFlipFlop reset signal
C00761/35	0: Not connected	Reserved
C00761/36	0: Not connected	Reserved
C00761/37	0: Not connected	Reserved
C00761/38	0: Not connected	Reserved
C00761/39	0: Not connected	Reserved

Parameter Name:		Data type: UNSIGNED_16 Index: 23814 _d = 5D06 _h
C00761 LA_SwitchPos: Digital connection list		
C00761/40	0: Not connected	LA_SwitchPos : bFreeIn1 Input for binary user signal 1
C00761/41	0: Not connected	LA_SwitchPos : bFreeIn2 Input for binary user signal 2
C00761/42	0: Not connected	LA_SwitchPos : bFreeIn3 Input for binary user signal 3
C00761/43	0: Not connected	LA_SwitchPos : bFreeIn4 Input for binary user signal 4
C00761/44	0: Not connected	LA_SwitchPos : bFreeIn5 Input for binary user signal 5
C00761/45	0: Not connected	LA_SwitchPos : bFreeIn6 Input for binary user signal 6
C00761/46	0: Not connected	LA_SwitchPos : bFreeIn7 Input for binary user signal 7
C00761/47	0: Not connected	LA_SwitchPos : bFreeIn8 Input for binary user signal 8
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00762

Parameter Name:	Data type: UNSIGNED_16 Index: 23813 _d = 5D05 _h
C00762 LA_SwitchPos: phi connection list	
This code is for device-internal use only and must not be written to by the user!	

C00765

Parameter Name:	Data type: UNSIGNED_16 Index: 23810 _d = 5D02 _h
C00765 LA_SwitchPos_Out: Analog signal list	
This code is for device-internal use only and must not be written to by the user!	

C00766

Parameter Name:	Data type: UNSIGNED_16 Index: 23809 _d = 5D01 _h
C00766 LA_SwitchPos_Out: Digital signal list	
This code is for device-internal use only and must not be written to by the user!	

C00767

Parameter Name:	Data type: UNSIGNED_16 Index: 23808 _d = 5D00 _h
C00767 LA_SwitchPos_Out: phi signal list	
This code is for device-internal use only and must not be written to by the user!	

C00800

Parameter Name:		Data type: INTEGER_16 Index: 23775 _d = 5CDF _h
C00800 L_MPot_1: Upper limit		
The L_MPot_1 FB: Upper limit of the motor potentiometer function		
Setting range (min. value unit max. value)		Lenze setting
-199.99	%	199.99
		100.00 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100		

C00801

Parameter Name: C00801 L_MPot_1: Lower limit			Data type: INTEGER_16 Index: 23774 _d = 5CDE _h
The L_MPot_1 FB: Lower limit of the motor potentiometer function			
Setting range (min. value unit max. value)			Lenze setting
-199.99	%	199.99	-100.00 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00802

Parameter Name: C00802 L_MPot_1: Acceleration time			Data type: UNSIGNED_16 Index: 23773 _d = 5CDD _h
The L_MPot_1 FB: Acceleration time of the motor potentiometer function			
Setting range (min. value unit max. value)			Lenze setting
0.1	s	6000.0	10.0 s
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10			

C00803

Parameter Name: C00803 L_MPot_1: Deceleration time			Data type: UNSIGNED_16 Index: 23772 _d = 5CDC _h
The L_MPot_1 FB: Deceleration time of the motor potentiometer function			
Setting range (min. value unit max. value)			Lenze setting
0.1	s	6000.0	10.0 s
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10			

C00804

Parameter Name: C00804 L_MPot_1: Inactive fct.		Data type: UNSIGNED_8 Index: 23771 _d = 5CDB _h
The L_MPot_1 FB: Selection of the response if the motor potentiometer is deactivated via input <i>blnAct</i>		
Selection list (Lenze setting printed in bold)		Info
0	Retain value	Keep output value
1	Deceleration to 0	Deceleration via ramp to 0
2	Deceleration to lower limit	Deceleration via ramp to the lower limit (C00801)
3	Without ramp to 0	Step change to 0
4	Without ramp to lower limit	Jump to lower limit (C00800)
5	Acceleration to upper limit	Acceleration via ramp to upper limit (C00800)
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00805

Parameter Name: C00805 L_MPot_1: Init fct.		Data type: UNSIGNED_8 Index: 23770 _d = 5CDA _h
The L_MPot_1 FB: Selection of the response at device switch-on		
Selection list (Lenze setting printed in bold)		
0	Load last value	
1	Load lower limit	
2	Load 0	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00806

Parameter Name: C00806 L_MPot_1: Use		Data type: UNSIGNED_8 Index: 23769 _d = 5CD9 _h
The L_MPot_1 FB: Use of the motor potentiometer		
Selection list (Lenze setting printed in bold)		Info
0	No	The motor potentiometer is not used. • The analog value applied to the <i>nIn_a</i> input is looped through without any changes to the <i>nOut_a</i> output.
1	Yes	The motor potentiometer is used. • The analog value applied at the <i>nIn_a</i> input is led via the motor potentiometer and provided at the <i>nOut_a</i> output.
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00807

Parameter Name: C00807 L_NLim_1: Max.SkipFrq.		Data type: INTEGER_16 Index: 23768 _d = 5CD8 _h
FB L_NLim_1 : Maximum blocking frequencies		
Setting range (min. value unit max. value)		
0.00	%	199.99
Subcodes	Lenze setting	Info
C00807/1	0.00 %	Maximum blocking frequency for zone 1
C00807/2	0.00 %	Maximum blocking frequency for zone 2
C00807/3	0.00 %	Maximum blocking frequency for zone 3
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100		

C00808

Parameter Name: C00808 L_NLim_1: Min.SkipFrq.		Data type: INTEGER_16 Index: 23767 _d = 5CD7 _h
FB L_NLim_1 : Minimum skip frequencies		
Setting range (min. value unit max. value)		
0.00	%	199.99
Subcodes	Lenze setting	Info
C00808/1	0.00 %	Minimum blocking frequency for zone 1
C00808/2	0.00 %	Minimum blocking frequency for zone 2
C00808/3	0.00 %	Minimum blocking frequency for zone 2
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100		

C00809

Parameter Name: C00809 L_NLim_2: Max.SkipFrq.			Data type: INTEGER_16 Index: 23766 _d = 5CD6 _h		
FB <u>L_NLim_2</u> : Maximum skip frequencies					
Setting range (min. value unit max. value)					
0.00	%	199.99			
Subcodes	Lenze setting	Info			
C00809/1	0.00 %	Maximum blocking frequency for zone 1			
C00809/2	0.00 %	Maximum blocking frequency for zone 2			
C00809/3	0.00 %	Maximum blocking frequency for zone 3			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00810

Parameter Name: C00810 L_NLim_2: Min.SkipFrq.			Data type: INTEGER_16 Index: 23765 _d = 5CD5 _h		
FB <u>L_NLim_2</u> : Minimum skip frequencies					
Setting range (min. value unit max. value)					
0.00	%	199.99			
Subcodes	Lenze setting		Info		
C00810/1	0.00 %		Minimum blocking frequency for zone 1		
C00810/2	0.00 %		Minimum blocking frequency for zone 2		
C00810/3	0.00 %		Minimum blocking frequency for zone 3		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00811

Parameter Name: C00811 L_NLim_1: Current output value			Data type: INTEGER_16 Index: 23764 _d = 5CD4 _h		
From version 02.00.00					
Display range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes			Info		
C00811/1			L_NLim_1 : Current output value		
C00811/2			L_NLim_2 : Current output value		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00812

Parameter Name: C00812 L_NLim: Current status			Data type: UNSIGNED_16 Index: 23763 _d = 5CD3 _h
From version 02.00.00			
Display area (min. hex value max. hex value)			
0x0000		0xFFFF	
Value is bit-coded:			
Bit 0	No blocking zone active		
Bit 1	Blocking zone 1 active		
Bit 2	Blocking zone 2 active		
Bit 3	Blocking zone 3 active		
Bit 4	Value in blocking zone		
Bit 5	Reserved		
Bit 6	Reserved		
Bit 7	Reserved		
Bit 8	Reserved		
Bit 9	Reserved		
Bit 10	Reserved		
Bit 11	Reserved		
Bit 12	Reserved		
Bit 13	Reserved		
Bit 14	Reserved		
Bit 15	Reserved		
Subcodes			Info
C00812/1			L_NLim_1 : Current status
C00812/2			L_NLim_2 : Current status
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT			

C00820

Parameter Name: C00820 L_DigitalLogic_1: Function		Data type: UNSIGNED_8 Index: 23755 _d = 5CCB _h
The L_DigitalLogic_1 FB: Selection of the internal logic function		
Selection list (Lenze setting printed in bold)		Info
0	bOut = 0	Constant value "FALSE"
1	bOut = 1	Constant value "TRUE"
2	bOut = bln1 AND bln2 AND bln3	AND operation
3	bOut = bln1 OR bln2 OR bln3	OR operation
4	bOut = f (truth table)	The truth table parameterised in C00821 is used.
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00821

Parameter Name: C00821 L_DigitalLogic_1: Truth table		Data type: UNSIGNED_8 Index: 23754 _d = 5CCA _h
The L_DigitalLogic_1 FB: Parameterisation of the truth table		
Selection list		
0	False	
1	True	
Subcodes	Lenze setting	Info
C00821/1	0: FALSE	L_DigitalLogic_1 : bIn3...bIn1=0 0 0
C00821/2	0: FALSE	L_DigitalLogic_1 : bIn3...bIn1=0 0 1
C00821/3	0: FALSE	L_DigitalLogic_1 : bIn3...bIn1=0 1 0
C00821/4	0: FALSE	L_DigitalLogic_1 : bIn3...bIn1=0 1 1
C00821/5	0: FALSE	L_DigitalLogic_1 : bIn3...bIn1=1 0 0
C00821/6	0: FALSE	L_DigitalLogic_1 : bIn3...bIn1=1 0 1
C00821/7	0: FALSE	L_DigitalLogic_1 : bIn3...bIn1=1 1 0
C00821/8	0: FALSE	L_DigitalLogic_1 : bIn3...bIn1=1 1 1
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00822

Parameter Name: C00822 L_DigitalLogic_2: Function		Data type: UNSIGNED_8 Index: 23753 _d = 5CC9 _h
The L_DigitalLogic_2 FB: Selection of the internal logic function		
Selection list (Lenze setting printed in bold)		Info
0	bOut = 0	Constant value "FALSE"
1	bOut = 1	Constant value "TRUE"
2	bOut = bIn1 AND ... bIn3	AND operation
3	bOut = bIn1 OR ... bIn3	OR operation
4	bOut = f (truth table)	The truth table parameterised in C00823 is used.
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00823

Parameter Name: C00823 L_DigitalLogic_2: Truth table		Data type: UNSIGNED_8 Index: 23752 _d = 5CC8 _h
The L_DigitalLogic_2 FB: Parameterisation of the truth table		
Selection list		
0	False	
1	True	
Subcodes	Lenze setting	Info
C00823/1	0: FALSE	L_DigitalLogic_2 : bIn3...bIn1=0 0 0
C00823/2	0: FALSE	L_DigitalLogic_2 : bIn3...bIn1=0 0 1
C00823/3	0: FALSE	L_DigitalLogic_2 : bIn3...bIn1=0 1 0
C00823/4	0: FALSE	L_DigitalLogic_2 : bIn3...bIn1=0 1 1
C00823/5	0: FALSE	L_DigitalLogic_2 : bIn3...bIn1=1 0 0
C00823/6	0: FALSE	L_DigitalLogic_2 : bIn3...bIn1=1 0 1
C00823/7	0: FALSE	L_DigitalLogic_2 : bIn3...bIn1=1 1 0
C00823/8	0: FALSE	L_DigitalLogic_2 : bIn3...bIn1=1 1 1
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00824

Parameter Name: C00824 L_DigitalLogic5_1: Function		Data type: UNSIGNED_8 Index: 23751 _d = 5CC7 _h
FB L_DigitalLogic5_1 : Selection of the interna logic operation		
Selection list (Lenze setting printed in bold)		Info
0	bOut = 0	The truth table parameterised in C00825 is used.
1	bOut = 1	
2	bOut = f (truth table)	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00825

Parameter Name: C00825 L_DigitalLogic5_1: Truth table		Data type: UNSIGNED_8 Index: 23750 _d = 5CC6 _h
FB L_DigitalLogic5_1 : Parameter setting of the truth table		
Selection list		
0	False	
1	True	
Subcodes	Lenze setting	Info
C00825/1	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 0 0 0 0
C00825/2	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 0 0 0 1
C00825/3	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 0 0 1 0
C00825/4	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 0 0 1 1
C00825/5	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 0 1 0 0
C00825/6	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 0 1 0 1
C00825/7	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 0 1 1 0
C00825/8	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 0 1 1 1
C00825/9	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 1 0 0 0
C00825/10	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 1 0 0 1

Parameter Name: C00825 L_DigitalLogic5_1: Truth table			Data type: UNSIGNED_8 Index: 23750 _d = 5CC6 _h
C00825/11	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 1 0 1 0	
C00825/12	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 1 0 1 1	
C00825/13	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 1 1 0 0	
C00825/14	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 1 1 0 1	
C00825/15	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 1 1 1 0	
C00825/16	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=0 1 1 1 1	
C00825/17	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 0 0 0 0	
C00825/18	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 0 0 0 1	
C00825/19	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 0 0 1 0	
C00825/20	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 0 0 1 1	
C00825/21	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 0 1 0 0	
C00825/22	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 0 1 0 1	
C00825/23	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 0 1 1 0	
C00825/24	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 0 1 1 1	
C00825/25	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 1 0 0 0	
C00825/26	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 1 0 0 1	
C00825/27	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 1 0 1 0	
C00825/28	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 1 0 1 1	
C00825/29	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 1 1 0 0	
C00825/30	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 1 1 0 1	
C00825/31	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 1 1 1 0	
C00825/32	0: FALSE	L_DigitalLogic5_1 : bIn5...bIn1=1 1 1 1 1	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00826

Parameter Name: C00826 L_DigitalLogic5_2: Function		Data type: UNSIGNED_8 Index: 23749 _d = 5CC5 _h
FB L_DigitalLogic5_2 : Selection of the interna logic operation		
Selection list (Lenze setting printed in bold)		Info
0	bOut = 0	
1	bOut = 1	
2	bOut = f (truth table)	The truth table parameterised in C00827 is used.
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00827

Parameter Name: C00827 L_DigitalLogic5_2: Truth table			Data type: UNSIGNED_8 Index: 23748 _d = 5CC4 _h
FB L_DigitalLogic5_2 : Parameter setting of the truth table			
Selection list			
0	False		
1	True		
Subcodes	Lenze setting	Info	
C00827/1	0: FALSE	L_DigitalLogic5_2 : bIn5...bIn1=0 0 0 0 0	
C00827/2	0: FALSE	L_DigitalLogic5_2 : bIn5...bIn1=0 0 0 0 1	

Parameter Name: C00827 L_DigitalLogic5_2: Truth table		Data type: UNSIGNED_8 Index: 23748 _d = 5CC4 _h
C00827/3	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=0 0 0 1 0
C00827/4	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=0 0 0 1 1
C00827/5	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=0 0 1 0 0
C00827/6	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=0 0 1 0 1
C00827/7	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=0 0 1 1 0
C00827/8	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=0 0 1 1 1
C00827/9	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=0 1 0 0 0
C00827/10	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=0 1 0 0 1
C00827/11	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=0 1 0 1 0
C00827/12	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=0 1 0 1 1
C00827/13	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=0 1 1 0 0
C00827/14	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=0 1 1 0 1
C00827/15	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=0 1 1 1 0
C00827/16	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=0 1 1 1 1
C00827/17	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 0 0 0 0
C00827/18	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 0 0 0 1
C00827/19	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 0 0 1 0
C00827/20	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 0 0 1 1
C00827/21	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 0 1 0 0
C00827/22	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 0 1 0 1
C00827/23	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 0 1 1 0
C00827/24	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 0 1 1 1
C00827/25	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 1 0 0 0
C00827/26	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 1 0 0 1
C00827/27	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 1 0 1 0
C00827/28	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 1 0 1 1
C00827/29	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 1 1 0 0
C00827/30	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 1 1 0 1
C00827/31	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 1 1 1 0
C00827/32	0: FALSE	L_DigitalLogic5_2 : bln5...bln1=1 1 1 1 1
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00828

Parameter Name: C00828 L_DigitalLogic_3: Function		Data type: UNSIGNED_8 Index: 23747 _d = 5CC3 _h
From version 02.00.00 The L_DigitalLogic_3 FB: Selection of the internal logic function		
Selection list (Lenze setting printed in bold)		Info
0	bOut = 0	Constant value "FALSE"
1	bOut = 1	Constant value "TRUE"
2	bOut = bln1 AND bln2 AND bln3	AND operation
3	bOut = bln1 OR bln2 OR bln3	OR operation
4	bOut = f (truth table)	The truth table parameterised in C00829 is used.
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00829

Parameter Name: C00829 L_DigitalLogic_3: Truth table		Data type: UNSIGNED_8 Index: 23746 _d = 5CC2 _h
From version 02.00.00 The L_DigitalLogic_3 FB: Parameterisation of the truth table		
Selection list		
0	False	
1	True	
Subcodes	Lenze setting	Info
C00829/1	0: FALSE	L_DigitalLogic_3 : bIn3...bIn1=0 0 0
C00829/2	0: FALSE	L_DigitalLogic_3 : bIn3...bIn1=0 0 1
C00829/3	0: FALSE	L_DigitalLogic_3 : bIn3...bIn1=0 1 0
C00829/4	0: FALSE	L_DigitalLogic_3 : bIn3...bIn1=0 1 1
C00829/5	0: FALSE	L_DigitalLogic_3 : bIn3...bIn1=1 0 0
C00829/6	0: FALSE	L_DigitalLogic_3 : bIn3...bIn1=1 0 1
C00829/7	0: FALSE	L_DigitalLogic_3 : bIn3...bIn1=1 1 0
C00829/8	0: FALSE	L_DigitalLogic_3 : bIn3...bIn1=1 1 1
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00830

Parameter Name: C00830 16-bit inputs [%]			Data type: INTEGER_16 Index: 23745 _d = 5CC1 _h
Display in percent of 16-bit input values of different blocks			
Display range (min. value unit max. value)			
-199.99	%	199.99	
Subcodes			Info
C00830/1			L Absolut 1 : nIn_a
C00830/2			L AddSub 1 : nIn1_a
C00830/3			L AddSub 1 : nIn2_a
C00830/4			L AddSub 1 : nIn3_a
C00830/5			L OffsetGain 1 : nIn_a
C00830/6			L OffsetGain 1 : nOffset_a
C00830/7			L OffsetGain 1 : nGain_a
C00830/8			L Negation 1 : nIn_a
C00830/9			L GainOffset 1 : nIn_a
C00830/10			L GainOffset 1 : nGain_a
C00830/11			L GainOffset 1 : nOffset_a
C00830/12			L Arithmetik 1 : nIn1_a
C00830/13			L Arithmetik 1 : nIn2_a
C00830/14			L AnalogSwitch 1 : nIn1_a
C00830/15			L AnalogSwitch 1 : nIn2_a
C00830/16			L Compare 1 : nIn1_a
C00830/17			L Compare 1 : nIn2_a
C00830/18			MCTRL : nTorqueLimitAdapt_a
C00830/19			Reserved
C00830/20			MCTRL : nPosCtrlPAdapt_a
C00830/21			MCTRL : nPosCtrlOutLimit_a
C00830/22			MCTRL : nSpeedSetValue_a
C00830/23			MCTRL : nSpeedLowLimit_a
C00830/24			MCTRL : nSpeedCtrlI_a
C00830/25			MCTRL : nSpeedCtrlPAdapt_a
C00830/26			MCTRL : nBoost_a
C00830/27			MCTRL : nTorqueSetValue_a
C00830/28			MCTRL : nTorqueGenLimit_a
C00830/29			MCTRL : nTorqueMotLimit_a
C00830/30			Reserved
C00830/31			MCTRL : nVoltageAdd_a
C00830/32			MCTRL : nPWMAngleOffset_a
C00830/33			L NSet 1 : nCInhVal_a
C00830/34			L NSet 1 : nNSet_a
C00830/35			L NSet 1 : nSet_a
C00830/36			L NSet 1 : nNAdd_a
C00830/37			DCTRL : wCANControl
C00830/38			DCTRL : wCCMControl

Parameter Name: C00830 16-bit inputs [%]		Data type: INTEGER_16 Index: 23745 _d = 5CC1 _h
C00830/39	L_NLim_1 : nIn_a	
C00830/40	Reserved	
C00830/41	L_Compare_2 : nIn1_a	
C00830/42	L_Compare_2 : nIn2_a	
C00830/43	L_Compare_3 : nIn1_a	
C00830/44	L_Compare_3 : nIn2_a	
C00830/45	L_AnalogSwitch_2 : nIn1_a	
C00830/46	L_AnalogSwitch_2 : nIn2_a	
C00830/47	L_AnalogSwitch_3 : nIn1_a	
C00830/48	L_AnalogSwitch_3 : nIn2_a	
C00830/49	L_Arithmetik_2 : nIn1_a	
C00830/50	L_Arithmetik_2 : nIn2_a	
C00830/51	Reserved	
C00830/52	Reserved	
C00830/53	L_GainOffset_2 : nIn_a	
C00830/54	L_GainOffset_2 : nGain_a	
C00830/55	L_GainOffset_2 : nOffset_a	
C00830/56	L_OffsetGainP_1 : nIn_a	
C00830/57	L_OffsetGainP_2 : nIn_a	
C00830/58	L_OffsetGain_2 : nIn_a	
C00830/59	L_OffsetGain_2 : nOffset_a	
C00830/60	L_OffsetGain_2 : nGain_a	
C00830/61	L_PCTRL_1 : nAct_a	
C00830/62	L_PCTRL_1 : nAdapt_a	
C00830/63	L_PCTRL_1 : nSet_a	
C00830/64	L_PCTRL_1 : nInfluence_a	
C00830/65	MCK: nSpeedCtrlI_a	
C00830/66	MCK: nPWMAngleOffset_a	
C00830/67	Reserved	
C00830/68	MCK: nMBrakeAddValue_a	
C00830/69	MCK: nTorqueSetValue_a	
C00830/70	MCK: nTorqueLimitAdapt_a	
C00830/71	MCK: nSRampOverride_a	
C00830/72	MCK: nSpeedSetValue_a	
C00830/73	MCK: wMotionCtrl2	
C00830/74	MCK: wMotionCtrl1	
C00830/75	MCK: nSpeedOverride_a	
C00830/76	MCK: nAccOverride_a	
C00830/77	MCK: nSpeedAdd_v	
C00830/78	MCK: wAuxCtrl	
C00830/79	MCK: wSMCtrl	
C00830/80	L_OffsetGainP_3 : nIn_a	
C00830/81	L_MPot_1 : nIn_a	
C00830/82	L_MulDiv_1 : nIn_a	

Parameter Name: C00830 16-bit inputs [%]		Data type: INTEGER_16 Index: 23745 _d = 5CC1 _h
C00830/83	LS_DataAccess: wIn1 (Lenze-internal)	
C00830/84	LS_DataAccess: wIn2 (Lenze-internal)	
C00830/85	LS_DataAccess: wIn3 (Lenze-internal)	
C00830/86	LS_DataAccess: wIn4 (Lenze-internal)	
C00830/87	L_PT1_1 : nIn_a	
C00830/88	MCTRL : nSpeedHighLimit_a	
C00830/89	L_PCTRL_1 : nNSet_a	
C00830/90	L_PCTRL_1 : nISet_a	
C00830/91	L_Interpolator_1 : nPhdIn_v	
C00830/92	L_Interpolator_1 : nNIn_a	
C00830/93	Reserved	
C00830/94	Reserved	
C00830/95	Reserved	
C00830/96	MCTRL : nInertiaAdapt_a	
C00830/97	MCTRL : nSpeedSetValueInertia_a	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100		

C00831

Parameter Name: C00831 16-bit inputs		Data type: UNSIGNED_16 Index: 23744 _d = 5CC0 _h
Decimal/hexadecimal/bit coded display of 16 bit input values of various blocks		
Display area (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		
Bit 0	Active	
...	...	
Bit 15	Active	
Subcodes	Info	
C00831/1	L_Absolut_1 : nIn_a	
C00831/2	L_AddSub_1 : nIn1_a	
C00831/3	L_AddSub_1 : nIn2_a	
C00831/4	L_AddSub_1 : nIn3_a	
C00831/5	L_OffsetGain_1 : nIn_a	
C00831/6	L_OffsetGain_1 : nOffset_a	
C00831/7	L_OffsetGain_1 : nGain_a	
C00831/8	L_Negation_1 : nIn_a	
C00831/9	L_GainOffset_1 : nIn_a	
C00831/10	L_GainOffset_1 : nGain_a	
C00831/11	L_GainOffset_1 : nOffset_a	
C00831/12	L_Arithmetik_1 : nIn1_a	
C00831/13	L_Arithmetik_1 : nIn2_a	

Parameter Name: C00831 16-bit inputs		Data type: UNSIGNED_16 Index: 23744 _d = 5C0 _h
C00831/14	L AnalogSwitch 1 : nIn1_a	
C00831/15	L AnalogSwitch 1 : nIn2_a	
C00831/16	L Compare 1 : nIn1_a	
C00831/17	L Compare 1 : nIn2_a	
C00831/18	MCTRL : nTorqueLimitAdapt_a	
C00831/19	Reserved	
C00831/20	MCTRL : nPosCtrlPAdapt_a	
C00831/21	MCTRL : nPosCtrlOutLimit_a	
C00831/22	MCTRL : nSpeedSetValue_a	
C00831/23	MCTRL : nSpeedLowLimit_a	
C00831/24	MCTRL : nSpeedCtrlI_a	
C00831/25	MCTRL : nSpeedCtrlPAdapt_a	
C00831/26	MCTRL : nBoost_a	
C00831/27	MCTRL : nTorqueSetValue_a	
C00831/28	MCTRL : nTorqueGenLimit_a	
C00831/29	MCTRL : nTorqueMotLimit_a	
C00831/30	Reserved	
C00831/31	MCTRL : nVoltageAdd_a	
C00831/32	MCTRL : nPWMAngleOffset_a	
C00831/33	L NSet 1 : nCInhVal_a	
C00831/34	L NSet 1 : nNSet_a	
C00831/35	L NSet 1 : nSet_a	
C00831/36	L NSet 1 : nNAdd_a	
C00831/37	DCTRL : wCANControl	
C00831/38	DCTRL : wMCIControl	
C00831/39	L NLim 1 : nIn_a	
C00831/40	Reserved	
C00831/41	L Compare 2 : nIn1_a	
C00831/42	L Compare 2 : nIn2_a	
C00831/43	L Compare 3 : nIn1_a	
C00831/44	L Compare 3 : nIn2_a	
C00831/45	L AnalogSwitch 2 : nIn1_a	
C00831/46	L AnalogSwitch 2 : nIn2_a	
C00831/47	L AnalogSwitch 3 : nIn1_a	
C00831/48	L AnalogSwitch 3 : nIn2_a	
C00831/49	L Arithmetik 2 : nIn1_a	
C00831/50	L Arithmetik 2 : nIn2_a	
C00831/51	Reserved	
C00831/52	Reserved	
C00831/53	L GainOffset 2 : nIn_a	
C00831/54	L GainOffset 2 : nGain_a	
C00831/55	L GainOffset 2 : nOffset_a	
C00831/56	L OffsetGainP 1 : nIn_a	
C00831/57	L OffsetGainP 2 : nIn_a	

Parameter Name: C00831 16-bit inputs		Data type: UNSIGNED_16 Index: 23744 _d = 5C0 _h
C00831/58	L_OffsetGain_2 : nIn_a	
C00831/59	L_OffsetGain_2 : nOffset_a	
C00831/60	L_OffsetGain_2 : nGain_a	
C00831/61	L_PCTRL_1 : nAct_a	
C00831/62	L_PCTRL_1 : nAdapt_a	
C00831/63	L_PCTRL_1 : nSet_a	
C00831/64	L_PCTRL_1 : nInfluence_a	
C00831/65	MCK: nSpeedCtrl_a	
C00831/66	MCK: nPWMAngleOffset_a	
C00831/67	Reserved	
C00831/68	MCK: nMBrakeAddValue_a	
C00831/69	MCK: nTorqueSetValue_a	
C00831/70	MCK: nTorqueLimitAdapt_a	
C00831/71	MCK: nSRampOverride_a	
C00831/72	MCK: nSpeedSetValue_a	
C00831/73	MCK: wMotionCtrl2	
C00831/74	MCK: wMotionCtrl1	
C00831/75	MCK: nSpeedOverride_a	
C00831/76	MCK: nAccOverride_a	
C00831/77	MCK: nSpeedAdd_v	
C00831/78	MCK: wAuxCtrl	
C00831/79	MCK: wSMCtrl	
C00831/80	L_OffsetGainP_3 : nIn_a	
C00831/81	L_MPOT_1 : nIn_a	
C00831/82	L_MulDiv_1 : nIn_a	
C00831/83	LS_DataAccess: wIn1 (Lenze-internal)	
C00831/84	LS_DataAccess: wIn2 (Lenze-internal)	
C00831/85	LS_DataAccess: wIn3 (Lenze-internal)	
C00831/86	LS_DataAccess: wIn4 (Lenze-internal)	
C00831/87	L_PT1_1 : nIn_a	
C00831/88	MCTRL : nSpeedHighLimit_a	
C00831/89	L_PCTRL_1 : nNSet_a	
C00831/90	L_PCTRL_1 : nISet_a	
C00831/91	L_Interpolator_1 : nPhdIn_v	
C00831/92	L_Interpolator_1 : nNIn	
C00831/93	Reserved	
C00831/94	Reserved	
C00831/95	Reserved	
C00831/96	MCTRL : nInertiaAdapt_a	
C00831/97	MCTRL : nSpeedSetValueInertia_a	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C00832

Parameter Name: C00832 16-bit inputs [rpm]			Data type: INTEGER_16 Index: 23743 _d = 5CBF _h
Display of 16-bit input values of different blocks in [rpm]			
Display range (min. value unit max. value)			
-32767	rpm	32767	
Subcodes		Info	
C00832/1		L Absolut 1 : nIn_a	
C00832/2		L AddSub 1 : nIn1_a	
C00832/3		L AddSub 1 : nIn2_a	
C00832/4		L AddSub 1 : nIn3_a	
C00832/5		L OffsetGain 1 : nIn_a	
C00832/6		L OffsetGain 1 : nOffset_a	
C00832/7		L OffsetGain 1 : nGain_a	
C00832/8		L Negation 1 : nIn_a	
C00832/9		L GainOffset 1 : nIn_a	
C00832/10		L GainOffset 1 : nGain_a	
C00832/11		L GainOffset 1 : nOffset_a	
C00832/12		L Arithmetik 1 : nIn1_a	
C00832/13		L Arithmetik 1 : nIn2_a	
C00832/14		L AnalogSwitch 1 : nIn1_a	
C00832/15		L AnalogSwitch 1 : nIn2_a	
C00832/16		L Compare 1 : nIn1_a	
C00832/17		L Compare 1 : nIn2_a	
C00832/18		MCTRL : nTorqueLimitAdapt_a	
C00832/19		Reserved	
C00832/20		MCTRL : nPosCtrlPAdapt_a	
C00832/21		MCTRL : nPosCtrlOutLimit_a	
C00832/22		MCTRL : nSpeedSetValue_a	
C00832/23		MCTRL : nSpeedLowLimit_a	
C00832/24		MCTRL : nSpeedCtrlI_a	
C00832/25		MCTRL : nSpeedCtrlPAdapt_a	
C00832/26		MCTRL : nBoost_a	
C00832/27		MCTRL : nTorqueSetValue_a	
C00832/28		MCTRL : nTorqueGenLimit_a	
C00832/29		MCTRL : nTorqueMotLimit_a	
C00832/30		Reserved	
C00832/31		MCTRL : nVoltageAdd_a	
C00832/32		MCTRL : nPWMAngleOffset_a	
C00832/33		L NSet 1 : nCInhVal_a	
C00832/34		L NSet 1 : nNSet_a	
C00832/35		L NSet 1 : nSet_a	
C00832/36		L NSet 1 : nNAdd_a	
C00832/37		DCTRL : wCANControl	
C00832/38		DCTRL : wCCMControl	

Parameter Name: C00832 16-bit inputs [rpm]		Data type: INTEGER_16 Index: 23743 _d = 5CBF _h
C00832/39	L NLim 1 : nIn_a	
C00832/40	Reserved	
C00832/41	L Compare 2 : nIn1_a	
C00832/42	L Compare 2 : nIn2_a	
C00832/43	L Compare 3 : nIn1_a	
C00832/44	L Compare 3 : nIn2_a	
C00832/45	L AnalogSwitch 2 : nIn1_a	
C00832/46	L AnalogSwitch 2 : nIn2_a	
C00832/47	L AnalogSwitch 3 : nIn1_a	
C00832/48	L AnalogSwitch 3 : nIn2_a	
C00832/49	L Arithmetik 2 : nIn1_a	
C00832/50	L Arithmetik 2 : nIn2_a	
C00832/51	Reserved	
C00832/52	Reserved	
C00832/53	L GainOffset 2 : nIn_a	
C00832/54	L GainOffset 2 : nGain_a	
C00832/55	L GainOffset 2 : nOffset_a	
C00832/56	L OffsetGainP 1 : nIn_a	
C00832/57	L OffsetGainP 2 : nIn_a	
C00832/58	L OffsetGain 2 : nIn_a	
C00832/59	L OffsetGain 2 : nOffset_a	
C00832/60	L OffsetGain 2 : nGain_a	
C00832/61	L PCTRL 1 : nAct_a	
C00832/62	L PCTRL 1 : nAdapt_a	
C00832/63	L PCTRL 1 : nSet_a	
C00832/64	L PCTRL 1 : nInfluence_a	
C00832/65	MCK: nSpeedCtrlI_a	
C00832/66	MCK: nPWMAngleOffset_a	
C00832/67	Reserved	
C00832/68	MCK: nMBrakeAddValue_a	
C00832/69	MCK: nTorqueSetValue_a	
C00832/70	MCK: nTorqueLimitAdapt_a	
C00832/71	MCK: nSRampOverride_a	
C00832/72	MCK: nSpeedSetValue_a	
C00832/73	MCK: wMotionCtrl2	
C00832/74	MCK: wMotionCtrl1	
C00832/75	MCK: nSpeedOverride_a	
C00832/76	MCK: nAccOverride_a	
C00832/77	MCK: nSpeedAdd_v	
C00832/78	MCK: wAuxCtrl	
C00832/79	MCK: wSMCtrl	
C00832/80	L OffsetGainP 3 : nIn_a	
C00832/81	L MPot 1 : nIn_a	
C00832/82	L MulDiv 1 : nIn_a	

Parameter Name: C00832 16-bit inputs [rpm]		Data type: INTEGER_16 Index: 23743 _d = 5CBF _h
C00832/83	LS_DataAccess: wIn1 (Lenze-internal)	
C00832/84	LS_DataAccess: wIn2 (Lenze-internal)	
C00832/85	LS_DataAccess: wIn3 (Lenze-internal)	
C00832/86	LS_DataAccess: wIn4 (Lenze-internal)	
C00832/87	L_PT1_1 : nIn_a	
C00832/88	MCTRL : nSpeedHighLimit_a	
C00832/89	L_PCTRL_1 : nNSet_a	
C00832/90	L_PCTRL_1 : nISet_a	
C00832/91	L_Interpolator_1 : nPhdIn_v	
C00832/92	L_Interpolator_1 : nNIn_a	
C00832/93	Reserved	
C00832/94	Reserved	
C00832/95	Reserved	
C00832/96	MCTRL : nInertiaAdapt_a	
C00832/97	MCTRL : nSpeedSetValueInertia_a	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00833

Parameter Name: C00833 Binary inputs		Data type: UNSIGNED_8 Index: 23742 _d = 5CBE _h
Display of the signal status of the binary inputs of different blocks		
Selection list		
0	False	
1	True	
Subcodes	Info	
C00833/1	L_And_1 : bIn1	
C00833/2	L_And_1 : bIn2	
C00833/3	L_And_1 : bIn3	
C00833/4	L_DFlipFlop_1 : bD	
C00833/5	L_DFlipFlop_1 : bClk	
C00833/6	L_DFlipFlop_1 : bClr	
C00833/7	L_Not_1 : bIn	
C00833/8	L_Or_1 : bIn1	
C00833/9	L_Or_1 : bIn2	
C00833/10	L_Or_1 : bIn3	
C00833/11	L_RLO_1 : bCw	
C00833/12	L_RLO_1 : bCcw	
C00833/13	L_AnalogSwitch_1 : bSet	
C00833/14	L_NSet_1 : bRfgStop	
C00833/15	L_NSet_1 : bRfg0	
C00833/16	L_NSet_1 : bNSetInv	

Parameter Name: C00833 Binary inputs		Data type: UNSIGNED 8 Index: 23742 _d = 5CBE _h
C00833/17	L NSet 1 : bLog1	
C00833/18	L NSet 1 : bLog2	
C00833/19	L NSet 1 : bLog4	
C00833/20	L NSet 1 : bLog8	
C00833/21	L NSet 1 : bTi1	
C00833/22	L NSet 1 : bTi2	
C00833/23	L NSet 1 : bTi4	
C00833/24	L NSet 1 : bTi8	
C00833/25	L NSet 1 : bLoad	
C00833/26	L NSet 1 : bExternalCINH	
C00833/27	MCTRL : bPosCtrlOn	
C00833/28	MCTRL : bSpeedInterpolatorOn	
C00833/29	MCTRL : bTorqueInterpolatorOn	
C00833/30	MCTRL : bTorquemodeOn	
C00833/31	MCTRL : bSpeedCtrlOn	
C00833/32	MCTRL : bAutoBoostOn	
C00833/33	MCTRL : bQSPOn	
C00833/34	MCTRL : bDcBrakeOn	
C00833/35	MCTRL : bDeltaPosOn	
C00833/36	DCTRL : bCINH	
C00833/37	DCTRL : bFailReset	
C00833/38	DCTRL : bStatus_B0	
C00833/39	DCTRL : bStatus_B2	
C00833/40	DCTRL : bStatus_B3	
C00833/41	DCTRL : bStatus_B4	
C00833/42	DCTRL : bStatus_B5	
C00833/43	DCTRL : bStatus_B14	
C00833/44	DCTRL : bStatus_B15	
C00833/45	DCTRL : bFree_1	
C00833/46	DCTRL : bFree_2	
C00833/47	DCTRL : bFree_3	
C00833/48	DCTRL : bFree_4	
C00833/49	L And 2 : bIn1	
C00833/50	L And 2 : bIn2	
C00833/51	L And 2 : bIn3	
C00833/52	L And 3 : bIn1	
C00833/53	L And 3 : bIn2	
C00833/54	L And 3 : bIn3	
C00833/55	L Or 2 : bIn1	
C00833/56	L Or 2 : bIn2	
C00833/57	L Or 2 : bIn3	
C00833/58	L Or 3 : bIn1	
C00833/59	L Or 3 : bIn2	
C00833/60	L Or 3 : bIn3	

Parameter Name: C00833 Binary inputs		Data type: UNSIGNED 8 Index: 23742 _d = 5CBE _h
C00833/61	L Not 2 : bIn	
C00833/62	L Not 3 : bIn	
C00833/63	L DigitalLogic 1 : bIn1	
C00833/64	L DigitalLogic 1 : bIn2	
C00833/65	L DigitalLogic 1 : bIn3	
C00833/66	L DigitalDelay 1 : bIn	
C00833/67	MCTRL : bPosDerivativeOn	
C00833/68	MCTRL : bMotorRefOffsetOn	
C00833/69	MCTRL : bSpeedCtrlPAadaptOn	
C00833/70	L AnalogSwitch 2 : bSet	
C00833/71	L AnalogSwitch 3 : bSet	
C00833/72	L MPot 1 : bUp	
C00833/73	L MPot 1 : bInAct	
C00833/74	L MPot 1 : bDown	
C00833/75	L PCTRL 1 : bPIDOff	
C00833/76	L PCTRL 1 : bInAct	
C00833/77	L PCTRL 1 : bIOff	
C00833/78	MCK: bSpeedCtrlOn	
C00833/79	MCK: bDcBrakeOn	
C00833/80	MCK: bMBrakeRelease	
C00833/81	MCK: bMBrakeStartValue2	
C00833/82	MCK: bMBrakeApplied	
C00833/83	MCK: bLimitSwitchPos	
C00833/84	MCK: bLimitSwitchNeg	
C00833/85	MCK: bPosCtrlOn	
C00833/86	MCK: bDeltaPosOn	
C00833/87	MCK: bPosDerivativeOn	
C00833/88	MCK: bMotorRefOffsetOn	
C00833/89	MCK: bQspOn	
C00833/90	MCK: bTorquemodeOn	
C00833/91	MCK: bTorqueLimitAdaptOn	
C00833/92	MCK: bHomMark	
C00833/93	L Transient 1 : bIn	
C00833/94	L Transient 2 : bIn	
C00833/95	L Transient 3 : bIn	
C00833/96	L Transient 4 : bIn	
C00833/97	Reserved	
C00833/98	MCTRL : bTorqueLimitAdaptOn	
C00833/99	L NSet 1 : bNAddInv	
C00833/100	L MPot 1 : bEnable	
C00833/101	L NLim 1 : bEnable	
C00833/102	LS_DataAccess: bEnableIn1 (Lenze-internal)	

Parameter Name: C00833 Binary inputs		Data type: UNSIGNED 8 Index: 23742 _d = 5CBE _h
C00833/103	LS_DataAccess: bEnableIn2 (Lenze-internal)	
C00833/104	LS_DataAccess: bEnableIn3 (Lenze-internal)	
C00833/105	LS_DataAccess: bEnableIn4 (Lenze-internal)	
C00833/106	L_PCTRL 1 : bEnableInfluenceRamp	
C00833/107	LS_SetError 2 : bSetError1	
C00833/108	LS_SetError 2 : bSetError2	
C00833/109	LS_SetError 2 : bSetError3	
C00833/110	LS_SetError 2 : bSetError4	
C00833/111	L_JogCtrlExtension 1 : bInputSel1	
C00833/112	L_JogCtrlExtension 1 : bInputSel2	
C00833/113	L_JogCtrlExtension 1 : bRfgIn	
C00833/114	L_JogCtrlExtension 1 : bJog1In	
C00833/115	L_JogCtrlExtension 1 : bJog2In	
C00833/116	L_JogCtrlExtension 1 : bSlowDown1	
C00833/117	L_JogCtrlExtension 1 : bStop1	
C00833/118	L_JogCtrlExtension 1 : bSlowDown2	
C00833/119	L_JogCtrlExtension 1 : bStop2	
C00833/120	L_JogCtrlExtension 1 : bSlowDown3	
C00833/121	L_JogCtrlExtension 1 : bStop3	
C00833/122	L_PCTRL 1 : bISet	
C00833/123	L_Interpolator 1 : bSpeedAct0	
C00833/124	L_Or 4 : bIn1	
C00833/125	L_Or 4 : bIn2	
C00833/126	L_Or 4 : bIn3	
C00833/127	L_DigitalLogic 3 : bIn1	
C00833/128	L_DigitalLogic 3 : bIn2	
C00833/129	L_DigitalLogic 3 : bIn3	
C00833/130	MCTRL : bBrakeChopperOn	
C00833/131	MCTRL : bVfcEcoDisable	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00834

Parameter Name: C00834 32-bit inputs [incr]			Data type: INTEGER_32 Index: 23741 _d = 5CBD _h		
Display in [increments] of 32 bit input values of various blocks					
Display range (min. value unit max. value)					
-2147483647	Incr.	2147483647			
Subcodes			Info		
C00834/1			MCK: dnPosSetValue_p		
C00834/2			MCK: dnMotorRefOffset_p		
C00834/3			MCK: dnDeltaPos_p		
C00834/4			MCTRL : dnDeltaPos_p		
C00834/5			MCTRL : dnPosSetValue_p		
C00834/6			MCTRL : dnMotorRefOffset_p		
C00834/7			MCK: dnProfilePosition_p		
C00834/8			L Interpolator 1 : dnPhiIn_p		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00835

Parameter Name: C00835 16-bit inputs [%] (Set2)			Data type: INTEGER_16 Index: 23740 _d = 5CBC _h		
Display in percent of 16-bit input values of different blocks					
Display range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes			Info		
C00835/1			L Absolut 2 : nIn_a		
C00835/2			L AnalogSwitch 4 : nIn1_a		
C00835/3			L AnalogSwitch 4 : nIn2_a		
C00835/4			L AnalogSwitch 5 : nIn1_a		
C00835/5			L AnalogSwitch 5 : nIn2_a		
C00835/6			L Compare 4 : nIn1_a		
C00835/7			L Compare 4 : nIn2_a		
C00835/8			L Compare 5 : nIn1_a		
C00835/9			L Compare 5 : nIn2_a		
C00835/10			L Arithmetik 3 : nIn1_a		
C00835/11			L Arithmetik 3 : nIn2_a		
C00835/12			L Arithmetik 4 : nIn1_a		
C00835/13			L Arithmetik 4 : nIn2_a		
C00835/14			L Arithmetik 5 : nIn1_a		
C00835/15			L Arithmetik 5 : nIn2_a		
C00835/16			L Counter 2 : wLdVal		
C00835/17			L Counter 2 : wCmpVal		
C00835/18			L Counter 3 : wLdVal		
C00835/19			L Counter 3 : wCmpVal		
C00835/20			L PhaseIntK 1 : nIn_v		
C00835/21			L Negation 2 : nIn_a		
C00835/22			L NLim 2 : nIn_a		

Parameter Name: C00835 16-bit inputs [%] (Set2)		Data type: INTEGER_16 Index: 23740 _d = 5CBC _h
C00835/23	L_OffsetGain_3 : nIn_a	
C00835/24	L_OffsetGain_3 : nOffset_a	
C00835/25	L_OffsetGain_3 : nGain_a	
C00835/26	L_PT1_2 : nIn_a	
C00835/27	L_PT1_3 : nIn_a	
C00835/28	L_PhaseIntK_2 : nIn_v	
C00835/29	L_SampleHold_1 : nIn_a	
C00835/30	L_SampleHold_2 : nIn_a	
C00835/31	L_Mux_1 : wInSelect	
C00835/32	L_GainOffset_3 : nIn_a	
C00835/33	L_GainOffset_3 : nGain_a	
C00835/34	L_GainOffset_3 : nOffset_a	
C00835/35	L_MulDiv_2 : nIn_a	
C00835/36	L_DT1_1 : nIn_a	
C00835/37	L_Counter_1 : wLdVal	
C00835/38	L_Counter_1 : wCmpVal	
C00835/39	L_GainOffsetP_1 : nIn_a	
C00835/40	L_GainOffsetP_2 : nIn_a	
C00835/41	L_GainOffsetP_3 : nIn_a	
C00835/42	L_Limit_1 : nIn_a	
C00835/43	L_Limit_2 : nIn_a	
C00835/44	L_MckCtrlInterface_1 : wOperationMode	
C00835/45	L_MckCtrlInterface_1 : wPosMode	
C00835/46	L_MckCtrlInterface_1 : wProfileNo	
C00835/47	L_MckCtrlInterface_1 : wInMckPosCtrl_1	
C00835/48	L_MckCtrlInterface_1 : wInMckPosCtrl_2	
C00835/49	L_MckStateInterface_1 : wInMckPosState_1	
C00835/50	L_MckStateInterface_1 : wInMckPosState_2	
C00835/51	L_PosShaftCtrlInterface_1 : wInPosiShaftCtrl_1	
C00835/52	L_PosShaftCtrlInterface_1 : wInPosiShaftCtrl_2	
C00835/53	L_PosShaftCtrlInterface_1 : wInPosiShaftCtrl_3	
C00835/54	L_PosShaftCtrlInterface_1 : wInPosiShaftCtrl_4	
C00835/55	L_ConvWordToBits_1 : wInInput	
C00835/56	L_ConvWordToBits_2 : wInInput	
C00835/57	L_ConvWordToBits_3 : wInInput	
C00835/58	L_ConvWordsToDInt_1 : wInLWord	
C00835/59	L_ConvWordsToDInt_1 : wInHWord	
C00835/60	L_ConvWordsToDInt_2 : wInLWord	
C00835/61	L_ConvWordsToDInt_2 : wInHWord	
C00835/62	L_ConvWordsToDInt_3 : wInLWord	
C00835/63	L_ConvWordsToDInt_3 : wInHWord	
C00835/64	L_ConvUnitsToIncr_1 : wInLWord	
C00835/65	L_ConvUnitsToIncr_1 : wInHWord	
C00835/66	L_ConvUnitsToIncr_2 : wInLWord	

Parameter Name: C00835 16-bit inputs [%] (Set2)		Data type: INTEGER_16 Index: 23740 _d = 5CBC _h
C00835/67	L_ConvUnitsToIncr_2 : wInHWord	
C00835/68	L_ConvUnitsToIncr_3 : wInLWord	
C00835/69	L_ConvUnitsToIncr_3 : wInHWord	
C00835/70	L_Curve_1 : nIn_a	
C00835/71	L_ConvW_1 : wIn	
C00835/72	L_ConvW_2 : wIn	
C00835/73	L_ConvW_3 : wIn	
C00835/74	L_ConvW_4 : wIn	
C00835/75	L_MckCtrlInterface_1 : wPosSetHW	
C00835/76	L_MckCtrlInterface_1 : wPosSetLW	
C00835/77	L_PhaseDiff_1 : nIn_v	
C00835/78	L_PhaseDiff_2 : nIn_v	
C00835/79	L_SRFG_1 : nIn_a	
C00835/80	L_SRFG_2 : nIn_a	
C00835/81	L_SRFG_1 : nSet_a	
C00835/82	L_SRFG_2 : nSet_a	
C00835/83	L_SignalSwitch_1 : wIn1	
C00835/84	L_SignalSwitch_2 : wIn1	
C00835/85	L_SignalSwitch_3 : wIn1	
C00835/86	L_SignalSwitch_4 : wIn1	
C00835/87	L_SignalSwitch_1 : wIn2	
C00835/88	L_SignalSwitch_2 : wIn2	
C00835/89	L_SignalSwitch_3 : wIn2	
C00835/90	L_SignalSwitch_4 : wIn2	
C00835/91	L_Odometer_1 : nInSpeed_v	
C00835/92	L_CalcDiameter_1 : wDMax	
C00835/93	L_CalcDiameter_1 : wDMin	
C00835/94	L_CalcDiameter_1 : wVMax	
C00835/95	L_CalcDiameter_1 : nVLine_a	
C00835/96	L_CalcDiameter_1 : nMotorSpeedAct_v	
C00835/97	L_CalcDiameter_1 : wGearNum	
C00835/98	L_CalcDiameter_1 : wGearDenom	
C00835/99	L_CalcDiameter_1 : nSetD_a	
C00835/100	L_ProcessCtrl_1 : nVpAdapt_a	
C00835/101	L_ProcessCtrl_1 : nSet_a	
C00835/102	L_ProcessCtrl_1 : nAct_a	
C00835/103	L_ProcessCtrl_1 : nRTimeAdapt_a	
C00835/104	L_ProcessCtrl_1 : nInfluence_a	
C00835/105	L_PhiIntegrator_1 : nIn_v	
C00835/106	L_PhiIntegrator_1 : wGearNum	
C00835/107	L_PhiIntegrator_1 : wGearDenom	
C00835/108	L_SwitchPoint_1 : nActSpeed_v	
C00835/109	L_PhiIntegrator_1 : nSpeedAdd_v	
C00835/110	L_DFSET_1 : nSpeedTrim_v	

Parameter Name: C00835 16-bit inputs [%] (Set2)		Data type: INTEGER_16 Index: 23740 _d = 5CBC _h
C00835/111	L_DFSET_1 : nSpeedTrim_a	
C00835/112	L_DFSET_1 : wGearNum	
C00835/113	L_DFSET_1 : wGainNum	
C00835/114	L_DFSET_1 : nSet_v	
C00835/115	L_DFSET_1 : wGainDenom	
C00835/116	L_DFSET_1 : wGearDenom	
C00835/117	L_DFSET_1 : nPositionTrimming	
C00835/118	L_DFSET_1 : nNAct_v	
C00835/119	L_DFRFG_1 : nIn_v	
C00835/120	L_GearComp_1 : nTorque_a	
C00835/121	L_ConvAP_1 : nIn_a	
C00835/122	L_ConvAP_2 : nIn_a	
C00835/123	L_ConvAP_3 : nIn_a	
C00835/124	L_ConvX_1 : nIn_a	
C00835/125	L_ConvX_1 : nNum	
C00835/126	L_ConvX_1 : wDenom	
C00835/127	L_ConvX_2 : nIn_a	
C00835/128	L_ConvX_2 : nNum	
C00835/129	L_ConvX_2 : wDenom	
C00835/130	L_ConvX_3 : nIn_a	
C00835/131	L_ConvX_3 : nNum	
C00835/132	L_ConvX_3 : wDenom	
C00835/133	L_ConvPP_1 : nNum	
C00835/134	L_ConvPP_1 : wDenom	
C00835/135	L_ConvPP_2 : nNum	
C00835/136	L_ConvPP_2 : wDenom	
C00835/137	L_ConvPP_3 : nNum	
C00835/138	L_ConvPP_3 : wDenom	
C00835/139	L_Curve_2 : nIn_a	
C00835/140	L_Curve_3 : nIn_a	
C00835/141	L_Sequencer_1 : wStartStep	
C00835/142	L_Sequencer_1 : wBranch1	
C00835/143	L_Sequencer_1 : wBranch2	
C00835/144	L_Sequencer_1 : wMotionState1	
C00835/145	L_Sequencer_1 : wMotionState2	
C00835/146	L_Sequencer_1 : wDigitalInputs	
C00835/147	L_ConvActPos_1 : nSetPos_a	
C00835/148	L_ConvActPos_1 : nPosIn_a	
C00835/149	L_ConvActPos_1 : wVMax	
C00835/150	L_ConvActPos_1 : nVLine_a	
C00835/151	L_MFail_1 : nAdapt_a	
C00835/152	L_MFail_1 : nConst_a	
C00835/153	L_MFail_1 : nDCSet_a	
C00835/154	L_MFail_1 : nNSet_a	

Parameter Name: C00835 16-bit inputs [%] (Set2)		Data type: INTEGER_16 Index: 23740 _d = 5CBB _h
C00835/155	L_MFail_1 : nThreshold_a	
C00835/156	L_MFail_1 : nNAct_a	
C00835/157	L_MFail_1 : nSet_a	
C00835/158	L_MFail_1 : nDCVoltAct_a	
C00835/159	L_Curve_3 : nCurveCtrl_a	
C00835/160	L_Curve_3 : nD0_a	
C00835/161	L_Curve_3 : nDiameter_a	
C00835/162	L_SwitchPointPar_1 : nActSpeed_v	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100		

C00836

Parameter Name: C00836 16-bit inputs (Set2)		Data type: UNSIGNED_16 Index: 23739 _d = 5CBB _h
Decimal/hexadecimal/bit coded display of 16 bit input values of various blocks		
Display area (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		
Bit 0	Active	
...	...	
Bit 15	Active	
Subcodes	Info	
C00836/1	L_Absolut_2 : nIn_a	
C00836/2	L_AnalogSwitch_4 : nIn1_a	
C00836/3	L_AnalogSwitch_4 : nIn2_a	
C00836/4	L_AnalogSwitch_5 : nIn1_a	
C00836/5	L_AnalogSwitch_5 : nIn2_a	
C00836/6	L_Compare_4 : nIn1_a	
C00836/7	L_Compare_4 : nIn2_a	
C00836/8	L_Compare_5 : nIn1_a	
C00836/9	L_Compare_5 : nIn2_a	
C00836/10	L_Arithmetik_3 : nIn1_a	
C00836/11	L_Arithmetik_3 : nIn2_a	
C00836/12	L_Arithmetik_4 : nIn1_a	
C00836/13	L_Arithmetik_4 : nIn2_a	
C00836/14	L_Arithmetik_5 : nIn1_a	
C00836/15	L_Arithmetik_5 : nIn2_a	
C00836/16	L_Counter_2 : wLdVal	
C00836/17	L_Counter_2 : wCmpVal	
C00836/18	L_Counter_3 : wLdVal	
C00836/19	L_Counter_3 : wCmpVal	
C00836/20	L_PhaseIntK_1 : nIn_v	
C00836/21	L_Negation_2 : nIn_a	
C00836/22	L_NLim_2 : nIn_a	
C00836/23	L_OffsetGain_3 : nIn_a	

Parameter Name: C00836 16-bit inputs (Set2)		Data type: UNSIGNED_16 Index: 23739 _d = 5CBB _h
C00836/24	L_OffsetGain_3 : nOffset_a	
C00836/25	L_OffsetGain_3 : nGain_a	
C00836/26	L_PT1_2 : nIn_a	
C00836/27	L_PT1_3 : nIn_a	
C00836/28	L_PhaseIntK_2 : nIn_v	
C00836/29	L_SampleHold_1 : nIn_a	
C00836/30	L_SampleHold_2 : nIn_a	
C00836/31	L_Mux_1 : wInSelect	
C00836/32	L_GainOffset_3 : nIn_a	
C00836/33	L_GainOffset_3 : nGain_a	
C00836/34	L_GainOffset_3 : nOffset_a	
C00836/35	L_MulDiv_2 : nIn_a	
C00836/36	L_DT1_1 : nIn_a	
C00836/37	L_Counter_1 : wLdVal	
C00836/38	L_Counter_1 : wCmpVal	
C00836/39	L_GainOffsetP_1 : nIn_a	
C00836/40	L_GainOffsetP_2 : nIn_a	
C00836/41	L_GainOffsetP_3 : nIn_a	
C00836/42	L_Limit_1 : nIn_a	
C00836/43	L_Limit_2 : nIn_a	
C00836/44	L_MckCtrlInterface_1 : wOperationMode	
C00836/45	L_MckCtrlInterface_1 : wPosMode	
C00836/46	L_MckCtrlInterface_1 : wProfileNo	
C00836/47	L_MckCtrlInterface_1 : wInMckPosCtrl_1	
C00836/48	L_MckCtrlInterface_1 : wInMckPosCtrl_2	
C00836/49	L_MckStateInterface_1 : wInMckPosState_1	
C00836/50	L_MckStateInterface_1 : wInMckPosState_2	
C00836/51	L_PosShaftCtrlInterface_1 : wInPosiShaftCtrl_1	
C00836/52	L_PosShaftCtrlInterface_1 : wInPosiShaftCtrl_2	
C00836/53	L_PosShaftCtrlInterface_1 : wInPosiShaftCtrl_3	
C00836/54	L_PosShaftCtrlInterface_1 : wInPosiShaftCtrl_4	
C00836/55	L_ConvWordToBits_1 : wInput	
C00836/56	L_ConvWordToBits_2 : wInput	
C00836/57	L_ConvWordToBits_3 : wInput	
C00836/58	L_ConvWordsToDInt_1 : wInLWord	
C00836/59	L_ConvWordsToDInt_1 : wInHWord	
C00836/60	L_ConvWordsToDInt_2 : wInLWord	
C00836/61	L_ConvWordsToDInt_2 : wInHWord	
C00836/62	L_ConvWordsToDInt_3 : wInLWord	
C00836/63	L_ConvWordsToDInt_3 : wInHWord	
C00836/64	L_ConvUnitsToIncr_1 : wInLWord	
C00836/65	L_ConvUnitsToIncr_1 : wInHWord	
C00836/66	L_ConvUnitsToIncr_2 : wInLWord	
C00836/67	L_ConvUnitsToIncr_2 : wInHWord	

Parameter Name: C00836 16-bit inputs (Set2)		Data type: UNSIGNED_16 Index: 23739 _d = 5CBB _h
C00836/68	L_ConvUnitsToIncr_3 : wInLWord	
C00836/69	L_ConvUnitsToIncr_3 : wInHWord	
C00836/70	L_Curve_1 : nIn_a	
C00836/71	L_ConvW_1 : wIn	
C00836/72	L_ConvW_2 : wIn	
C00836/73	L_ConvW_3 : wIn	
C00836/74	L_ConvW_4 : wIn	
C00836/75	L_MckCtrlInterface_1 : wPosSetHW	
C00836/76	L_MckCtrlInterface_1 : wPosSetLW	
C00836/77	L_PhaseDiff_1 : nIn_v	
C00836/78	L_PhaseDiff_2 : nIn_v	
C00836/79	L_SRFG_1 : nIn_a	
C00836/80	L_SRFG_2 : nIn_a	
C00836/81	L_SRFG_1 : nSet_a	
C00836/82	L_SRFG_2 : nSet_a	
C00836/83	L_SignalSwitch_1 : wIn1	
C00836/84	L_SignalSwitch_2 : wIn1	
C00836/85	L_SignalSwitch_3 : wIn1	
C00836/86	L_SignalSwitch_4 : wIn1	
C00836/87	L_SignalSwitch_1 : wIn2	
C00836/88	L_SignalSwitch_2 : wIn2	
C00836/89	L_SignalSwitch_3 : wIn2	
C00836/90	L_SignalSwitch_4 : wIn2	
C00836/91	L_Odometer_1 : nInSpeed_v	
C00836/92	L_CalcDiameter_1 : wDMax	
C00836/93	L_CalcDiameter_1 : wDMin	
C00836/94	L_CalcDiameter_1 : wVMax	
C00836/95	L_CalcDiameter_1 : nVLine_a	
C00836/96	L_CalcDiameter_1 : nMotorSpeedAct_v	
C00836/97	L_CalcDiameter_1 : wGearNum	
C00836/98	L_CalcDiameter_1 : wGearDenom	
C00836/99	L_CalcDiameter_1 : nSetD_a	
C00836/100	L_ProcessCtrl_1 : nVpAdapt_a	
C00836/101	L_ProcessCtrl_1 : nSet_a	
C00836/102	L_ProcessCtrl_1 : nAct_a	
C00836/103	L_ProcessCtrl_1 : nRTIMEAdapt_a	
C00836/104	L_ProcessCtrl_1 : nInfluence_a	
C00836/105	L_PhiIntegrator_1 : nIn_v	
C00836/106	L_PhiIntegrator_1 : wGearNum	
C00836/107	L_PhiIntegrator_1 : wGearDenom	
C00836/108	L_SwitchPoint_1 : nActSpeed_v	
C00836/109	L_PhiIntegrator_1 : nSpeedAdd_v	
C00836/110	L_DFSET_1 : nSpeedTrim_v	
C00836/111	L_DFSET_1 : nSpeedTrim_a	

Parameter Name: C00836 16-bit inputs (Set2)		Data type: UNSIGNED_16 Index: 23739 _d = 5CBB _h
C00836/112	L_DFSET_1 : wGearNum	
C00836/113	L_DFSET_1 : wGainNum	
C00836/114	L_DFSET_1 : nSet_v	
C00836/115	L_DFSET_1 : wGainDenom	
C00836/116	L_DFSET_1 : wGearDenom	
C00836/117	L_DFSET_1 : nPositionTrimming	
C00836/118	L_DFSET_1 : nNAct_v	
C00836/119	L_DFRFG_1 : nIn_v	
C00836/120	L_GearComp_1 : nTorque_a	
C00836/121	L_ConvAP_1 : nIn_a	
C00836/122	L_ConvAP_2 : nIn_a	
C00836/123	L_ConvAP_3 : nIn_a	
C00836/124	L_ConvX_1 : nIn_a	
C00836/125	L_ConvX_1 : nNum	
C00836/126	L_ConvX_1 : wDenom	
C00836/127	L_ConvX_2 : nIn_a	
C00836/128	L_ConvX_2 : nNum	
C00836/129	L_ConvX_2 : wDenom	
C00836/130	L_ConvX_3 : nIn_a	
C00836/131	L_ConvX_3 : nNum	
C00836/132	L_ConvX_3 : wDenom	
C00836/133	L_ConvPP_1 : nNum	
C00836/134	L_ConvPP_1 : wDenom	
C00836/135	L_ConvPP_2 : nNum	
C00836/136	L_ConvPP_2 : wDenom	
C00836/137	L_ConvPP_3 : nNum	
C00836/138	L_ConvPP_3 : wDenom	
C00836/139	L_Curve_2 : nIn_a	
C00836/140	L_Curve_3 : nIn_a	
C00836/141	L_Sequencer_1 : wStartStep	
C00836/142	L_Sequencer_1 : wBranch1	
C00836/143	L_Sequencer_1 : wBranch2	
C00836/144	L_Sequencer_1 : wMotionState1	
C00836/145	L_Sequencer_1 : wMotionState2	
C00836/146	L_Sequencer_1 : wDigitalInputs	
C00836/147	L_ConvActPos_1 : nSetPos_a	
C00836/148	L_ConvActPos_1 : nPosIn_a	
C00836/149	L_ConvActPos_1 : wVMax	
C00836/150	L_ConvActPos_1 : nVLine_a	
C00836/151	L_MFail_1 : nAdapt_a	
C00836/152	L_MFail_1 : nConst_a	
C00836/153	L_MFail_1 : nDCSet_a	
C00836/154	L_MFail_1 : nNSet_a	
C00836/155	L_MFail_1 : nThreshold_a	

Parameter Name: C00836 16-bit inputs (Set2)		Data type: UNSIGNED_16 Index: 23739 _d = 5CBB _h
C00836/156	L MFail 1 : nNAct_a	
C00836/157	L MFail 1 : nSet_a	
C00836/158	L MFail 1 : nDCVoltAct_a	
C00836/159	L Curve 3 : nCurveCtrl_a	
C00836/160	L Curve 3 : nD0_a	
C00836/161	L Curve 3 : nDiameter_a	
C00836/162	L SwitchPointPar 1 : nActSpeed_v	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C00837

Parameter Name: C00837 16-bit inputs [rpm] (Set2)			Data type: INTEGER_16 Index: 23738 _d = 5CBA _h
Display of 16-bit input values of different blocks in [rpm]			
Display range (min. value unit max. value)			
-32767	rpm	32767	
Subcodes			Info
C00837/1			L Absolut 2 : nIn_a
C00837/2			L AnalogSwitch 4 : nIn1_a
C00837/3			L AnalogSwitch 4 : nIn2_a
C00837/4			L AnalogSwitch 5 : nIn1_a
C00837/5			L AnalogSwitch 5 : nIn2_a
C00837/6			L Compare 4 : nIn1_a
C00837/7			L Compare 4 : nIn2_a
C00837/8			L Compare 5 : nIn1_a
C00837/9			L Compare 5 : nIn2_a
C00837/10			L Arithmetik 3 : nIn1_a
C00837/11			L Arithmetik 3 : nIn2_a
C00837/12			L Arithmetik 4 : nIn1_a
C00837/13			L Arithmetik 4 : nIn2_a
C00837/14			L Arithmetik 5 : nIn1_a
C00837/15			L Arithmetik 5 : nIn2_a
C00837/16			L Counter 2 : wLdVal
C00837/17			L Counter 2 : wCmpVal
C00837/18			L Counter 3 : wLdVal
C00837/19			L Counter 3 : wCmpVal
C00837/20			L PhaseIntK 1 : nIn_v
C00837/21			L Negation 2 : nIn_a
C00837/22			L NLim 2 : nIn_a
C00837/23			L OffsetGain 3 : nIn_a
C00837/24			L OffsetGain 3 : nOffset_a
C00837/25			L OffsetGain 3 : nGain_a
C00837/26			L PT1 2 : nIn_a
C00837/27			L PT1 3 : nIn_a
C00837/28			L PhaseIntK 2 : nIn_v

Parameter Name: C00837 16-bit inputs [rpm] (Set2)		Data type: INTEGER_16 Index: 23738 _d = 5CBA _h
C00837/29	L_SampleHold_1 : nIn_a	
C00837/30	L_SampleHold_2 : nIn_a	
C00837/31	L_Mux_1 : wInSelect	
C00837/32	L_GainOffset_3 : nIn_a	
C00837/33	L_GainOffset_3 : nGain_a	
C00837/34	L_GainOffset_3 : nOffset_a	
C00837/35	L_MulDiv_2 : nIn_a	
C00837/36	L_DT1_1 : nIn_a	
C00837/37	L_Counter_1 : wLdVal	
C00837/38	L_Counter_1 : wCmpVal	
C00837/39	L_GainOffsetP_1 : nIn_a	
C00837/40	L_GainOffsetP_2 : nIn_a	
C00837/41	L_GainOffsetP_3 : nIn_a	
C00837/42	L_Limit_1 : nIn_a	
C00837/43	L_Limit_2 : nIn_a	
C00837/44	L_MckCtrlInterface_1 : wOperationMode	
C00837/45	L_MckCtrlInterface_1 : wPosMode	
C00837/46	L_MckCtrlInterface_1 : wProfileNo	
C00837/47	L_MckCtrlInterface_1 : wInMckPosCtrl_1	
C00837/48	L_MckCtrlInterface_1 : wInMckPosCtrl_2	
C00837/49	L_MckStateInterface_1 : wInMckPosState_1	
C00837/50	L_MckStateInterface_1 : wInMckPosState_2	
C00837/51	L_PosShaftCtrlInterface_1 : wInPosiShaftCtrl_1	
C00837/52	L_PosShaftCtrlInterface_1 : wInPosiShaftCtrl_2	
C00837/53	L_PosShaftCtrlInterface_1 : wInPosiShaftCtrl_3	
C00837/54	L_PosShaftCtrlInterface_1 : wInPosiShaftCtrl_4	
C00837/55	L_ConvWordToBits_1 : wInput	
C00837/56	L_ConvWordToBits_2 : wInput	
C00837/57	L_ConvWordToBits_3 : wInput	
C00837/58	L_ConvWordsToDInt_1 : wInLWord	
C00837/59	L_ConvWordsToDInt_1 : wInHWord	
C00837/60	L_ConvWordsToDInt_2 : wInLWord	
C00837/61	L_ConvWordsToDInt_2 : wInHWord	
C00837/62	L_ConvWordsToDInt_3 : wInLWord	
C00837/63	L_ConvWordsToDInt_3 : wInHWord	
C00837/64	L_ConvUnitsToIncr_1 : wInLWord	
C00837/65	L_ConvUnitsToIncr_1 : wInHWord	
C00837/66	L_ConvUnitsToIncr_2 : wInLWord	
C00837/67	L_ConvUnitsToIncr_2 : wInHWord	
C00837/68	L_ConvUnitsToIncr_3 : wInLWord	
C00837/69	L_ConvUnitsToIncr_3 : wInHWord	
C00837/70	L_Curve_1 : nIn_a	
C00837/71	L_ConvW_1 : wIn	
C00837/72	L_ConvW_2 : wIn	

Parameter Name: C00837 16-bit inputs [rpm] (Set2)		Data type: INTEGER_16 Index: 23738 _d = 5CBA _h
C00837/73	L_ConvW_3 : wIn	
C00837/74	L_ConvW_4 : wIn	
C00837/75	L_MckCtrlInterface_1 : wPosSetHW	
C00837/76	L_MckCtrlInterface_1 : wPosSetLW	
C00837/77	L_PhaseDiff_1 : nIn_v	
C00837/78	L_PhaseDiff_2 : nIn_v	
C00837/79	L_SRFG_1 : nIn_a	
C00837/80	L_SRFG_2 : nIn_a	
C00837/81	L_SRFG_1 : nSet_a	
C00837/82	L_SRFG_2 : nSet_a	
C00837/83	L_SignalSwitch_1 : wIn1	
C00837/84	L_SignalSwitch_2 : wIn1	
C00837/85	L_SignalSwitch_3 : wIn1	
C00837/86	L_SignalSwitch_4 : wIn1	
C00837/87	L_SignalSwitch_1 : wIn2	
C00837/88	L_SignalSwitch_2 : wIn2	
C00837/89	L_SignalSwitch_3 : wIn2	
C00837/90	L_SignalSwitch_4 : wIn2	
C00837/91	L_Odometer_1 : nInSpeed_v	
C00837/92	L_CalcDiameter_1 : wDMax	
C00837/93	L_CalcDiameter_1 : wDMin	
C00837/94	L_CalcDiameter_1 : wVMax	
C00837/95	L_CalcDiameter_1 : nVLine_a	
C00837/96	L_CalcDiameter_1 : nMotorSpeedAct_v	
C00837/97	L_CalcDiameter_1 : wGearNum	
C00837/98	L_CalcDiameter_1 : wGearDenom	
C00837/99	L_CalcDiameter_1 : nSetD_a	
C00837/100	L_ProcessCtrl_1 : nVpAdapt_a	
C00837/101	L_ProcessCtrl_1 : nSet_a	
C00837/102	L_ProcessCtrl_1 : nAct_a	
C00837/103	L_ProcessCtrl_1 : nRTIMEAdapt_a	
C00837/104	L_ProcessCtrl_1 : nInfluence_a	
C00837/105	L_PhiIntegrator_1 : nIn_v	
C00837/106	L_PhiIntegrator_1 : wGearNum	
C00837/107	L_PhiIntegrator_1 : wGearDenom	
C00837/108	L_SwitchPoint_1 : nActSpeed_v	
C00837/109	L_PhiIntegrator_1 : nSpeedAdd_v	
C00837/110	L_DFSET_1 : nSpeedTrim_v	
C00837/111	L_DFSET_1 : nSpeedTrim_a	
C00837/112	L_DFSET_1 : wGearNum	
C00837/113	L_DFSET_1 : wGainNum	
C00837/114	L_DFSET_1 : nSet_v	
C00837/115	L_DFSET_1 : wGainDenom	
C00837/116	L_DFSET_1 : wGearDenom	

Parameter Name: C00837 16-bit inputs [rpm] (Set2)		Data type: INTEGER_16 Index: 23738 _d = 5CBA _h
C00837/117	L_DFSET_1 : nPositionTrimming	
C00837/118	L_DFSET_1 : nNAct_v	
C00837/119	L_DFRFG_1 : nIn_v	
C00837/120	L_GearComp_1 : nTorque_a	
C00837/121	L_ConvAP_1 : nIn_a	
C00837/122	L_ConvAP_2 : nIn_a	
C00837/123	L_ConvAP_3 : nIn_a	
C00837/124	L_ConvX_1 : nIn_a	
C00837/125	L_ConvX_1 : nNum	
C00837/126	L_ConvX_1 : wDenom	
C00837/127	L_ConvX_2 : nIn_a	
C00837/128	L_ConvX_2 : nNum	
C00837/129	L_ConvX_2 : wDenom	
C00837/130	L_ConvX_3 : nIn_a	
C00837/131	L_ConvX_3 : nNum	
C00837/132	L_ConvX_3 : wDenom	
C00837/133	L_ConvPP_1 : nNum	
C00837/134	L_ConvPP_1 : wDenom	
C00837/135	L_ConvPP_2 : nNum	
C00837/136	L_ConvPP_2 : wDenom	
C00837/137	L_ConvPP_3 : nNum	
C00837/138	L_ConvPP_3 : wDenom	
C00837/139	L_Curve_2 : nIn_a	
C00837/140	L_Curve_3 : nIn_a	
C00837/141	L_Sequencer_1 : wStartStep	
C00837/142	L_Sequencer_1 : wBranch1	
C00837/143	L_Sequencer_1 : wBranch2	
C00837/144	L_Sequencer_1 : wMotionState1	
C00837/145	L_Sequencer_1 : wMotionState2	
C00837/146	L_Sequencer_1 : wDigitalInputs	
C00837/147	L_ConvActPos_1 : nSetPos_a	
C00837/148	L_ConvActPos_1 : nPosIn_a	
C00837/149	L_ConvActPos_1 : wVMax	
C00837/150	L_ConvActPos_1 : nVLine_a	
C00837/151	L_MFail_1 : nAdapt_a	
C00837/152	L_MFail_1 : nConst_a	
C00837/153	L_MFail_1 : nDCSet_a	
C00837/154	L_MFail_1 : nNSet_a	
C00837/155	L_MFail_1 : nThreshold_a	
C00837/156	L_MFail_1 : nNAct_a	
C00837/157	L_MFail_1 : nSet_a	
C00837/158	L_MFail_1 : nDCVoltAct_a	
C00837/159	L_Curve_3 : nCurveCtrl_a	
C00837/160	L_Curve_3 : nD0_a	

Parameter Name: C00837 16-bit inputs [rpm] (Set2)		Data type: INTEGER_16 Index: 23738 _d = 5CBA _h
C00837/161	L Curve 3 : nDiameter_a	
C00837/162	L SwitchPointPar 1 : nActSpeed_v	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00838

Parameter Name: C00838 Binary inputs (Set2)		Data type: UNSIGNED_8 Index: 23737 _d = 5CB9 _h
Display of the signal status of the binary inputs of different blocks • In addition to the parameter C00833 .		
Selection list		
0	False	
1	True	
Subcodes	Info	
C00838/1	L And5 1 : bIn1	
C00838/2	L And5 1 : bIn2	
C00838/3	L And5 1 : bIn3	
C00838/4	L And5 1 : bIn4	
C00838/5	L And5 1 : bIn5	
C00838/6	L And5 2 : bIn1	
C00838/7	L And5 2 : bIn2	
C00838/8	L And5 2 : bIn3	
C00838/9	L And5 2 : bIn4	
C00838/10	L And5 2 : bIn5	
C00838/11	L AnalogSwitch 4 : bSet	
C00838/12	L AnalogSwitch 5 : bSet	
C00838/13	L DFlipFlop 2 : bD	
C00838/14	L DFlipFlop 2 : bClk	
C00838/15	L DFlipFlop 2 : bClr	
C00838/16	L DigitalDelay 2 : bIn	
C00838/17	L DigitalDelay 3 : bIn	
C00838/18	L PhaseIntK 1 : bLoad	
C00838/19	L PhaseIntK 2 : bLoad	
C00838/20	L DigitalLogic 2 : bIn1	
C00838/21	L DigitalLogic 2 : bIn2	
C00838/22	L DigitalLogic 2 : bIn3	
C00838/23	L DigitalLogic5 1 : bIn1	
C00838/24	L DigitalLogic5 1 : bIn2	
C00838/25	L DigitalLogic5 1 : bIn3	
C00838/26	L DigitalLogic5 1 : bIn4	
C00838/27	L DigitalLogic5 1 : bIn5	
C00838/28	L DigitalLogic5 2 : bIn1	
C00838/29	L DigitalLogic5 2 : bIn2	
C00838/30	L DigitalLogic5 2 : bIn3	
C00838/31	L DigitalLogic5 2 : bIn4	

Parameter Name: C00838 Binary inputs (Set2)		Data type: UNSIGNED_8 Index: 23737 _d = 5CB9 _h
C00838/32	L_DigitalLogic5_2 : bIn5	
C00838/33	L_NLim_2 : bEnable	
C00838/34	L_Or5_1 : bIn1	
C00838/35	L_Or5_1 : bIn2	
C00838/36	L_Or5_1 : bIn3	
C00838/37	L_Or5_1 : bIn4	
C00838/38	L_Or5_1 : bIn5	
C00838/39	L_Or5_2 : bIn1	
C00838/40	L_Or5_2 : bIn2	
C00838/41	L_Or5_2 : bIn3	
C00838/42	L_Or5_2 : bIn4	
C00838/43	L_Or5_2 : bIn5	
C00838/44	L_Not_4 : bIn	
C00838/45	L_Not_5 : bIn	
C00838/46	L_Not_6 : bIn	
C00838/47	L_Not_7 : bIn	
C00838/48	L_RSFlipFlop_1 : bSet	
C00838/49	L_RSFlipFlop_1 : bReset	
C00838/50	L_RSFlipFlop_2 : bSet	
C00838/51	L_RSFlipFlop_2 : bReset	
C00838/52	L_SampleHold_1 : bLoad	
C00838/53	L_SampleHold_2 : bLoad	
C00838/54	L_Counter_2 : bClkUp	
C00838/55	L_Counter_2 : bClkDown	
C00838/56	L_Counter_2 : bLoad	
C00838/57	L_Counter_3 : bClkUp	
C00838/58	L_Counter_3 : bClkDown	
C00838/59	L_Counter_3 : bLoad	
C00838/60	L_Transient_5 : bIn	
C00838/61	L_Transient_6 : bIn	
C00838/62	L_Transient_7 : bIn	
C00838/63	L_Transient_8 : bIn	
C00838/64	L_Counter_1 : bCountUp	
C00838/65	L_Counter_1 : bCountDown	
C00838/66	L_Counter_1 : bLoad	
C00838/67	L_ConvBitsToWord_1 : bBit0	
C00838/68	L_ConvBitsToWord_1 : bBit1	
C00838/69	L_ConvBitsToWord_1 : bBit2	
C00838/70	L_ConvBitsToWord_1 : bBit3	
C00838/71	L_ConvBitsToWord_1 : bBit4	
C00838/72	L_ConvBitsToWord_1 : bBit5	
C00838/73	L_ConvBitsToWord_1 : bBit6	
C00838/74	L_ConvBitsToWord_1 : bBit7	
C00838/75	L_ConvBitsToWord_1 : bBit8	

Parameter Name: C00838 Binary inputs (Set2)		Data type: UNSIGNED_8 Index: 23737 _d = 5CB9 _h
C00838/76	L_ConvBitsToWord_1 : bBit9	
C00838/77	L_ConvBitsToWord_1 : bBit10	
C00838/78	L_ConvBitsToWord_1 : bBit11	
C00838/79	L_ConvBitsToWord_1 : bBit12	
C00838/80	L_ConvBitsToWord_1 : bBit13	
C00838/81	L_ConvBitsToWord_1 : bBit14	
C00838/82	L_ConvBitsToWord_1 : bBit15	
C00838/83	L_ConvBitsToWord_2 : bBit0	
C00838/84	L_ConvBitsToWord_2 : bBit1	
C00838/85	L_ConvBitsToWord_2 : bBit2	
C00838/86	L_ConvBitsToWord_2 : bBit3	
C00838/87	L_ConvBitsToWord_2 : bBit4	
C00838/88	L_ConvBitsToWord_2 : bBit5	
C00838/89	L_ConvBitsToWord_2 : bBit6	
C00838/90	L_ConvBitsToWord_2 : bBit7	
C00838/91	L_ConvBitsToWord_2 : bBit8	
C00838/92	L_ConvBitsToWord_2 : bBit9	
C00838/93	L_ConvBitsToWord_2 : bBit10	
C00838/94	L_ConvBitsToWord_2 : bBit11	
C00838/95	L_ConvBitsToWord_2 : bBit12	
C00838/96	L_ConvBitsToWord_2 : bBit13	
C00838/97	L_ConvBitsToWord_2 : bBit14	
C00838/98	L_ConvBitsToWord_2 : bBit15	
C00838/99	L_ConvBitsToWord_3 : bBit0	
C00838/100	L_ConvBitsToWord_3 : bBit1	
C00838/101	L_ConvBitsToWord_3 : bBit2	
C00838/102	L_ConvBitsToWord_3 : bBit3	
C00838/103	L_ConvBitsToWord_3 : bBit4	
C00838/104	L_ConvBitsToWord_3 : bBit5	
C00838/105	L_ConvBitsToWord_3 : bBit6	
C00838/106	L_ConvBitsToWord_3 : bBit7	
C00838/107	L_ConvBitsToWord_3 : bBit8	
C00838/108	L_ConvBitsToWord_3 : bBit9	
C00838/109	L_ConvBitsToWord_3 : bBit10	
C00838/110	L_ConvBitsToWord_3 : bBit11	
C00838/111	L_ConvBitsToWord_3 : bBit12	
C00838/112	L_ConvBitsToWord_3 : bBit13	
C00838/113	L_ConvBitsToWord_3 : bBit14	
C00838/114	L_ConvBitsToWord_3 : bBit15	
C00838/115	L_MckCtrlInterface_1 : bManJogPos	
C00838/116	L_MckCtrlInterface_1 : bManJogNeg	
C00838/117	L_MckCtrlInterface_1 : bManJogExecute2ndVel	
C00838/118	L_MckCtrlInterface_1 : bReleaseLimitSwitch	
C00838/119	L_MckCtrlInterface_1 : bHomingStartStop	

Parameter Name: C00838 Binary inputs (Set2)		Data type: UNSIGNED_8 Index: 23737 _d = 5CB9 _h
C00838/120	L MckCtrlInterface 1 : bHomingSetPos	
C00838/121	L MckCtrlInterface 1 : bHomingResetPos	
C00838/122	L MckCtrlInterface 1 : bEnableVelOverride	
C00838/123	L MckCtrlInterface 1 : bEnableAccOverride	
C00838/124	L MckCtrlInterface 1 : bDisableSShaping	
C00838/125	L MckCtrlInterface 1 : bPosExecute	
C00838/126	L MckCtrlInterface 1 : bPosExecuteFinish	
C00838/127	L MckCtrlInterface 1 : bPosDisableFollowProfile	
C00838/128	L MckCtrlInterface 1 : bPosStop	
C00838/129	L MckCtrlInterface 1 : bPosTeachSetPos	
C00838/130	L MckCtrlInterface 1 : bPosTeachActPos	
C00838/131	L MckCtrlInterface 1 : bProfileNo_1	
C00838/132	L MckCtrlInterface 1 : bProfileNo_2	
C00838/133	L MckCtrlInterface 1 : bProfileNo_4	
C00838/134	L MckCtrlInterface 1 : bProfileNo_8	
C00838/135	L MckCtrlInterface 1 : bOperationMode_1	
C00838/136	L MckCtrlInterface 1 : bOperationMode_2	
C00838/137	L MckCtrlInterface 1 : bOperationMode_4	
C00838/138	L MckCtrlInterface 1 : bOperationMode_8	
C00838/139	L PhaseDiff 1 : bEnable	
C00838/140	L PhaseDiff 2 : bEnable	
C00838/141	L PhaseDiff 1 : bReset	
C00838/142	L PhaseDiff 2 : bReset	
C00838/143	L SRFG 1 : bLoad	
C00838/144	L SRFG 2 : bLoad	
C00838/145	L SignalSwitch 1 : bSet	
C00838/146	L SignalSwitch 2 : bSet	
C00838/147	L SignalSwitch 3 : bSet	
C00838/148	L SignalSwitch 4 : bSet	
C00838/149	L Odometer 1 : bTriggerPulse	
C00838/150	L Odometer 1 : bReset	
C00838/151	L FixSet a 1 : bSelect1	
C00838/152	L FixSet a 1 : bSelect2	
C00838/153	L FixSet a 1 : bSelect4	
C00838/154	L FixSet a 1 : bSelect8	
C00838/155	L FixSet w 1 : bSelect1	
C00838/156	L FixSet w 1 : bSelect2	
C00838/157	L FixSet w 1 : bSelect4	
C00838/158	L FixSet w 1 : bSelect8	
C00838/159	L FixSet w 2 : bSelect1	
C00838/160	L FixSet w 2 : bSelect2	
C00838/161	L FixSet w 2 : bSelect4	
C00838/162	L FixSet w 2 : bSelect8	
C00838/163	L CalcDiameter 1 : bResetPos	

Parameter Name: C00838 Binary inputs (Set2)		Data type: UNSIGNED_8 Index: 23737 _d = 5CB9 _h
C00838/164	L_CalcDiameter_1 : bHoldD	
C00838/165	L_CalcDiameter_1 : bUnidirect	
C00838/166	L_CalcDiameter_1 : bUnwind	
C00838/167	L_CalcDiameter_1 : bLoadDiameter	
C00838/168	L_CalcDiameter_1 : bCalcRef	
C00838/169	L_ProcessCtrl_1 : bLoadAct	
C00838/170	L_ProcessCtrl_1 : bOff	
C00838/171	L_ProcessCtrl_1 : bReset	
C00838/172	L_PhilIntegrator_1 : bTPReceived	
C00838/173	L_PhilIntegrator_1 : bReset	
C00838/174	L_PhilIntegrator_1 : bLoad	
C00838/175	L_PosCtrlLin_1 : bExecute	
C00838/176	L_PosCtrlLin_1 : bSetPos0	
C00838/177	L_PosCtrlLin_1 : bPosMode	
C00838/178	L_PosCtrlLin_1 : bEnable	
C00838/179	L_PosCtrlLin_2 : bExecute	
C00838/180	L_PosCtrlLin_2 : bSetPos0	
C00838/181	L_PosCtrlLin_2 : bPosMode	
C00838/182	L_PosCtrlLin_2 : bEnable	
C00838/183	L_SwitchPoint_1 : bDisable	
C00838/184	L_DFSET_1 : bZeroPulse	
C00838/185	L_DFSET_1 : bSetTPReceived	
C00838/186	L_DFSET_1 : bActTPReceived	
C00838/187	L_DFSET_1 : bSetActIntegrator	
C00838/188	L_DFSET_1 : bResetAllIntegrators	
C00838/189	L_DFRFG_1 : bSetTPReceived	
C00838/190	L_DFRFG_1 : bRfg0	
C00838/191	L_DFRFG_1 : bRfgStop	
C00838/192	L_DFRFG_1 : bReset	
C00838/193	L_ConvX_1 : bInvers	
C00838/194	L_ConvX_2 : bInvers	
C00838/195	L_ConvX_3 : bInvers	
C00838/196	L_ConvPP_1 : bAct	
C00838/197	L_ConvPP_2 : bAct	
C00838/198	L_ConvPP_3 : bAct	
C00838/199	L_SignalSwitch32_1 : bSet	
C00838/200	L_SignalSwitch32_2 : bSet	
C00838/201	L_SignalSwitch32_3 : bSet	
C00838/202	L_Sequencer_1 : bStart	
C00838/203	L_Sequencer_1 : bPause	
C00838/204	L_Sequencer_1 : bNextStep	
C00838/205	L_Sequencer_1 : bCancel	
C00838/206	L_Sequencer_1 : bBreak	
C00838/207	L_Sequencer_1 : bReset	

Parameter Name: C00838 Binary inputs (Set2)		Data type: UNSIGNED_8 Index: 23737 _d = 5CB9 _h
C00838/208	L_ConvActPos_1 : bWriteMaxPos	
C00838/209	L_ConvActPos_1 : bWriteMinPos	
C00838/210	L_MFail_1 : bFault	
C00838/211	L_MFail_1 : bReset	
C00838/212	L_Curve_3 : bEnableTensionCurve	
C00838/213	L_SwitchPointPar_1 : bDisable	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00839

Parameter Name: C00839 32-bit inputs [incr] (Set2)			Data type: INTEGER_32 Index: 23736 _d = 5CB8 _h
Display in [increments] of 32 bit input values of various blocks • In addition to the parameter C00834 .			
Display range (min. value unit max. value)			
-2147483647	Incr.	2147483647	
Subcodes			Info
C00839/1	L_ComparePhi_1 : dnIn1_p		
C00839/2	L_ComparePhi_1 : dnIn2_p		
C00839/3	L_ComparePhi_2 : dnIn1_p		
C00839/4	L_ComparePhi_2 : dnIn2_p		
C00839/5	L_ComparePhi_3 : dnIn1_p		
C00839/6	L_ComparePhi_3 : dnIn2_p		
C00839/7	L_ComparePhi_4 : dnIn1_p		
C00839/8	L_ComparePhi_4 : dnIn2_p		
C00839/9	L_ComparePhi_5 : dnIn1_p		
C00839/10	L_ComparePhi_5 : dnIn2_p		
C00839/11	L_ArithmetikPhi_1 : dnIn1_p		
C00839/12	L_ArithmetikPhi_1 : dnIn2_p		
C00839/13	L_ArithmetikPhi_2 : dnIn1_p		
C00839/14	L_ArithmetikPhi_2 : dnIn2_p		
C00839/15	L_ArithmetikPhi_3 : dnIn1_p		
C00839/16	L_ArithmetikPhi_3 : dnIn2_p		
C00839/17	L_GainOffsetPhiP_1 : dnIn_p		
C00839/18	L_GainOffsetPhiP_2 : dnIn_p		
C00839/19	L_LimitPhi_1 : dnIn_p		
C00839/20	L_LimitPhi_2 : dnIn_p		
C00839/21	L_LimitPhi_3 : dnIn_p		
C00839/22	L_OffsetGainPhiP_1 : dnIn_p		
C00839/23	L_OffsetGainPhiP_2 : dnIn_p		
C00839/24	L_PhaseIntK_1 : dnSet_p		
C00839/25	L_PhaseIntK_2 : dnSet_p		
C00839/26	L_Mux_1 : dnInput1_p		
C00839/27	L_Mux_1 : dnInput2_p		
C00839/28	L_Mux_1 : dnInput3_p		

Parameter Name: C00839 32-bit inputs [incr] (Set2)		Data type: INTEGER_32 Index: 23736 _d = 5CB8 _h
C00839/29	L Mux 1 : dnInput4_p	
C00839/30	L Mux 1 : dnInput5_p	
C00839/31	L Mux 1 : dnInput6_p	
C00839/32	L Mux 1 : dnInput7_p	
C00839/33	L Mux 1 : dnInput8_p	
C00839/34	L SQrt 1 : dnInput_p	
C00839/35	L ConvDIntToWords 1 : dnInput_p	
C00839/36	L ConvDIntToWords 2 : dnInput_p	
C00839/37	L ConvDIntToWords 3 : dnInput_p	
C00839/38	L MckCtrlInterface 1 : dnPosSetIn_p	
C00839/39	L PhaseDiff 1 : dnSet_p	
C00839/40	L PhaseDiff 2 : dnSet_p	
C00839/41	L PhaseDiff 1 : dnAdd_p	
C00839/42	L PhaseDiff 2 : dnAdd_p	
C00839/43	L MckStateInterface 1 : dnPosIn_p	
C00839/44	L Odometer 1 : dnInPosition_p	
C00839/45	L PhiIntegrator 1 : dnTPPosition_p	
C00839/46	L PhiIntegrator 1 : dnLoadVal_p	
C00839/47	L PosCtrlLin 1 : dnSet_p	
C00839/48	L PosCtrlLin 1 : dnAct_p	
C00839/49	L PosCtrlLin 2 : dnSet_p	
C00839/50	L PosCtrlLin 2 : dnAct_p	
C00839/51	L SwitchPoint 1 : dnActPos_p	
C00839/52	L SwitchPoint 1 : dnSwitchPoint1_p	
C00839/53	L SwitchPoint 1 : dn2ndPoint_Size1_p	
C00839/54	L SwitchPoint 1 : dnSwitchPoint2_p	
C00839/55	L SwitchPoint 1 : dn2ndPoint_Size2_p	
C00839/56	L SwitchPoint 1 : dnSwitchPoint3_p	
C00839/57	L SwitchPoint 1 : dn2ndPoint_Size3_p	
C00839/58	L SwitchPoint 1 : dnSwitchPoint4_p	
C00839/59	L SwitchPoint 1 : dn2ndPoint_Size4_p	
C00839/60	L DFSET 1 : dnSetTPPos_p	
C00839/61	L DFSET 1 : dnActTPPos_p	
C00839/62	L DFSET 1 : dnPosOffset	
C00839/63	L DFRFG 1 : dnSetTPPos_p	
C00839/64	L GearComp 1 : dnPhiln_p	
C00839/65	L ConvPA 1 : dnIn_p	
C00839/66	L ConvPA 2 : dnIn_p	
C00839/67	L ConvPA 3 : dnIn_p	
C00839/68	L ConvPP 1 : dnIn_p	
C00839/69	L ConvPP 2 : dnIn_p	
C00839/70	L ConvPP 3 : dnIn_p	
C00839/71	L SignalSwitch32 1 : dnIn1	
C00839/72	L SignalSwitch32 1 : dnIn2	

Parameter Name: C00839 32-bit inputs [incr] (Set2)		Data type: INTEGER_32 Index: 23736 _d = 5CB8 _h
C00839/73	L_SignalSwitch32_2 : dnIn1	
C00839/74	L_SignalSwitch32_2 : dnIn2	
C00839/75	L_SignalSwitch32_3 : dnIn1	
C00839/76	L_SignalSwitch32_3 : dnIn2	
C00839/77	L_ArithmetikPhi_4 : adnIn1_p	
C00839/78	L_ArithmetikPhi_4 : adnIn2_p	
C00839/79	L_ArithmetikPhi_5 : adnIn1_p	
C00839/80	L_ArithmetikPhi_5 : adnIn2_p	
C00839/81	L_ArithmetikPhi_6 : adnIn1_p	
C00839/82	L_ArithmetikPhi_6 : adnIn2_p	
C00839/83	L_PhiDiv_1 : dnIn_p	
C00839/84	L_PhiAdd_1 : dnIn1_p	
C00839/85	L_PhiAdd_1 : dnIn2_p	
C00839/86	L_PhiAdd_1 : dnIn3_p	
C00839/87	L_DFSET_1 : dnDeltaPosIn_p	
C00839/88	L_SwitchPoint_1 : dnSwitchPoint5_p	
C00839/89	L_SwitchPoint_1 : dn2ndPoint_Size5_p	
C00839/90	L_SwitchPoint_1 : dnSwitchPoint6_p	
C00839/91	L_SwitchPoint_1 : dn2ndPoint_Size6_p	
C00839/92	L_SwitchPoint_1 : dnSwitchPoint7_p	
C00839/93	L_SwitchPoint_1 : dn2ndPoint_Size7_p	
C00839/94	L_SwitchPoint_1 : dnSwitchPoint8_p	
C00839/95	L_SwitchPoint_1 : dn2ndPoint_Size8_p	
C00839/96	L_SwitchPointPar_1 : dnActPos_p	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00840

Parameter Name: C00840 16-bit inputs I/O level [%]		Data type: INTEGER_16 Index: 23735 _d = 5CB7 _h
Display in percent of 16 bit input values of various blocks of the I/O level		
Display range (min. value unit max. value)		
-199.99	%	199.99
Subcodes		Info
C00840/1	LS_AnalogOutput : nOut1_a (V)	
C00840/2	LP_CanOut1 : wState	
C00840/3	LP_CanOut1 : wOut2	
C00840/4	LP_CanOut1 : wOut3	
C00840/5	LP_CanOut1 : wOut4	
C00840/6	LP_CanOut2 : wOut1	
C00840/7	LP_CanOut2 : wOut2	
C00840/8	LP_CanOut2 : wOut3	
C00840/9	LP_CanOut2 : wOut4	
C00840/10	LP_CanOut3 : wOut1	
C00840/11	LP_CanOut3 : wOut2	

Parameter Name: C00840 16-bit inputs I/O level [%]		Data type: INTEGER_16 Index: 23735 _d = 5CB7 _h
C00840/12	LP_CanOut3 : wOut3	
C00840/13	LP_CanOut3 : wOut4	
C00840/14	LS_DisFree_a : nDis1_a	
C00840/15	LS_DisFree_a : nDis2_a	
C00840/16	LS_DisFree_a : nDis3_a	
C00840/17	LS_DisFree_a : nDis4_a	
C00840/18	LS_DisFree : wDis1	
C00840/19	LS_DisFree : wDis2	
C00840/20	LS_DisFree : wDis3	
C00840/21	LS_DisFree : wDis4	
C00840/22	LP_MciOut : wState	
C00840/23	LP_MciOut : wOut2	
C00840/24	LP_MciOut : wOut3	
C00840/25	LP_MciOut : wOut4	
C00840/26	LP_MciOut : wOut5	
C00840/27	LP_MciOut : wOut6	
C00840/28	LP_MciOut : wOut7	
C00840/29	LP_MciOut : wOut8	
C00840/30	LP_MciOut : wOut9	
C00840/31	LP_MciOut : wOut10	
C00840/32	LP_MciOut : wOut11	
C00840/33	LP_MciOut : wOut12	
C00840/34	LP_MciOut : wOut13	
C00840/35	LP_MciOut : wOut14	
C00840/36	LP_MciOut : wOut15	
C00840/37	LP_MciOut : wOut16	
C00840/38	LS_AnalogOutput : nOut2_a (V)	
C00840/39	LS_AnalogOutput : nOut1_a (I)	
C00840/40	LS_AnalogOutput : nOut2_a (I)	
C00840/41	LS_DisFree_a : nDis5_a	
C00840/42	LS_DisFree_a : nDis6_a	
C00840/43	LS_DisFree_a : nDis7_a	
C00840/44	LS_DisFree_a : nDis8_a	
C00840/45	LS_DisFree : wDis5	
C00840/46	LS_DisFree : wDis6	
C00840/47	LS_DisFree : wDis7	
C00840/48	LS_DisFree : wDis8	
C00840/49	LS_ParReadWrite_1 : wParIndex	
C00840/50	LS_ParReadWrite_1 : wParSubindex	
C00840/51	LS_ParReadWrite_1 : wInHWord	
C00840/52	LS_ParReadWrite_1 : wInLWord	
C00840/53	LS_ParReadWrite_2 : wParIndex	
C00840/54	LS_ParReadWrite_2 : wParSubindex	
C00840/55	LS_ParReadWrite_2 : wInHWord	

Parameter Name: C00840 16-bit inputs I/O level [%]		Data type: INTEGER_16 Index: 23735 _d = 5CB7 _h
C00840/56	LS_ParReadWrite_2 : wInLWord	
C00840/57	LS_ParReadWrite_3 : wParIndex	
C00840/58	LS_ParReadWrite_3 : wParSubindex	
C00840/59	LS_ParReadWrite_3 : wInHWord	
C00840/60	LS_ParReadWrite_3 : wInLWord	
C00840/61	LS_ParReadWrite_4 : wParIndex	
C00840/62	LS_ParReadWrite_4 : wParSubindex	
C00840/63	LS_ParReadWrite_4 : wInHWord	
C00840/64	LS_ParReadWrite_4 : wInLWord	
C00840/65	LS_ParReadWrite_5 : wParIndex	
C00840/66	LS_ParReadWrite_5 : wParSubindex	
C00840/67	LS_ParReadWrite_5 : wInHWord	
C00840/68	LS_ParReadWrite_5 : wInLWord	
C00840/69	LS_ParReadWrite_6 : wParIndex	
C00840/70	LS_ParReadWrite_6 : wParSubindex	
C00840/71	LS_ParReadWrite_6 : wInHWord	
C00840/72	LS_ParReadWrite_6 : wInLWord	
C00840/73	Reserved	
C00840/74	Reserved	
C00840/75	Reserved	
C00840/76	Reserved	
C00840/77	Reserved	
C00840/78	Reserved	
C00840/79	Reserved	
C00840/80	Reserved	
C00840/81	Reserved	
C00840/82	Reserved	
C00840/83	Reserved	
C00840/84	Reserved	
C00840/85	Reserved	
C00840/86	Reserved	
C00840/87	Reserved	
C00840/88	Reserved	
C00840/89	LS_RetainData : wIn1	
C00840/90	LS_RetainData : wIn2	
C00840/91	LS_RetainData : wIn3	
C00840/92	LS_RetainData : wIn4	
C00840/93	LS_AxisBusOut : wLine1	
C00840/94	LS_AxisBusOut : wLine2	
C00840/95	LS_AxisBusOut : wLine3	
C00840/96	LS_AxisBusOut : wCas1	
C00840/97	LS_AxisBusOut : wCas2	
C00840/98	LS_AxisBusOut : wCas3	
C00840/99	LS_AxisBusOut : wCas4	

Parameter Name: C00840 16-bit inputs I/O level [%]		Data type: INTEGER_16 Index: 23735 _d = 5CB7 _h
C00840/100	LS_AxisBusAux : wAuxOut1	
C00840/101	LS_AxisBusAux : wAuxOut2	
C00840/102	LS_AxisBusAux : wAuxOut3	
C00840/103	LS_AxisBusAux : wAuxOut4	
C00840/104	LS_AxisBusAux : wSelectSlave	
C00840/105	LS_DFOut : nOut_v	
C00840/106	LS_MultiEncoder : wActPosExternalHW	
C00840/107	LS_MultiEncoder : wActPosExternalLW	
C00840/108	LP_CanOut4 : wOut1	
C00840/109	LP_CanOut4 : wOut2	
C00840/110	LP_CanOut4 : wOut3	
C00840/111	LP_CanOut4 : wOut4	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100		

C00841

Parameter Name: C00841 16-bit inputs I/O level		Data type: UNSIGNED_16 Index: 23734 _d = 5CB6 _h
Decimal/hexadecimal/bit coded display of 16 bit input values of various blocks of the I/O level		
Display area (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		
Bit 0	Active	
...	...	
Bit 15	Active	
Subcodes		Info
C00841/1	LS_AnalogOutput : nOut1_a (V)	
C00841/2	LP_CanOut1 : wState	
C00841/3	LP_CanOut1 : wOut2	
C00841/4	LP_CanOut1 : wOut3	
C00841/5	LP_CanOut1 : wOut4	
C00841/6	LP_CanOut2 : wOut1	
C00841/7	LP_CanOut2 : wOut2	
C00841/8	LP_CanOut2 : wOut3	
C00841/9	LP_CanOut2 : wOut4	
C00841/10	LP_CanOut3 : wOut1	
C00841/11	LP_CanOut3 : wOut2	
C00841/12	LP_CanOut3 : wOut3	
C00841/13	LP_CanOut3 : wOut4	
C00841/14	LS_DisFree_a : nDis1_a	
C00841/15	LS_DisFree_a : nDis2_a	
C00841/16	LS_DisFree_a : nDis3_a	
C00841/17	LS_DisFree_a : nDis4_a	
C00841/18	LS_DisFree : wDis1	
C00841/19	LS_DisFree : wDis2	

Parameter Name: C00841 16-bit inputs I/O level		Data type: UNSIGNED_16 Index: 23734 _d = 5CB6 _h
C00841/20	LS_DisFree : wDis3	
C00841/21	LS_DisFree : wDis4	
C00841/22	LP_MciOut : wState	
C00841/23	LP_MciOut : wOut2	
C00841/24	LP_MciOut : wOut3	
C00841/25	LP_MciOut : wOut4	
C00841/26	LP_MciOut : wOut5	
C00841/27	LP_MciOut : wOut6	
C00841/28	LP_MciOut : wOut7	
C00841/29	LP_MciOut : wOut8	
C00841/30	LP_MciOut : wOut9	
C00841/31	LP_MciOut : wOut10	
C00841/32	LP_MciOut : wOut11	
C00841/33	LP_MciOut : wOut12	
C00841/34	LP_MciOut : wOut13	
C00841/35	LP_MciOut : wOut14	
C00841/36	LP_MciOut : wOut15	
C00841/37	LP_MciOut : wOut16	
C00841/38	LS_AnalogOutput : nOut2_a (V)	
C00841/39	LS_AnalogOutput : nOut1_a (I)	
C00841/40	LS_AnalogOutput : nOut2_a (I)	
C00841/41	LS_DisFree_a : nDis5_a	
C00841/42	LS_DisFree_a : nDis6_a	
C00841/43	LS_DisFree_a : nDis7_a	
C00841/44	LS_DisFree_a : nDis8_a	
C00841/45	LS_DisFree : wDis5	
C00841/46	LS_DisFree : wDis6	
C00841/47	LS_DisFree : wDis7	
C00841/48	LS_DisFree : wDis8	
C00841/49	LS_ParReadWrite_1 : wParIndex	
C00841/50	LS_ParReadWrite_1 : wParSubindex	
C00841/51	LS_ParReadWrite_1 : wInHWord	
C00841/52	LS_ParReadWrite_1 : wInLWord	
C00841/53	LS_ParReadWrite_2 : wParIndex	
C00841/54	LS_ParReadWrite_2 : wParSubindex	
C00841/55	LS_ParReadWrite_2 : wInHWord	
C00841/56	LS_ParReadWrite_2 : wInLWord	
C00841/57	LS_ParReadWrite_3 : wParIndex	
C00841/58	LS_ParReadWrite_3 : wParSubindex	
C00841/59	LS_ParReadWrite_3 : wInHWord	
C00841/60	LS_ParReadWrite_3 : wInLWord	
C00841/61	LS_ParReadWrite_4 : wParIndex	
C00841/62	LS_ParReadWrite_4 : wParSubindex	
C00841/63	LS_ParReadWrite_4 : wInHWord	

Parameter Name: C00841 16-bit inputs I/O level		Data type: UNSIGNED_16 Index: 23734 _d = 5CB6 _h
C00841/64	LS_ParReadWrite_4 : wInLWord	
C00841/65	LS_ParReadWrite_5 : wParIndex	
C00841/66	LS_ParReadWrite_5 : wParSubindex	
C00841/67	LS_ParReadWrite_5 : wInHWord	
C00841/68	LS_ParReadWrite_5 : wInLWord	
C00841/69	LS_ParReadWrite_6 : wParIndex	
C00841/70	LS_ParReadWrite_6 : wParSubindex	
C00841/71	LS_ParReadWrite_6 : wInHWord	
C00841/72	LS_ParReadWrite_6 : wInLWord	
C00841/73	Reserved	
C00841/74	Reserved	
C00841/75	Reserved	
C00841/76	Reserved	
C00841/77	Reserved	
C00841/78	Reserved	
C00841/79	Reserved	
C00841/80	Reserved	
C00841/81	Reserved	
C00841/82	Reserved	
C00841/83	Reserved	
C00841/84	Reserved	
C00841/85	Reserved	
C00841/86	Reserved	
C00841/87	Reserved	
C00841/88	Reserved	
C00841/89	LS_RetainData : wIn1	
C00841/90	LS_RetainData : wIn2	
C00841/91	LS_RetainData : wIn3	
C00841/92	LS_RetainData : wIn4	
C00841/93	LS_AxisBusOut : wLine1	
C00841/94	LS_AxisBusOut : wLine2	
C00841/95	LS_AxisBusOut : wLine3	
C00841/96	LS_AxisBusOut : wCas1	
C00841/97	LS_AxisBusOut : wCas2	
C00841/98	LS_AxisBusOut : wCas3	
C00841/99	LS_AxisBusOut : wCas4	
C00841/100	LS_AxisBusAux : wAuxOut1	
C00841/101	LS_AxisBusAux : wAuxOut2	
C00841/102	LS_AxisBusAux : wAuxOut3	
C00841/103	LS_AxisBusAux : wAuxOut4	
C00841/104	LS_AxisBusAux : wSelectSlave	
C00841/105	LS_DFOut : nOut_v	
C00841/106	LS_MultiEncoder : wActPosExternalHW	
C00841/107	LS_MultiEncoder : wActPosExternalLW	

Parameter Name: C00841 16-bit inputs I/O level		Data type: UNSIGNED_16 Index: 23734 _d = 5CB6 _h
C00841/108	LP_CanOut4 : wOut1	
C00841/109	LP_CanOut4 : wOut2	
C00841/110	LP_CanOut4 : wOut3	
C00841/111	LP_CanOut4 : wOut4	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C00843

Parameter Name: C00843 Binary inputs I/O level		Data type: UNSIGNED_8 Index: 23732 _d = 5CB4 _h
Display of the signal status of the binary inputs of different I/O level blocks		
Selection list		
0	False	
1	True	
Subcodes	Info	
C00843/1	LS_DigitalOutput : bRelay	
C00843/2	LS_DigitalOutput : bOut1	
C00843/3	LS_DigitalInput : bCountIn1_Reset	
C00843/4	LS_DigitalInput : bCountIn1_LoadStartValue	
C00843/5	LP_CanOut1 : bState_B0	
C00843/6	LP_CanOut1 : bState_B1	
C00843/7	LP_CanOut1 : bState_B2	
C00843/8	LP_CanOut1 : bState_B3	
C00843/9	LP_CanOut1 : bState_B4	
C00843/10	LP_CanOut1 : bState_B5	
C00843/11	LP_CanOut1 : bState_B6	
C00843/12	LP_CanOut1 : bState_B7	
C00843/13	LP_CanOut1 : bState_B8	
C00843/14	LP_CanOut1 : bState_B9	
C00843/15	LP_CanOut1 : bState_B10	
C00843/16	LP_CanOut1 : bState_B11	
C00843/17	LP_CanOut1 : bState_B12	
C00843/18	LP_CanOut1 : bState_B13	
C00843/19	LP_CanOut1 : bState_B14	
C00843/20	LP_CanOut1 : bState_B15	
C00843/21	LS_DisFree_b : bDis1	
C00843/22	LS_DisFree_b : bDis2	
C00843/23	LS_DisFree_b : bDis3	
C00843/24	LS_DisFree_b : bDis4	
C00843/25	LS_DisFree_b : bDis5	
C00843/26	LS_DisFree_b : bDis6	
C00843/27	LS_DisFree_b : bDis7	
C00843/28	LS_DisFree_b : bDis8	
C00843/29	LP_CanOut2 : bOut1_B0	
C00843/30	LP_CanOut2 : bOut1_B1	

Parameter Name: C00843 Binary inputs I/O level		Data type: UNSIGNED_8 Index: 23732 _d = 5CB4 _h
C00843/31	LP_CanOut2 : bOut1_B2	
C00843/32	LP_CanOut2 : bOut1_B3	
C00843/33	LP_CanOut2 : bOut1_B4	
C00843/34	LP_CanOut2 : bOut1_B5	
C00843/35	LP_CanOut2 : bOut1_B6	
C00843/36	LP_CanOut2 : bOut1_B7	
C00843/37	LP_CanOut2 : bOut1_B8	
C00843/38	LP_CanOut2 : bOut1_B9	
C00843/39	LP_CanOut2 : bOut1_B10	
C00843/40	LP_CanOut2 : bOut1_B11	
C00843/41	LP_CanOut2 : bOut1_B12	
C00843/42	LP_CanOut2 : bOut1_B13	
C00843/43	LP_CanOut2 : bOut1_B14	
C00843/44	LP_CanOut2 : bOut1_B15	
C00843/45	LP_CanOut3 : bOut1_B0	
C00843/46	LP_CanOut3 : bOut1_B1	
C00843/47	LP_CanOut3 : bOut1_B2	
C00843/48	LP_CanOut3 : bOut1_B3	
C00843/49	LP_CanOut3 : bOut1_B4	
C00843/50	LP_CanOut3 : bOut1_B5	
C00843/51	LP_CanOut3 : bOut1_B6	
C00843/52	LP_CanOut3 : bOut1_B7	
C00843/53	LP_CanOut3 : bOut1_B8	
C00843/54	LP_CanOut3 : bOut1_B9	
C00843/55	LP_CanOut3 : bOut1_B10	
C00843/56	LP_CanOut3 : bOut1_B11	
C00843/57	LP_CanOut3 : bOut1_B12	
C00843/58	LP_CanOut3 : bOut1_B13	
C00843/59	LP_CanOut3 : bOut1_B14	
C00843/60	LP_CanOut3 : bOut1_B15	
C00843/61	LP_MciOut : bState_B0	
C00843/62	LP_MciOut : bState_B1	
C00843/63	LP_MciOut : bState_B2	
C00843/64	LP_MciOut : bState_B3	
C00843/65	LP_MciOut : bState_B4	
C00843/66	LP_MciOut : bState_B5	
C00843/67	LP_MciOut : bState_B6	
C00843/68	LP_MciOut : bState_B7	
C00843/69	LP_MciOut : bState_B8	
C00843/70	LP_MciOut : bState_B9	
C00843/71	LP_MciOut : bState_B10	
C00843/72	LP_MciOut : bState_B11	
C00843/73	LP_MciOut : bState_B12	
C00843/74	LP_MciOut : bState_B13	

Parameter Name: C00843 Binary inputs I/O level		Data type: UNSIGNED_8 Index: 23732 _d = 5CB4 _h
C00843/75	LP_MciOut : bState_B14	
C00843/76	LP_MciOut : bState_B15	
C00843/77	LP_MciOut : bOut2_B0	
C00843/78	LP_MciOut : bOut2_B1	
C00843/79	LP_MciOut : bOut2_B2	
C00843/80	LP_MciOut : bOut2_B3	
C00843/81	LP_MciOut : bOut2_B4	
C00843/82	LP_MciOut : bOut2_B5	
C00843/83	LP_MciOut : bOut2_B6	
C00843/84	LP_MciOut : bOut2_B7	
C00843/85	LP_MciOut : bOut2_B8	
C00843/86	LP_MciOut : bOut2_B9	
C00843/87	LP_MciOut : bOut2_B10	
C00843/88	LP_MciOut : bOut2_B11	
C00843/89	LP_MciOut : bOut2_B12	
C00843/90	LP_MciOut : bOut2_B13	
C00843/91	LP_MciOut : bOut2_B14	
C00843/92	LP_MciOut : bOut2_B15	
C00843/93	LS_SetError_1 : bSetError1	
C00843/94	LS_SetError_1 : bSetError2	
C00843/95	LS_SetError_1 : bSetError3	
C00843/96	LS_SetError_1 : bSetError4	
C00843/97	LS_DigitalInput : bCountIn6_Reset	
C00843/98	LS_DigitalInput : bCountIn6_LoadStartValue	
C00843/99	LS_DigitalOutput : bOut2	
C00843/100	LS_DigitalOutput : bOut3	
C00843/101	LS_DigitalOutput : bOut_HighCurrent	
C00843/102	LS_DisFree_b : bDis9	
C00843/103	LS_DisFree_b : bDis10	
C00843/104	LS_DisFree_b : bDis11	
C00843/105	LS_DisFree_b : bDis12	
C00843/106	LS_DisFree_b : bDis13	
C00843/107	LS_DisFree_b : bDis14	
C00843/108	LS_DisFree_b : bDis15	
C00843/109	LS_DisFree_b : bDis16	
C00843/110	Reserved	
C00843/111	LS_ParReadWrite_1 : bExecute	
C00843/112	LS_ParReadWrite_1 : bReadWrite	
C00843/113	LS_ParReadWrite_2 : bExecute	
C00843/114	LS_ParReadWrite_2 : bReadWrite	
C00843/115	LS_ParReadWrite_3 : bExecute	
C00843/116	LS_ParReadWrite_3 : bReadWrite	
C00843/117	LS_ParReadWrite_4 : bExecute	
C00843/118	LS_ParReadWrite_4 : bReadWrite	

Parameter Name: C00843 Binary inputs I/O level		Data type: UNSIGNED_8 Index: 23732 _d = 5CB4 _h
C00843/119	LS_ParReadWrite_5 : bExecute	
C00843/120	LS_ParReadWrite_5 : bReadWrite	
C00843/121	LS_ParReadWrite_6 : bExecute	
C00843/122	LS_ParReadWrite_6 : bReadWrite	
C00843/123	LS_WriteParamList : bExecute	
C00843/124	LS_WriteParamList : bSelectWriteValue_1	
C00843/125	LS_WriteParamList : bSelectWriteValue_2	
C00843/126	LS_CANManagement : bResetNode	
C00843/127	LS_CANManagement : bReInitCAN	
C00843/128	LS_DigitalInput : bPosIn12_Load	
C00843/129	Reserved	
C00843/130	Reserved	
C00843/131	Reserved	
C00843/132	Reserved	
C00843/133	Reserved	
C00843/134	Reserved	
C00843/135	Reserved	
C00843/136	Reserved	
C00843/137	Reserved	
C00843/138	Reserved	
C00843/139	Reserved	
C00843/140	Reserved	
C00843/141	Reserved	
C00843/142	Reserved	
C00843/143	Reserved	
C00843/144	Reserved	
C00843/145	Reserved	
C00843/146	Reserved	
C00843/147	LS_TouchProbe : bDisableTPDigIn3	
C00843/148	LS_TouchProbe : bDisableTPDigIn4	
C00843/149	LS_TouchProbe : bDisableTPDigIn5	
C00843/150	LS_TouchProbe : bDisableTPDigIn6	
C00843/151	LS_TouchProbe : bDisableTPDigIn7	
C00843/152	LS_TouchProbe : bDisableTPDigIn3_Rising	
C00843/153	LS_TouchProbe : bDisableTPDigIn3_Falling	
C00843/154	LS_TouchProbe : bDisableTPDigIn4_Rising	
C00843/155	LS_TouchProbe : bDisableTPDigIn4_Falling	
C00843/156	LS_TouchProbe : bDisableTPDigIn5_Rising	
C00843/157	LS_TouchProbe : bDisableTPDigIn5_Falling	
C00843/158	LS_TouchProbe : bDisableTPDigIn3Window	
C00843/159	LS_TouchProbe : bDisableTPDigIn4Window	
C00843/160	LS_TouchProbe : bDisableTPDigIn5Window	
C00843/161	LS_AxisBusIO : bSetFail	
C00843/162	LS_AxisBusIO : bResetFail	

Parameter Name: C00843 Binary inputs I/O level		Data type: UNSIGNED 8 Index: 23732 _d = 5CB4 _h
C00843/163	Reserved	
C00843/164	LS_MultiEncoder : bSetRef	
C00843/165	LS_RetainData : bSetRetain_1	
C00843/166	LS_RetainData : bSetRetain_2	
C00843/167	LS_RetainData : bSetRetain_3	
C00843/168	LS_RetainData : bLoadParams	
C00843/169	LS_RetainData : bIn1	
C00843/170	LS_RetainData : bIn2	
C00843/171	LS_RetainData : bIn3	
C00843/172	LS_RetainData : bIn4	
C00843/173	LS_AxisBusAux : bReadWrite	
C00843/174	LS_AxisBusAux : bExecute	
C00843/175	LS_AxisBusAux : bStop	
C00843/176	LS_DigitalOutput : bUserLED	
C00843/177	LS_TouchProbe : bDisableTPEncoderWindow	
C00843/178	LS_TouchProbe : bDisableTPResolverWindow	
C00843/179	LS_TouchProbe : bDisableTPEncoder	
C00843/180	LS_TouchProbe : bDisableTPResolver	
C00843/181	LS_DFOut : bSynRdy	
C00843/182	Reserved	
C00843/183	Reserved	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00844

Parameter Name: C00844 32-bit inputs I/O level [incr]			Data type: INTEGER_32 Index: 23731 _d = 5CB3 _h
Display of 32-bit input values of different I/O level blocks in [increments]			
Display range (min. value unit max. value)			
-2147483647	Incr.	2147483647	
Subcodes			Info
C00844/1			LS_DisFree_p : dnDis1_p
C00844/2			LS_DisFree_p : dnDis2_p
C00844/3			LS_DisFree_p : dnDis3_p
C00844/4			LS_DisFree_p : dnDis4_p
C00844/5			LS_DisFree_p : dnDis5_p
C00844/6			LS_DisFree_p : dnDis6_p
C00844/7			LS_DisFree_p : dnDis7_p
C00844/8			LS_DisFree_p : dnDis8_p
C00844/9			LP_CanOut1 : dnOut34_p
C00844/10			LP_CanOut2 : dnOut34_p
C00844/11			LP_CanOut3 : dnOut34_p
C00844/12			LP_MciOut : dnOut34_p
C00844/13			LS_DigitalInput : dnPosIn12_Set_p
C00844/14			Reserved
C00844/15			Reserved
C00844/16			LS_RetainData : dnIn1
C00844/17			LS_RetainData : dnIn2
C00844/18			LS_RetainData : dnIn3
C00844/19			LS_RetainData : dnIn4
C00844/20			LS_AxisBusOut : dnLine12
C00844/21			LS_AxisBusOut : dnCas12
C00844/22			LS_AxisBusOut : dnCas34
C00844/23			LS_AxisBusAux : dnAuxOut12
C00844/24			LS_AxisBusAux : dnAuxOut34
C00844/25			LP_CanOut4 : dnOut34_p
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00866

Parameter Name: C00866 CAN input words			Data type: UNSIGNED_16 Index: 23709 _d = 5C9D _h			
Display of the 16 bit input values of the CAN interface						
▶ "CAN on board" system bus						
Display area (min. hex value max. hex value)						
0x0000		0xFFFF				
Value is bit-coded:						
Bit 0		Active				
...		...				
Bit 15		Active				
Subcodes			Info			
C00866/1			LP_CanIn1 : wCtrl			
C00866/2			LP_CanIn1 : wIn2			
C00866/3			LP_CanIn1 : wIn3			
C00866/4			LP_CanIn1 : wIn4			
C00866/5			LP_CanIn2 : wIn1			
C00866/6			LP_CanIn2 : wIn2			
C00866/7			LP_CanIn2 : wIn3			
C00866/8			LP_CanIn2 : wIn4			
C00866/9			LP_CanIn3 : wIn1			
C00866/10			LP_CanIn3 : wIn2			
C00866/11			LP_CanIn3 : wIn3			
C00866/12			LP_CanIn3 : wIn4			
C00866/13			LP_CanIn4 : wIn1 • From version 15.00.00			
C00866/14			LP_CanIn4 : wIn2 • From version 15.00.00			
C00866/15			LP_CanIn4 : wIn3 • From version 15.00.00			
C00866/16			LP_CanIn4 : wIn4 • From version 15.00.00			
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT						

C00868

Parameter Name: C00868 CAN output words		Data type: UNSIGNED_16 Index: 23707 _d = 5C9B _h	
Display of the 16 bit output values of the CAN interface			
▶ "CAN on board" system bus			
Display area (min. hex value max. hex value)			
0x0000			0xFFFF
Value is bit-coded:			
Bit 0	Active		
Bit 1	Active		
Bit 2	Active		
Bit 3	Active		
Bit 4	Active		
Bit 5	Active		
Bit 6	Active		
Bit 7	Active		
Bit 8	Active		
Bit 9	Active		
Bit 10	Active		
Bit 11	Active		
Bit 12	Active		
Bit 13	Active		
Bit 14	Active		
Bit 15	Active		
Subcodes		Info	
C00868/1		LP_CanOut1 : wState	
C00868/2		LP_CanOut1 : wOut2	
C00868/3		LP_CanOut1 : wOut3	
C00868/4		LP_CanOut1 : wOut4	
C00868/5		LP_CanOut2 : wOut1	
C00868/6		LP_CanOut2 : wOut2	
C00868/7		LP_CanOut2 : wOut3	
C00868/8		LP_CanOut2 : wOut4	
C00868/9		LP_CanOut3 : wOut1	
C00868/10		LP_CanOut3 : wOut2	
C00868/11		LP_CanOut3 : wOut3	
C00868/12		LP_CanOut3 : wOut4	
C00868/13		LP_CanOut4 : wOut1 • From version 15.00.00	
C00868/14		LP_CanOut4 : wOut2 • From version 15.00.00	
C00868/15		LP_CanOut4 : wOut3 • From version 15.00.00	
C00868/16		LP_CanOut4 : wOut4 • From version 15.00.00	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT			

C00876

Parameter Name: C00876 MCI input words			Data type: UNSIGNED_16 Index: 23699 _d = 5C93 _h		
Display of the 16 bit input values of the communication module					
Display area (min. hex value max. hex value)					
0x0000		0xFFFF			
Value is bit-coded:					
Bit 0	Active				
...	...				
Bit 15	Active				
Subcodes			Info		
C00876/1			LP_McIln : wCtrl		
C00876/2			LP_McIln : wIn2		
C00876/3			LP_McIln : wIn3		
C00876/4			LP_McIln : wIn4		
C00876/5			LP_McIln : wIn5		
C00876/6			LP_McIln : wIn6		
C00876/7			LP_McIln : wIn7		
C00876/8			LP_McIln : wIn8		
C00876/9			LP_McIln : wIn9		
C00876/10			LP_McIln : wIn10		
C00876/11			LP_McIln : wIn11		
C00876/12			LP_McIln : wIn12		
C00876/13			LP_McIln : wIn13		
C00876/14			LP_McIln : wIn14		
C00876/15			LP_McIln : wIn15		
C00876/16			LP_McIln : wIn16		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT					

C00877

Parameter | Name: C00877 | MCI output words

Data type: UNSIGNED_16
Index: 23698_d = 5C92_h

Display of the 16 bit output values of the communication module

Display area (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		
Bit 0	Active	
...	...	
Bit 15	Active	
Subcodes		Info
C00877/1		LP_MciOut : wState
C00877/2		LP_MciOut : wOut2
C00877/3		LP_MciOut : wOut3
C00877/4		LP_MciOut : wOut4
C00877/5		LP_MciOut : wOut5
C00877/6		LP_MciOut : wOut6
C00877/7		LP_MciOut : wOut7
C00877/8		LP_MciOut : wOut8
C00877/9		LP_MciOut : wOut9
C00877/10		LP_MciOut : wOut10
C00877/11		LP_MciOut : wOut11
C00877/12		LP_MciOut : wOut12
C00877/13		LP_MciOut : wOut13
C00877/14		LP_MciOut : wOut14
C00877/15		LP_MciOut : wOut15
C00877/16		LP_MciOut : wOut16
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C00890

Parameter Name: C00890 MCI_InOut: Inversion		Data type: UNSIGNED_16 Index: 23685 _d = 5C85 _h	
This parameter serves to invert the control/status bits of the MCI port blocks.			
Setting range (min. hex value max. hex value)			
0x0000			
Value is bit-coded:		Info	
Bit 0	Active	Bit set = inversion active	
...	...		
Bit 15	Active		
Subcodes	Lenze setting	Info	
C00890/1	0x0000	LP_MciIn : Invert.Ctrl_B0..15	
C00890/2	0x0000	LP_MciOut : Invert.State_B0..15	
C00890/3	0x0000	LP_MciIn : Invert.In2_B0..15	
C00890/4	0x0000	LP_MciOut : Invert.Out2_B0..15	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT			

C00905

Parameter | Name:

C00905 | Motor phase direction of rotation

Data type: UNSIGNED_8

Index: 23670_d = 5C76_h

To correct such misconnected motor phases, the rotating field of the controller's output can be reversed by selecting "1: Inverted". In this case, a phase will be reversed at the output of the inverter.

Note:

Up to and including version 02.00.00, this function may only be activated for the following motor control types:

- V/f characteristic control (VFCplus)
- Energy-saving V/f characteristic control (VFCplusEco)

For all other motor control types, this function must not be activated because the set control mode would not work in that case!

From version 12.00.00, this function may be activated for all motor control types with the exception of the ones for synchronous motor.

The activation of this function does not affect the control types for synchronous motor since these control types require an in-phase connection of the synchronous motor.

Selection list (Lenze setting printed in bold)	
0	not inverted
1	inverted

☒ Read access
 ☒ Write access
 ☒ CINH
 ☐ PLC STOP
 ☐ No transfer
 ☐ COM
 ☐ MOT

Scaling factor: 1

C00909

Parameter Name: C00909 Speed limitation			Data type: INTEGER_16 Index: 23666 _d = 5C72 _h
Max. positive/negative speed for all motor control modes			
Setting range (min. value unit max. value)			
0.00	%	175.00	
Subcodes	Lenze setting	Info	
C00909/1	120.00 %	Max. pos. speed	
C00909/2	120.00 %	Max. neg. speed	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C00910

Parameter Name: C00910 Frequency limitation			Data type: UNSIGNED_16 Index: 23665 _d = 5C71 _h
Max. positive/negative output frequency for all motor control modes			
Setting range (min. value unit max. value)			
0	Hz	1300	
Subcodes	Lenze setting	Info	
C00910/1	1000 Hz	Max. pos. output frequency	
C00910/2	1000 Hz	Max. neg. output frequency	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00915

Parameter Name: C00915 Motor cable length			Data type: UNSIGNED_16 Index: 23660 _d = 5C6C _h
Single motor cable length for calculating the motor cable resistance • The calculated motor cable resistance is displayed in C00917 .			
Setting range (min. value unit max. value)			Lenze setting
0.0	m	1000.0	5.0 m
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10			

C00916

Parameter Name: C00916 Motor cable cross-section			Data type: UNSIGNED_16 Index: 23659 _d = 5C6B _h
Motor cable cross-section of a phase/cable for calculating the motor cable resistance • The calculated motor cable resistance is displayed in C00917 .			
Setting range (min. value unit max. value)			Lenze setting
0.50	mm ²	100.00	6.00 mm²
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C00917

Parameter Name: C00917 Motor cable resistance			Data type: UNSIGNED_16 Index: 23658 _d = 5C6A _h
Display of the motor cable resistance of a motor cable phase • The motor cable resistance is calculated from the motor cable length set in C00915 and the motor cable cross-section set in C00916 .			
Display range (min. value unit max. value)			
0	mOhm	64000	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00918

Parameter Name: C00918 SC: Start motor magnetising current			Data type: UNSIGNED_8 Index: 23657 _d = 5C69 _h
If the servo control (SC) mode is selected and the controller is enabled, the speed setpoint for motor control will only be enabled when the motor magnetising current has reached the threshold value set here. • The adjustable percentage threshold value refers to the rated magnetising current (C00095).			
Setting range (min. value unit max. value)			Lenze setting
0	%	90	87 %
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00919

Parameter Name: C00919 Moment of inertia from load			Data type: UNSIGNED_32 Index: 23656 _d = 5C68 _h		
From version 12.00.00					
In order to take account of mass inertias changing during the process (e.g. reels) when optimising the response to setpoint changes, the maximum value of the changing moment of inertia must be set here. The process signal <i>nInertiaAdapt_a</i> of the LS_MotorInterface SB can then be used in the process to dynamically control what percentage of it is to be taken into account for the setpoint feedforward control.					
Setting range (min. value unit max. value)					
0.00	kg cm^2	6000000.00			
Subcodes	Lenze setting		Info		
C00919/1	0.00 kg cm^2		Load moment of inertia		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C00922

Parameter Name: C00922 ICM_DiagnosticCounter		Data type: UNSIGNED_16 Index: 23653 _d = 5C65 _h	
This code is for device-internal use only and must not be written to by the user!			

C00925

Parameter Name: C00925 LS_Resolver: Number of pole pairs			Data type: UNSIGNED_8 Index: 23650 _d = 5C62 _h	
<div>► Encoder/feedback system</div>				
Setting range (min. value unit max. value)			Lenze setting	
1		10	1	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1				

C00926

Parameter Name: C00926 Pole position			Data type: INTEGER_16 Index: 23649 _d = 5C61 _h
<div>▸ Encoder/feedback system</div>			
Setting range (min. value unit max. value)			
-179.9	°		
Subcodes	Lenze setting	Info	
C00926/1	-90.0 °	LS_Resolver : Pole position	
C00926/2	0.0 °	LS_MultiEncoder : Pole position	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10</div>			

C00927

Parameter Name: C00927 Motor rotor position			Data type: UNSIGNED_16 Index: 23648 _d = 5C60 _h	
<div>▸ Encoder/feedback system</div>				
Display range (min. value unit max. value)				
0		2047		
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1</div>				

C00937

Parameter Name: C00937 Field-oriented motor currents			Data type: INTEGER_16 Index: 23638 _d = 5C56 _h		
From version 02.00.00					
<div>► Field weakening for synchronous motors</div>					
Display range (min. value unit max. value)					
-320.00	A	320.00			
Subcodes			Info		
C00937/1			Field-producing current		
C00937/2			Torque-producing current		
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 100</div></div>					

C00938

Parameter Name: C00938 PSM: Maximum motor current field weakening			Data type: UNSIGNED_16 Index: 23637 _d = 5C55 _h		
From version 02.00.00					
▶ Field weakening for synchronous motors					
Setting range (min. value unit max. value)			Lenze setting		
0.00	%	500.00	30.00 %		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C00939

Parameter Name: C00939 Ultimate motor current			Data type: UNSIGNED_16 Index: 23636 _d = 5C54 _h		
Setting range (min. value unit max. value)			Lenze setting		
0.0	A	3000.0	3000.0 A		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C00940

Parameter Name: C00940 L_ConvW numerator			Data type: INTEGER_16 Index: 23635 _d = 5C53 _h		
Setting range (min. value unit max. value)					
-32767		32767			
Subcodes	Lenze setting		Info		
C00940/1	1		L_ConvW 1 : Numerator		
C00940/2	1		L_ConvW 2 : Numerator		
C00940/3	1		L_ConvW 3 : Numerator		
C00940/4	1		L_ConvW 4 : Numerator		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00941

Parameter Name: C00941 L_ConvW denominator			Data type: INTEGER_16 Index: 23634 _d = 5C52 _h
Setting range (min. value unit max. value)			
1		32767	
Subcodes	Lenze setting	Info	
C00941/1	1	L_ConvW 1 : Denominator	
C00941/2	1	L_ConvW 2 : Denominator	
C00941/3	1	L_ConvW 3 : Denominator	
C00941/4	1	L_ConvW 4 : Denominator	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00942

Parameter Name: C00942 L_ConvW conversion method		Data type: UNSIGNED_8 Index: 23633 _d = 5C51 _h
Selection list		
0	no conversion	
1	from [%] into [incr./ms]	
2	from [incr./ms] into [%]	
3	Factors signed	
4	Factors unsigned	
Subcodes	Lenze setting	Info
C00942/1	0: No conversion	L_ConvW 1 : Conversion method
C00942/2	0: No conversion	L_ConvW 2 : Conversion method
C00942/3	0: No conversion	L_ConvW 3 : Conversion method
C00942/4	0: No conversion	L_ConvW 4 : Conversion method
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00950

Parameter Name: C00950 L_Interpolator_1: Activation FB functions		Data type: UNSIGNED_8 Index: 23625 _d = 5C49 _h
The L_Interpolator_1 FB: Activation of signal interpolation and signal monitoring		
Selection list		
0	Off	
1	On	
Subcodes	Lenze setting	Info
C00950/1	0: Off	L_Interpolator_1 : Signal interpolation
C00950/2	0: Off	L_Interpolator_1 : Signal monitoring
C00950/3	0: Off	L_Interpolator_1 : Master value monitoring
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00951

Parameter Name: C00951 L_Interpolator_1: No. of interpolation steps			Data type: UNSIGNED_16 Index: 23624 _d = 5C48 _h
The L_Interpolator_1 FB: No. of interpolation steps			
Setting range (min. value unit max. value)			Lenze setting
0		65535	1
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00952

Parameter Name: C00952 L_Interpolator_1: Limit value - error cycles			Data type: UNSIGNED_16 Index: 23623 _d = 5C47 _h
The L_Interpolator_1 FB: Limit value for missing data telegrams			
Setting range (min. value unit max. value)			Lenze setting
0		65535	5
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00953

Parameter Name: C00953 L_Interpolator_1: Speed-up			Data type: UNSIGNED_8 Index: 23622 _d = 5C46 _h
FB L_Interpolator_1 : Limitation of the number of correction increments per cycle (speed-up)			
Setting range (min. value unit max. value)			Lenze setting
0		100	0
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00959

Parameter Name: C00959 L_Curve: Current output value			Data type: INTEGER_16 Index: 23616 _d = 5C40 _h
From version 02.00.00			
FB L_Curve_1 : Display of the current output value <i>nOut_a</i>			
Display range (min. value unit max. value)			
-199.99	%	199.99	
Subcodes			Info
C00959/1			L_Curve_1 : Current output value
C00959/2			L_Curve_2 : Current output value
C00959/3			L_Curve_3 : Current output value
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C00960

Parameter Name: C00960 L_Curve_1: Selected curve type		Data type: UNSIGNED_8 Index: 23615 _d = 5C3F _h
FB L_Curve_1 : Selected curve type		
Selection list		
0	Out = 0	
1	Out = In	
2	Out = f(In)	
3	Out = f(table)	
Subcodes	Lenze setting	Info
C00960/1	1: Out = In	L_Curve_1 : Function
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C00961

Parameter Name: C00961 L_Curve_1: Input limitation		Data type: INTEGER_16 Index: 23614 _d = 5C3E _h
FB L_Curve_1 : Upper and lower limit for input value		
Setting range (min. value unit max. value)		
-199.99	%	199.99
Subcodes	Lenze setting	Info
C00961/1	199.99 %	L_Curve_1 : Max. input
C00961/2	-199.99 %	L_Curve_1 : Min. input
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100		

C00963

Parameter Name: C00963 L_Curve_1: Table X-values			Data type: INTEGER_16 Index: 23612 _d = 5C3C _h
FB L_Curve_1 : X-values for characteristic function			
Setting range (min. value unit max. value)			
-32767		32767	
Subcodes	Lenze setting	Info	
C00963/1	0	X values 1 ... 32 for characteristic function	
C00963/...			
C00963/32			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00964

Parameter Name: C00964 L_Curve_1: Table Y-values			Data type: INTEGER_16 Index: 23611 _d = 5C3B _h
FB L_Curve_1 : Y-value for characteristic function			
Setting range (min. value unit max. value)			
-32767		32767	
Subcodes	Lenze setting	Info	
C00964/1	0	Y values 1 ... 32 for characteristic function	
C00964/...			
C00964/32			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C00965

Parameter Name: C00965 Max. motor speed			Data type: UNSIGNED_16 Index: 23610 _d = 5C3A _h
When the drive reaches the motor speed set here: <ul style="list-style-type: none"> • The "Fault" error response takes place, i.e. the motor is shut down immediately. • The error message "oS2: Max. motor speed reached" is entered into the logbook. 			
Setting range (min. value unit max. value)		Lenze setting	
50	rpm	65000	60000 rpm
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00966

Parameter Name: C00966 VFC: Time const. slip comp.			Data type: UNSIGNED_16 Index: 23609 _d = 5C39 _h
Filter time constant of the slip compensation for V/f characteristic control (VFCplus) <ul style="list-style-type: none"> • The time constant of slip compensation serves to specify the dynamics of slip compensation for V/f characteristic control without feedback. • The lower the selected time constant, the higher the dynamic performance of the slip compensation. 			
Setting range (min. value unit max. value)		Lenze setting	
1	ms	6000	100 ms
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C00967

Parameter | Name: **C00967 | VFC: Frequency interpol. point n**

Data type: INTEGER_16
Index: 23608_d = 5C38_h

Selection of the interpolation points (frequency values) for the V/f characteristic control (**VFCplus**) with user-definable V/f characteristic (**C00006** = "10")

Setting range (min. value unit max. value)		
-2600.0	Hz	2600.0
Subcodes	Lenze setting	Info
C00967/1	-50.0 Hz	VFC : Frequency interpol. point 1
C00967/2	-40.0 Hz	VFC : Frequency interpol. point 2
C00967/3	-30.0 Hz	VFC : Frequency interpol. point 3
C00967/4	-20.0 Hz	VFC : Frequency interpol. point 4
C00967/5	-10.0 Hz	VFC : Frequency interpol. point 5
C00967/6	0.0 Hz	VFC : Frequency interpol. point 6
C00967/7	10.0 Hz	VFC : Frequency interpol. point 7
C00967/8	20.0 Hz	VFC : Frequency interpol. point 8
C00967/9	30.0 Hz	VFC : Frequency interpol. point 9
C00967/10	40.0 Hz	VFC : Frequency interpol. point 10
C00967/11	50.0 Hz	VFC : Frequency interpol. point 11

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☒ MOT Scaling factor: 10

C00968

Parameter Name: C00968 VFC: Voltage interpol. point n			Data type: UNSIGNED_16 Index: 23607 _d = 5C37 _h
Selection of the interpolation points (voltage values) for the V/f characteristic control (VFCplus) with user-definable V/f characteristic (C00006 = "10")			
Setting range (min. value unit max. value)			
0.00	V	600.00	
Subcodes	Lenze setting	Info	
C00968/1	400.00 V	VFC : Voltage interpol. point 1	
C00968/2	320.00 V	VFC : Voltage interpol. point 2	
C00968/3	240.00 V	VFC : Voltage interpol. point 3	
C00968/4	160.00 V	VFC : Voltage interpol. point 4	
C00968/5	80.00 V	VFC : Voltage interpol. point 5	
C00968/6	0.00 V	VFC : Voltage interpol. point 6	
C00968/7	80.00 V	VFC : Voltage interpol. point 7	
C00968/8	160.00 V	VFC : Voltage interpol. point 8	
C00968/9	240.00 V	VFC : Voltage interpol. point 9	
C00968/10	320.00 V	VFC : Voltage interpol. point 10	
C00968/11	400.00 V	VFC : Voltage interpol. point 11	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C00969

Parameter Name: C00969 Motorparameter			Data type: UNSIGNED_8 Index: 23606 _d = 5C36 _h		
From version 12.00.00					
Display range (min. value unit max. value)					
1		255			
Subcodes			Info		
C00969/1			Motor - number of pole pairs		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00971

Parameter Name: C00971 VFC: Limitation V/f +encoder			Data type: UNSIGNED_16 Index: 23604 _d = 5C34 _h		
Limitation of the output frequency of the slip regulator and limitation of the injected stator frequency for the V/f control (VFCplus+encoder)					
Setting range (min. value unit max. value)					
0.00	Hz	100.00			
Subcodes	Lenze setting		Info		
C00971/1	10.00 Hz		Maximum output / correcting variable of the slip regulator <ul style="list-style-type: none">The slip regulator output is limited to the value set here in motor/generator mode.It is recommended to select 1 to 3 times the slip frequency of the motor as limit value.		
C00971/2	100.00 Hz		Maximum frequency deviation between the rotational frequency (speed) measured mechanically by the encoder and the injected stator frequency. <ul style="list-style-type: none">A limitation may e.g. avoid overcurrent interruption when traversing to a fixed limit stop.		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C00972

Parameter Name: C00972 VFC: Vp V/f +encoder			Data type: UNSIGNED_16 Index: 23603 _d = 5C33 _h		
Proportional gain of the slip regulator for V/f control (VFCplus+encoder) <ul style="list-style-type: none">• The gain must be selected depending on the drive system and the sensor resolution (range: 0.005 ... 5).• A high gain requires a high number of increments.					
Setting range (min. value unit max. value)			Lenze setting		
0.000	Hz/Hz	64.000	0.100 Hz/Hz		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT			Scaling factor: 1000		

C00973

Parameter Name: C00973 VFC: Ti V/f +encoder			Data type: UNSIGNED_16 Index: 23602 _d = 5C32 _h		
Integral time constant of the slip regulator for V/f control (VFCplus+encoder) <ul style="list-style-type: none">In general, the time constant should be selected in a range of 20 ms (high dynamics) to 200 (low dynamics).					
Setting range (min. value unit max. value)			Lenze setting		
0.0	ms	6000.0	100.0 ms		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C00975

Parameter Name: C00975 VFC-ECO: Vp CosPhi controller			Data type: UNSIGNED_16 Index: 23600 _d = 5C30 _h		
Proportional gain of the Cos-Phi controller for energy-saving V/f characteristic control (VFCplusEco)					
Setting range (min. value unit max. value)			Lenze setting		
0.000	Hz/Hz	64.000	0.500 Hz/Hz		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1000					

C00976

Parameter Name: C00976 VFC-ECO: Ti CosPhi controller			Data type: UNSIGNED_16 Index: 23599 _d = 5C2F _h		
Reset time of the Cos-Phi controller for energy-saving V/f characteristic control (VFCplusEco)					
Setting range (min. value unit max. value)			Lenze setting		
0.0	ms	6000.0	200.0 ms		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C00977

Parameter Name: C00977 VFC-ECO: Minimum voltage V/f			Data type: INTEGER_16 Index: 23598 _d = 5C2E _h		
Minimum voltage V/f of the Cos-Phi controller for energy-saving V/f characteristic control (VFCplusEco)					
Setting range (min. value unit max. value)			Lenze setting		
20.00	%	100.00	20.00 %		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C00978

Parameter Name: C00978 VFC-ECO: Voltage reduction			Data type: INTEGER_16 Index: 23597 _d = 5C2D _h		
Display of the voltage reduction with energy-saving V/f characteristic control (VFCplusEco)					
Display range (min. value unit max. value)					
-1000	V	1000			
<input checked="" type="checkbox"/> Read access			<input type="checkbox"/> Write access		
<input type="checkbox"/> CINH			<input type="checkbox"/> PLC STOP		
<input type="checkbox"/> No transfer			<input type="checkbox"/> COM		
<input type="checkbox"/> MOT			Scaling factor: 1		

C00979

Parameter Name: C00979 Cosine phi			Data type: INTEGER_16 Index: 23596 _d = 5C2C _h		
Display of the cosφ setpoint and actual value with energy-saving V/f characteristic control (VFCplusEco)					
Display range (min. value unit max. value)					
-1.00		1.00			
Subcodes			Info		
C00979/1			Cosine phi act		
C00979/2			Cosine phi set		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00980

Parameter Name: C00980 Output power			Data type: INTEGER_32 Index: 23595 _d = 5C2B _h		
Display parameter for an energy analysis in the prevailing application. From this, decisions can be deduced whether a measure for energy optimisation is economic.					
Display range (min. value unit max. value)					
-32.000	kW	32.000			
Subcodes			Info		
C00980/1			Active output power		
C00980/2			Apparent output power		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C00981

Parameter Name: C00981 Energy display			Data type: INTEGER_32 Index: 23594 _d = 5C2A _h		
Display parameter for an energy analysis in the prevailing application. From this, decisions can be deduced whether a measure for energy optimisation is economic. <ul style="list-style-type: none">• The values are saved to the device by switching off the mains and cannot be reset.					
Display range (min. value unit max. value)					
0.00	kWh	21474836.47			
Subcodes			Info		
C00981/1			Output energy in motor mode		
C00981/2			Output energy in generator mode		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00982

Parameter Name: C00982 VFC-ECO: Voltage reduction ramp			Data type: UNSIGNED_8 Index: 23593 _d = 5C29 _h		
Voltage ramp for cancelling V-Sub with energy-saving V/f characteristic control (VFCplusEco)					
Setting range (min. value unit max. value)			Lenze setting		
0.0	s	5.0	0.8 s		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C00983

Parameter Name: C00983 Delay			Data type: UNSIGNED_16 Index: 23592 _d = 5C28 _h		
Setting range (min. value unit max. value)					
0	ms	4000			
Subcodes	Lenze setting		Info		
C00983/1	50 ms		Delay I _{max}		
C00983/2	1000 ms		VFC : Voltage ramp after overvoltage oU • From version 15.00.00		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C00985

Parameter Name:			Data type: INTEGER_16		
C00985 SLVC: Field current controller gain			Index: 23590 _d = 5C26 _h		
Gain of the direct-axis current difference (Id) between setpoint and actual current for the voltage model of the sensorless vector control (SLVC)					
• The gain should be selected in a range of 0 ...1 %.					
Setting range (min. value unit max. value)			Lenze setting		
0.00	%	20.00	0.50 %		
<input checked="" type="checkbox"/> Read access			<input checked="" type="checkbox"/> Write access		
<input type="checkbox"/> CINH			<input type="checkbox"/> PLC STOP		
<input type="checkbox"/> No transfer			<input type="checkbox"/> COM		
<input checked="" type="checkbox"/> MOT			Scaling factor: 100		

C00986

Parameter Name: C00986 SLVC: Cross current controller gain				Data type: INTEGER_16 Index: 23589 _d = 5C25 _h	
Gain of the cross current difference for the voltage model of the sensorless vector control (SLVC)					
Setting range (min. value unit max. value)			Lenze setting		
0.00	%	20.00	0.00 %		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C00987

Parameter Name: C00987 Inverter motor brake: nAdd			Data type: INTEGER_16 Index: 23588 _d = 5C24 _h		
Speed lift which is connected in pulses to the brake rampe when the motor is braked.					
► Inverter motor brake					
Setting range (min. value unit max. value)			Lenze setting		
0	rpm	1000	80 rpm		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C00988

Parameter Name: C00988 Inverter motor brake: PT1 filter time			Data type: INTEGER_16 Index: 23587 _d = 5C23 _h		
PT1 filter time for smoothing the speed lift which is added in pulses (C00987)					
► Inverter motor brake					
Setting range (min. value unit max. value)			Lenze setting		
0.0	ms	100.0	0.0 ms		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10					

C00989

Parameter Name: C00989 Restart on the fly: Flying restart frequency fd_add			Data type: INTEGER_16 Index: 23586 _d = 5C22 _h		
From version 15.00.00					
<div>► Flying restart fct.</div>					
Setting range (min. value unit max. value)					
0.00	Hz	5.00			
Subcodes	Lenze setting		Info		
C00989/1	0.00 Hz		Restart on the fly: Flying restart frequency fd_add		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT <div>Scaling factor: 100</div></div>					

C00990

Parameter Name: C00990 Flying restart fct.: Activation		Data type: UNSIGNED_8 Index: 23585 _d = 5C21 _h
Switch on/activate flying restart circuit for non-feedback drive systems		
▶ Flying restart fct.		
Selection list (Lenze setting printed in bold)		
0	Off	
1	On	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input checked="" type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00991

Parameter Name: C00991 Flying restart fct.: Process		Data type: UNSIGNED_16 Index: 23584 _d = 5C20 _h
Selection of the starting value and the speed search range for the flying restart function		
▶ Flying restart fct.		
Selection list (Lenze setting printed in bold)		Info
0	0...+n Start: +10 Hz	Search positive speed range (0 ... +n) with a start frequency of +10 Hz
1	-n...0 Start: -10 Hz	Search negative speed range (-n ... 0) with a start frequency of -10 Hz
2	-n...+n Start: +10 Hz	Search negative and positive speed range (-n ... n) with a start frequency of +10 Hz
3	-n...+n Start: -10 Hz	Search negative and positive speed range (-n ... n) with a start frequency of -10 Hz
4	-n...+n Start: Cx992	Search the negative and positive speed range (-n ... n) with the start frequency set in C00992
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00992

Parameter Name: C00992 Flying restart fct.: Start frequency		Data type: INTEGER_16 Index: 23583 _d = 5C1F _h
Manual selection of the starting value for the flying restart function		
• Only active if C00991 = 4		
▶ Flying restart fct.		
Setting range (min. value unit max. value)		Lenze setting
-200	Hz	200
		10 Hz
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C00993

Parameter Name: C00993 Flying restart fct: Int. time		Data type: UNSIGNED_16 Index: 23582 _d = 5C1E _h
Time constant of the angular difference controller of the flying restart function		
• The time constant is to amount between 60 ... 300 ms.		
▶ Flying restart fct.		
Setting range (min. value unit max. value)		Lenze setting
0.0	ms	6000.0
		300.0 ms
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10		

C00994

Parameter Name: C00994 Flying restart fct.: Current			Data type: INTEGER_16 Index: 23581 _d = 5C1D _h		
Current to be injected during the flying restart process <ul style="list-style-type: none">• 100 % ≡ rated motor current (C00088).• The flying restart current should amount to 10 ... 25 % of the rated motor current.					
<div>Flying restart fct.</div>					
Setting range (min. value unit max. value)			Lenze setting		
0.00	%	100.00	25.00 %		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100</div>					

C00995

Parameter Name: C00995 SLPSM: Controlled current setpoint			Data type: UNSIGNED_16 Index: 23580 _d = 5C1C _h		
▶ Sensorless control for synchronous motor					
Setting range (min. value unit max. value)					
5.00	%	400.00			
Subcodes	Lenze setting		Info		
C00995/1	100.00 %		SLPSM : Controlled accelerating current		
C00995/2	20.00 %		SLPSM : Controlled standstill current		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C00996

Parameter Name: C00996 SLPSM: Switching speed			Data type: INTEGER_16 Index: 23579 _d = 5C1B _h		
▶ Sensorless control for synchronous motor					
Setting range (min. value unit max. value)					
0.00	%	100.00			
Subcodes	Lenze setting	Info			
C00996/1	13.00 %	SLPSM : Switching speed, closed-loop control			
C00996/2	8.00 %	SLPSM : Switching speed, open-loop control			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00997

Parameter Name: C00997 SLPSM: Filter cutoff frequency			Data type: INTEGER_16 Index: 23578 _d = 5C1A _h		
▶ Sensorless control for synchronous motor					
Setting range (min. value unit max. value)			Lenze setting		
0.00	%	100.00	5.00 %		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C00998

Parameter Name: C00998 SLPSM: Filter time rotor position			Data type: INTEGER_16 Index: 23577 _d = 5C19 _h		
▸ Sensorless control for synchronous motor					
Setting range (min. value unit max. value)					
0.5	ms	20.0			
Subcodes	Lenze setting	Info			
C00998/1	3.0 ms	SLPSM : Filter time rotor position			
C00998/2	5.0 ms	SLPSM : Filter time actual speed value			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C00999

Parameter Name: C00999 SLPSM: PLL gain			Data type: INTEGER_16 Index: 23576 _d = 5C18 _h		
▸ Sensorless control for synchronous motor					
Setting range (min. value unit max. value)			Lenze setting		
0	%	1000	400 %		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C01000

Parameter Name: C01000 MCTRL: Status		Data type: UNSIGNED_16 Index: 23575 _d = 5C17 _h
Display area (min. hex value max. hex value)		
0x0000	0xFFFF	
Value is bit-coded:		Info
Bit 0	SLPSM: Speed closed-loop control	1 ≡ The sensorless control for synchronous motors is in the closed-loop controlled operation ($ n_{\text{Setpoint}} > n_{\text{C00996}}$). ▶ Sensorless control for synchronous motors (SLPSM)
Bit 1	SLPSM: Speed open-loop control	From version 12.00.00 1 ≡ The sensorless control for synchronous motors is in the open-loop controlled operation ($ n_{\text{Setpoint}} > n_{\text{C00996}}$). ▶ Sensorless control for synchronous motors (SLPSM)
Bit 2	Motor ASM	From version 12.00.00 1 ≡ Set motor type is "Asynchronous motor"
Bit 3	Motor PSM	From version 12.00.00 1 ≡ Set motor type is "Synchronous motor"
Bit 4	Encoder open circuit: V/f linear active	From version 15.00.00 1 ≡ Due to an encoder open circuit, it has been internally switched to the encoderless V/f characteristic control to avoid impermissible motor movements.
Bit 5	Reserved	
Bit 6	Reserved	
Bit 7	Reserved	
Bit 8	Reserved	
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	Reserved	
Bit 15	Reserved	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT		

C01001

Parameter Name: C01001 Manual entry of motor type		Data type: UNSIGNED_8 Index: 23574 _d = 5C16 _h
From version 14.00.00		
Selection list		
0	Automatic	
1	ASM	
2	PSM	
Subcodes	Lenze setting	Info
C01001/1	0: Automatic	Manual entry of motor type
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C01010

Parameter Name: C01010 L_ArithmetikPhi 1-3: Function		Data type: UNSIGNED_8 Index: 23565 _d = 5C0D _h
Selection of the internal arithmetics		
Selection list		
0	dnOut_p = dnIn1_p	
1	dnOut_p = dnIn1_p + dnIn2_p	
2	dnOut_p = dnIn1_p - dnIn2_p	
3	dnOut_p = dnIn1_p * dnIn2_p	
4	dnOut_p = dnIn1_p / dnIn2_p	
Subcodes	Lenze setting	Info
C01010/1	0: dnOut_p = dnIn1_p	L_ArithmetikPhi 1 : Function
C01010/2	0: dnOut_p = dnIn1_p	L_ArithmetikPhi 2 : Function
C01010/3	0: dnOut_p = dnIn1_p	L_ArithmetikPhi 3 : Function
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01011

Parameter Name: C01011 L_ArithmetikPhi 4-6: Function		Data type: UNSIGNED_8 Index: 23564 _d = 5C0C _h
From version 12.00.00 Selection of the internal arithmetics		
Selection list		
0	dnOut_p = dnIn1_p	
1	dnOut_p = dnIn1_p + dnIn2_p	
2	dnOut_p = dnIn1_p - dnIn2_p	
3	dnOut_p = dnIn1_p * dnIn2_p	
4	dnOut_p = dnIn1_p / dnIn2_p	
Subcodes	Lenze setting	Info
C01011/1	0: dnOut_p = dnIn1_p	L_ArithmetikPhi 4 : Function
C01011/2	0: dnOut_p = dnIn1_p	L_ArithmetikPhi 5 : Function
C01011/3	0: dnOut_p = dnIn1_p	L_ArithmetikPhi 6 : Function
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01012

Parameter Name: C01012 L_PhiDiv: byDivision		Data type: INTEGER_8 Index: 23563 _d = 5C0B _h
From version 12.00.00		
Setting range (min. value unit max. value)		
-31		
		31
Subcodes	Lenze setting	Info
C01012/1	0	L_PhiDiv 1 : byDivision
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01020

Parameter Name: C01020 L_Odometer_1: Memory length		Data type: UNSIGNED_8 Index: 23555 _d = 5C03 _h
FB L_Odometer_1 : No. of measurements		
Selection list (Lenze setting printed in bold)		
1	1 measurement	
2	2 measurements	
3	3 measurements	
4	4 measurements	
5	5 measurements	
6	6 measurements	
7	7 measurements	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01021

Parameter Name: C01021 L_Odometer_1: Memory type		Data type: UNSIGNED_8 Index: 23554 _d = 5C02 _h
FB L_Odometer_1 : If "ring buffer" is selected, it is started again after the measurements set in C01020 and the old values are overwritten. Otherwise, the measurement stops.		
Selection list (Lenze setting printed in bold)		
0	No ring buffer	
1	Ring buffer	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01022

Parameter Name: C01022 L_Odometer_1: Input selection		Data type: UNSIGNED_8 Index: 23553 _d = 5C01 _h
FB L_Odometer_1 : Selection of position or speed input		
Selection list (Lenze setting printed in bold)		
0	Pos input	
1	V input	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01023

Parameter Name: C01023 L_Odometer_1: Edge selection		Data type: UNSIGNED_8 Index: 23552 _d = 5C00 _h
FB L_Odometer_1 : No. of the edge triggering the measurement		
Selection list (Lenze setting printed in bold)		
0	High edge	
1	Low edge	
2	High and low edge	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01025

Parameter Name: C01025 L_Curve_2: Selected curve type		Data type: UNSIGNED_8 Index: 23550 _d = 5BFE _h
From version 02.00.00 FB L_Curve_2 : Selected curve type		
Selection list		
0	Out = 0	
1	Out = ln	
2	Out = f(ln)	
3	Out = f(table)	
Subcodes	Lenze setting	Info
C01025/1	1: Out = ln	L_Curve_2 : Function
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01026

Parameter Name: C01026 L_Curve_2: Input limitation		Data type: INTEGER_16 Index: 23549 _d = 5BFD _h
From version 02.00.00 FB L_Curve_2 : Upper and lower limit for input value		
Setting range (min. value unit max. value)		
-199.99	%	
199.99		
Subcodes	Lenze setting	Info
C01026/1	199.99 %	L_Curve_2 : Max. input
C01026/2	-199.99 %	L_Curve_2 : Min. input
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100		

C01028

Parameter Name: C01028 L_Curve_2: Table X-values			Data type: INTEGER_16 Index: 23547 _d = 5BFB _h
From version 02.00.00 FB L_Curve_2 : X-values for characteristic function			
Setting range (min. value unit max. value)			
-32767			
Subcodes	Lenze setting	Info	
C01028/1	0	X values 1 ... 32 for characteristic function	
C01028/...			
C01028/32			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01029

Parameter Name: C01029 L_Curve_2: Table Y-values			Data type: INTEGER_16 Index: 23546 _d = 5BFA _h
From version 02.00.00 FB L_Curve_2 : Y-value for characteristic function			
Setting range (min. value unit max. value)			
-32767			
Subcodes	Lenze setting	Info	
C01029/1	0	Y values 1 ... 32 for characteristic function	
C01029/...			
C01029/32			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01030

Parameter Name: C01030 L_Curve_3: Selected curve type		Data type: UNSIGNED_8 Index: 23545 _d = 5BF9 _h
From version 02.00.00 FB L_Curve_3 : Selected curve type		
Selection list		Info
0	Out = 0	
1	Out = In	
2	Out = f(In)	
3	Out = f(table)	
4	Out = f(characteristic)	From version 12.00.00
Subcodes	Lenze setting	Info
C01030/1	1: Out = In	L_Curve_3 : Function
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01031

Parameter Name: C01031 L_Curve_3: Input limitation			Data type: INTEGER_16 Index: 23544 _d = 5BF8 _h
From version 02.00.00 FB L_Curve_3: Upper and lower limit for input value			
Setting range (min. value unit max. value)			
-199.99	%	199.99	
Subcodes	Lenze setting	Info	
C01031/1	199.99 %	L_Curve_3: Max. input	
C01031/2	-199.99 %	L_Curve_3: Min. input	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C01033

Parameter Name: C01033 L_Curve_3: Table X-values			Data type: INTEGER_16 Index: 23542 _d = 5BF6 _h
From version 02.00.00 FB L_Curve_3 : X-values for characteristic function			
Setting range (min. value unit max. value)			
-32767			
Subcodes	Lenze setting	Info	
C01033/1	0	X values 1 ... 32 for characteristic function	
C01033/...			
C01033/32			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01034

Parameter Name: C01034 L_Curve_3: Table Y-values			Data type: INTEGER_16 Index: 23541 _d = 5BF5 _h
From version 02.00.00 FB <u>L_Curve_3</u> : Y-value for characteristic function			
Setting range (min. value unit max. value)			
-32767		32767	
Subcodes	Lenze setting	Info	
C01034/1	0	Y values 1 ... 32 for characteristic function	
C01034/...			
C01034/32			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01035

Parameter Name: C01035 <u>L_Curve_3</u> : SelectCurve		Data type: UNSIGNED_16 Index: 23540 _d = 5BF4 _h
From version 12.00.00 FB <u>L_Curve_3</u> : Selection of the tensile force profile		
Selection list		Info
0	Linear tensile force profile	► Use of L_Curve_3 for tensile force characteristic
1	Linear torque characteristic	
2	Tensile force profile according to characteristic	
Subcodes	Lenze setting	Info
C01035/1	0: Linearer Zugkraftverlauf	L_Curve_3 : SelectCurve
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01040

Parameter Name: C01040 L_SRFG_1..2 linear ramp time			Data type: UNSIGNED_32 Index: 23535 _d = 5BEF _h		
Symmetrical acceleration/deceleration time for the ramp function generator					
Setting range (min. value unit max. value)					
0.001	s	999.999			
Subcodes	Lenze setting		Info		
C01040/1	100.000 s		L_SRFG_1 : linear ramp time		
C01040/2	100.000 s		L_SRFG_2 : linear ramp time		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C01041

Parameter Name: C01041 L_SRFG_1..2 S-ramp time			Data type: UNSIGNED_32 Index: 23534 _d = 5BEE _h		
S-ramp time for jerk-free acceleration					
Setting range (min. value unit max. value)					
0.001	s	50.000			
Subcodes	Lenze setting		Info		
C01041/1	0.200 s		L_SRFG_1 : S-ramp time		
C01041/2	0.200 s		L_SRFG_2 : S-ramp time		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C01042

Parameter Name: C01042 L_SRFG_1..2 limitations of output values			Data type: INTEGER_16 Index: 23533 _d = 5BED _h		
Limitation of the output values					
Setting range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes	Lenze setting		Info		
C01042/1	100.00 %		L_SRFG_1 : Pos. Limit		
C01042/2	-100.00 %		L_SRFG_1 : Neg. Limit		
C01042/3	100.00 %		L_SRFG_2 : Pos. Limit		
C01042/4	-100.00 %		L_SRFG_2 : Neg. Limit		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C01045

Parameter Name: C01045 L_ConvAP 1-3: Numerator/denominator			Data type: INTEGER_16 Index: 23530 _d = 5BEA _h
From version 02.00.00			
Setting range (min. value unit max. value)			
-32767		32767	
Subcodes	Lenze setting	Info	
C01045/1	1	L_ConvAP 1 : Numerator	
C01045/2	1	L_ConvAP 1 : Denominator	
C01045/3	1	L_ConvAP 2 : Numerator	
C01045/4	1	L_ConvAP 2 : Denominator	
C01045/5	1	L_ConvAP 3 : Numerator	
C01045/6	1	L_ConvAP 3 : Denominator	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01046

Parameter Name: C01046 L_ConvPA 1-3: byDivision			Data type: INTEGER_8 Index: 23529 _d = 5BE9 _h
From version 02.00.00			
Setting range (min. value unit max. value)			
0		31	
Subcodes	Lenze setting	Info	
C01046/1	1	L_ConvPA 1 : Division factor	
C01046/2	1	L_ConvPA 2 : Division factor	
C01046/3	1	L_ConvPA 3 : Division factor	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01047

Parameter Name: C01047 L_GearComp_1: Offset			Data type: INTEGER_16 Index: 23528 _d = 5BE8 _h
From version 02.00.00			
Setting range (min. value unit max. value)			
-16383		16383	
Subcodes	Lenze setting	Info	
C01047/1	0	L_GearComp_1 : Offset	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01048

Parameter Name: C01048 L_GearComp_1: Num_Denom			Data type: INTEGER_16 Index: 23527 _d = 5BE7 _h
From version 02.00.00			
Setting range (min. value unit max. value)			
-32767		32767	
Subcodes	Lenze setting	Info	
C01048/1	1	L_GearComp_1 : Numerator	
C01048/2	1	L_GearComp_1 : Denominator	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01049

Parameter Name: C01049 L_CalcDiameter_1: Status			Data type: INTEGER_16 Index: 23526 _d = 5BE6 _h	
From version 02.00.00				
Display range (min. value unit max. value)				
-10		30		
Subcodes			Info	
C01049/1			L_CalcDiameter_1 : Status	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1				

C01050

Parameter Name: C01050 L_CalcDiameter_1: Diameter recalculation			Data type: UNSIGNED_32 Index: 23525 _d = 5BE5 _h
From version 02.00.00			
Setting range (min. value unit max. value)			
0.001	Rev.	1000.000	
Subcodes	Lenze setting	Info	
C01050/1	1.000 rev.	L_CalcDiameter_1 : Diameter recalculation 0	
C01050/2	0.100 rev.	L_CalcDiameter_1 : Diameter recalculation 1	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C01051

Parameter Name: C01051 L_CalcDiameter_1: Filter time constant			Data type: UNSIGNED_16 Index: 23524 _d = 5BE4 _h
From version 02.00.00			
Setting range (min. value unit max. value)			
0.010	s	3.000	
Subcodes	Lenze setting	Info	
C01051/1	1.000 s	L_CalcDiameter_1 : Filter time constant	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C01052

Parameter Name: C01052 L_CalcDiameter_1: Web break monitoring			Data type: INTEGER_16 Index: 23523 _d = 5BE3 _h
From version 02.00.00			
Setting range (min. value unit max. value)			
0.00	%	100.00	
Subcodes	Lenze setting	Info	
C01052/1	10.00 %	L_CalcDiameter_1 : Permissible diameter change	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <input type="checkbox"/> Scaling factor: 100			

C01053

Parameter Name: C01053 L_ProcessCtrl_1: Controller times			Data type: UNSIGNED_16 Index: 23522 _d = 5BE2 _h
From version 02.00.00			
Setting range (min. value unit max. value)			
0.000	s	30.000	
Subcodes	Lenze setting	Info	
C01053/1	0.000 s	L_ProcessCtrl_1 : Acceleration/deceleration time	
C01053/2	0.000 s	L_ProcessCtrl_1 : Filter time constant	
C01053/3	0.000 s	L_ProcessCtrl_1 : Rate time	
C01053/4	1.000 s	L_ProcessCtrl_1 : Reset time	
C01053/5	0.000 s	L_ProcessCtrl_1 : Rate action	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C01054

Parameter Name: C01054 L_ProcessCtrl_1: System deviation			Data type: INTEGER_16 Index: 23521 _d = 5BE1 _h
From version 02.00.00			
Setting range (min. value unit max. value)			
0.00	%	199.99	
Subcodes	Lenze setting	Info	
C01054/1	100.00 %	L_ProcessCtrl_1 : Gain of system deviation	
C01054/2	0.00 %	L_ProcessCtrl_1 : Area of system deviation	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C01055

Parameter Name:		Data type: UNSIGNED_8	
C01055 L_ProcessCtrl_1: Correcting variable limitation		Index: 23520 _d = 5BE0 _h	
From version 02.00.00			
Selection list			
0	False		
1	True		
Subcodes	Lenze setting	Info	
C01055/1	0: FALSE	L_ProcessCtrl_1: Correcting variable limitation	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <input type="checkbox"/> Scaling factor: 1			

C01056

Parameter Name: C01056 L_ProcessCtrl_1: Controller gain			Data type: UNSIGNED_16 Index: 23519 _d = 5BDF _h		
From version 02.00.00					
Setting range (min. value unit max. value)					
0.00		100.00			
Subcodes	Lenze setting		Info		
C01056/1	0.10		L_ProcessCtrl_1 : Controller gain		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C01057

Parameter Name: C01057 L_CalcDiameter_1: Current diameter			Data type: UNSIGNED_32 Index: 23518 _d = 5BDE _h		
From version 02.00.00					
Display range (min. value unit max. value)					
0.000	mm	10000.000			
Subcodes			Info		
C01057/1			L_CalcDiameter_1 : Current diameter		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C01058

Parameter Name:		Data type: UNSIGNED_8	
C01058 L_PosCtrlLin 1-2: Limit stop		Index: 23517 _d = 5BDD _h	
From version 02.00.00			
Selection list			
0	deactivated		
1	activated		
Subcodes	Lenze setting	Info	
C01058/1	0: Deactivated	L_PosCtrlLin_1 : Limit stop	
C01058/2	0: Deactivated	L_PosCtrlLin_2 : Limit stop	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01059

Parameter Name: C01059 L_PosCtrlLin 1-2: Positioning behaviour		Data type: UNSIGNED_8 Index: 23516 _d = 5BDC _h
From version 02.00.00		
Selection list		
0	dnOut_p = 0	
1	dnOut_p/nOut_v follow dnAct_p	
2	dnOut_p/nOut_v follow dnSet_p	
3	dnOut_p/nOut_v follow dnAct_p (without limitation)	
Subcodes	Lenze setting	Info
C01059/1	0: dnOut_p = 0	L_PosCtrlLin_1 : Positioning behaviour
C01059/2	0: dnOut_p = 0	L_PosCtrlLin_2 : Positioning behaviour
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01060

Parameter Name: C01060 L_PosCtrlLin 1-2: Ramps			Data type: INTEGER_32 Index: 23515 _d = 5BDB _h
From version 02.00.00			
Setting range (min. value unit max. value)			
0.010	s	130.000	
Subcodes	Lenze setting	Info	
C01060/1	1.000 s	L_PosCtrlLin 1 : Deceleration of set position	
C01060/2	1.000 s	L_PosCtrlLin 1 : Acceleration ramp	
C01060/3	1.000 s	L_PosCtrlLin 1 : Deceleration ramp	
C01060/4	1.000 s	L_PosCtrlLin 2 : Deceleration of set position	
C01060/5	1.000 s	L_PosCtrlLin 2 : Acceleration ramp	
C01060/6	1.000 s	L_PosCtrlLin 2 : Deceleration ramp	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C01061

Parameter Name: C01061 L_PosCtrlLin 1-2: Traversing speeds			Data type: INTEGER_16 Index: 23514 _d = 5BDA _h
From version 02.00.00			
Setting range (min. value unit max. value)			
-15000	rpm	15000	
Subcodes	Lenze setting	Info	
C01061/1	199 rpm	L_PosCtrlLin 1: Forward motion	
C01061/2	199 rpm	L_PosCtrlLin 1: Return motion	
C01061/3	199 rpm	L_PosCtrlLin 2: Forward motion	
C01061/4	199 rpm	L_PosCtrlLin 2: Return motion	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01062

Parameter Name: C01062 L_SwitchPoint_1: Dead time			Data type: UNSIGNED_16 Index: 23513 _d = 5BD9 _h
From version 02.00.00			
Setting range (min. value unit max. value)			
0		65535	
Subcodes	Lenze setting	Info	
C01062/1	0	L_SwitchPoint_1 : Dead time 1	
C01062/2	0	L_SwitchPoint_1 : Dead time 2	
C01062/3	0	L_SwitchPoint_1 : Dead time 3	
C01062/4	0	L_SwitchPoint_1 : Dead time 4	
C01062/5	0	L_SwitchPoint_1 : Dead time 5	
C01062/6	0	L_SwitchPoint_1 : Dead time 6	
C01062/7	0	L_SwitchPoint_1 : Dead time 7	
C01062/8	0	L_SwitchPoint_1 : Dead time 8	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01063

Parameter Name: C01063 L_SwitchPoint_1: Hysteresis			Data type: UNSIGNED_16 Index: 23512 _d = 5BD8 _h		
From version 02.00.00					
Setting range (min. value unit max. value)					
0	Incr.	65535			
Subcodes	Lenze setting	Info			
C01063/1	0 incr.	L_SwitchPoint_1 : Hysteresis 1			
C01063/2	0 incr.	L_SwitchPoint_1 : Hysteresis 2			
C01063/3	0 incr.	L_SwitchPoint_1 : Hysteresis 3			
C01063/4	0 incr.	L_SwitchPoint_1 : Hysteresis 4			
C01063/5	0 incr.	L_SwitchPoint_1 : Hysteresis 5			
C01063/6	0 incr.	L_SwitchPoint_1 : Hysteresis 6			
C01063/7	0 incr.	L_SwitchPoint_1 : Hysteresis 7			
C01063/8	0 incr.	L_SwitchPoint_1 : Hysteresis 8			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01064

Parameter Name: C01064 L_SwitchPoint_1: CenterMode		Data type: UNSIGNED_8 Index: 23511 _d = 5BD7 _h
From version 02.00.00		
Selection list		
0	False	
1	True	
Subcodes	Lenze setting	Info
C01064/1	0: FALSE	L_SwitchPoint_1 : CenterMode 1
C01064/2	0: FALSE	L_SwitchPoint_1 : CenterMode 2
C01064/3	0: FALSE	L_SwitchPoint_1 : CenterMode 3
C01064/4	0: FALSE	L_SwitchPoint_1 : CenterMode 4
C01064/5	0: FALSE	L_SwitchPoint_1 : CenterMode 5
C01064/6	0: FALSE	L_SwitchPoint_1 : CenterMode 6
C01064/7	0: FALSE	L_SwitchPoint_1 : CenterMode 7
C01064/8	0: FALSE	L_SwitchPoint_1 : CenterMode 8
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01065

Parameter Name: C01065 L_SwitchPoint_1: Running time			Data type: UNSIGNED_16 Index: 23510 _d = 5BD6 _h		
From version 02.00.00					
Setting range (min. value unit max. value)					
0	ms	60000			
Subcodes	Lenze setting		Info		
C01065/1	0 ms		L_SwitchPoint_1 : Running time 1		
C01065/2	0 ms		L_SwitchPoint_1 : Running time 2		
C01065/3	0 ms		L_SwitchPoint_1 : Running time 3		
C01065/4	0 ms		L_SwitchPoint_1 : Running time 4		
C01065/5	0 ms		L_SwitchPoint_1 : Running time 5		
C01065/6	0 ms		L_SwitchPoint_1 : Running time 6		
C01065/7	0 ms		L_SwitchPoint_1 : Running time 7		
C01065/8	0 ms		L_SwitchPoint_1 : Running time 8		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01066

Parameter Name: C01066 L_SwitchPoint_1: Status		Data type: INTEGER_16 Index: 23509 _d = 5BD5 _h	
From version 02.00.00			
Selection list			
0	OK		
10	FB not active		
100	Switching points not plausible		
Subcodes		Info	
C01066/1		L_SwitchPoint_1 : Status 1	
C01066/2		L_SwitchPoint_1 : Status 2	
C01066/3		L_SwitchPoint_1 : Status 3	
C01066/4		L_SwitchPoint_1 : Status 4	
C01066/5		L_SwitchPoint_1 : Status 5	
C01066/6		L_SwitchPoint_1 : Status 6	
C01066/7		L_SwitchPoint_1 : Status 7	
C01066/8		L_SwitchPoint_1 : Status 8	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01067

Parameter Name: C01067 Inversion of gearbox stages		Data type: UNSIGNED_8 Index: 23508 _d = 5BD4 _h
From version 02.00.00		
Selection list		
0	not inverted	
1	inverted	
2	Automatically from MCK	
Subcodes	Lenze setting	Info
C01067/1	0: Not inverted	L_PhiIntegrator_1 : Invert. gearbox nSet_v
C01067/2	0: Not inverted	L_DFSET_1 : Invert. gearbox nSet_v
C01067/3	0: Not inverted	L_CalcDiameter_1 : Invert. gearbox nMotorSpeedAct_v
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01068

Parameter Name: C01068 L_SwitchPoint_1: Invert		Data type: UNSIGNED_16 Index: 23507 _d = 5BD3 _h
From version 12.00.00		
Setting range (min. hex value max. hex value)		
0x0000	0xFFFF	
Value is bit-coded:		Info
Bit 0	Invert Output1	Bit set = inversion active
Bit 1	Invert Output2	
Bit 2	Invert Output3	
Bit 3	Invert Output4	
Bit 4	Invert Output5	
Bit 5	Invert Output6	
Bit 6	Invert Output7	
Bit 7	Invert Output8	
Bit 8	Reserved	
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	Reserved	
Bit 15	Reserved	
Subcodes	Lenze setting	Info
C01068/1	0x0000	L_SwitchPoint_1 : Inversion of outputs
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C01069

Parameter Name: C01069 L_DFSET_1: Ramp settings			Data type: UNSIGNED_16 Index: 23506 _d = 5BD2 _h		
From version 02.00.00					
Setting range (min. value unit max. value)					
0	Incr./ms	32767			
Subcodes	Lenze setting		Info		
C01069/1	10 incr./ms		L_DFSET_1 : Ramp SpeedTrim (1/100) • From version 12.00.00 onwards, this setting has a resolution increased by the factor 100: A value of 32767 is internally evaluated with 327.67. Hence, the unit is [incr./100 ms].		
C01069/2	100 incr./ms		L_DFSET_1 : Ramp angle compensation		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01070

Parameter Name: C01070 L_DFSET_1: Angular trimming			Data type: INTEGER_32 Index: 23505 _d = 5BD1 _h		
From version 02.00.00					
Setting range (min. value unit max. value)					
-134217728	Incr.	134217728			
Subcodes	Lenze setting		Info		
C01070/1	0 incr.		L_DFSET_1 : Speed-dependent angle adjustment		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01071

Parameter Name: C01071 L_DFSET_1: Following error limit			Data type: UNSIGNED_32 Index: 23504 _d = 5BD0 _h		
From version 02.00.00					
Setting range (min. value unit max. value)					
10	Incr.	2147483647			
Subcodes	Lenze setting		Info		
C01071/1	32768 incr.		L_DFSET_1: Following error limit		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01072

Parameter Name: C01072 L_DFSET_1: Multiplier - angular trimming			Data type: INTEGER_16 Index: 23503 _d = 5BCF _h		
From version 02.00.00					
Setting range (min. value unit max. value)					
-20000		20000			
Subcodes	Lenze setting		Info		
C01072/1	1		L_DFSET_1 : Multiplier - angular trimming		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01073

Parameter Name: C01073 L_DFSET_1: Adjustment		Data type: UNSIGNED_8 Index: 23502 _d = 5BC _{Eh}
From version 02.00.00		
Setting range (min. hex value max. hex value)		
0x00		0xFF
Value is bit-coded:		Info
Bit 0	Setpoint angle without gearbox factor	0 ≡ Evaluation of the setpoint angle with gearbox factor 1 ≡ Evaluation of the setpoint angle without gearbox factor
Bit 1	Angle correction with polynomial	0 ≡ Angle correction without downstream polynomial 1 ≡ Angle correction with downstream polynomial
Bit 2	External angle correction	0 ≡ Internal angle correction 1 ≡ External angle correction • From version 13.00.00
Bit 3	Reserved	
Bit 4	Reserved	
Bit 5	Reserved	
Bit 6	Reserved	
Bit 7	Reserved	
Subcodes	Lenze setting	Info
C01073/1	0x02	L_DFSET_1 : Adjustment
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C01074

Parameter Name: C01074 L_DFSET_1: Zero pulse divider		Data type: UNSIGNED_16 Index: 23501 _d = 5BCD _h
From version 02.00.00		
Setting range (min. value unit max. value)		
0		16384
Subcodes	Lenze setting	Info
C01074/1	0	L_DFSET_1 : Divider for actual value zero pulse
C01074/2	0	L_DFSET_1 : Divider for setpoint zero pulse
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01075

Parameter Name: C01075 L_DFSET_1: Synchronisation mode		Data type: UNSIGNED_8 Index: 23500 _d = 5BC _h
From version 02.00.00		
Selection list		
0	Inactive	
1	Permanent sync. without enable (bZeroPulse)	
2	Permanent sync. with enable (bZeroPulse)	
10	1x sync. - Angular diff. shortest path setpoint	
11	1x Sync. - Angular diff. Cw	
12	1x Sync. - Angular diff. Ccw	
13	1x Sync. - Angular diff. shortest path act. value	
Subcodes	Lenze setting	Info
C01075/1	0: Inactive	L_DFSET_1 : Synchronisation mode
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01076

Parameter Name: C01076 L_DFRFG_1: Times		Data type: UNSIGNED_32 Index: 23499 _d = 5BCB _h
From version 02.00.00		
Setting range (min. value unit max. value)		
0.000	s	999.900
Subcodes	Lenze setting	Info
C01076/1	1.000 s	L_DFRFG_1 : Acceleration and deceleration time
C01076/2	0.000 s	L_DFRFG_1 : Deceleration time for quick stop
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000		

C01077

Parameter Name: C01077 L_DFRFG_1: Max. speed-up		Data type: INTEGER_16 Index: 23498 _d = 5BCA _h
From version 02.00.00		
Setting range (min. value unit max. value)		
1	rpm	15000
Subcodes	Lenze setting	Info
C01077/1	3000 rpm	L_DFRFG_1 : Max. speed-up
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01078

Parameter Name: C01078 L_DFRFG_1: Following error			Data type: UNSIGNED_32 Index: 23497 _d = 5BC9 _h		
From version 02.00.00					
Setting range (min. value unit max. value)					
10	Incr.	2000000000			
Subcodes	Lenze setting		Info		
C01078/1	2000000000 incr.		L_DFRFG_1 : Following error limit		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01079

Parameter Name:			Data type: UNSIGNED_16 Index: 23496 _d = 5BC8 _h		
C01079 L_DFRFG_1: Synchronisation window					
From version 02.00.00					
Setting range (min. value unit max. value)					
0	Incr.	65535			
Subcodes	Lenze setting		Info		
C01079/1	100 incr.		L_DFRFG_1: Synchronisation window (position)		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01080

Parameter Name: C01080 L_DFRFG_1: Offset			Data type: INTEGER_32 Index: 23495 _d = 5BC7 _h		
From version 02.00.00					
Setting range (min. value unit max. value)					
-2147483647	Incr.	2147483647			
Subcodes	Lenze setting		Info		
C01080/1	0 incr.		L_DFRFG_1 : Offset		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01081

Parameter Name: C01081 L_DFRFG_1: Sync. direction / TP function		Data type: UNSIGNED_8 Index: 23494 _d = 5BC6 _h	
From version 02.00.00			
Selection list			
1	cw/ccw - without TP		
2	cw - without TP		
3	ccw - without TP		
4	cw/ccw - with TP		
5	cw - with TP		
6	ccw - with TP		
Subcodes	Lenze setting	Info	
C01081/1	1: cw/ccw - without TP	L_DFRFG_1 : Sync. direction / TP function	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01082

Parameter Name: C01082 LS_WriteParamList: Execute Mode		Data type: UNSIGNED_8 Index: 23493 _d = 5BC5 _h
Parameter change-over : Selection of the activation method		
Selection list (Lenze setting printed in bold)		Info
0	by Execute	The writing of the parameter list is activated by a FALSE/TRUE edge at the <i>bExecute</i> input.
1	by Input Select	The writing of the parameter list is carried out if a change is made at the select inputs and if the controller is initialised.
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01083

Parameter Name: C01083 LS_WriteParamList: Error status		Data type: UNSIGNED_16 Index: 23492 _d = 5BC4 _h
Parameter change-over : Error status:		
<ul style="list-style-type: none"> • 0 = no error • 33803 0x840B = invalid data type (e.g. STRING) • 33804 0x840C = limit violation • 33806 0x840E = invalid code • 33813 0x8415 = no element of the selection list • 33815 0x8417 = writing of the parameter not permitted • 33816 0x8418 = writing of the parameter only permitted if controller is inhibited • 33829 0x8425 = invalid subcode • 33865 0x8449 = no parameter with subcodes 		
Display range (min. value unit max. value)		
0		34000
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01084

Parameter Name: C01084 LS_WriteParamList: Error line		Data type: UNSIGNED_8 Index: 23491 _d = 5BC3 _h
Parameter change-over : Display of the number of list entry where the error occurred (in connection with the value set selected via <i>bSelectWriteValue_1</i> and <i>bSelectWriteValue_2</i>).		
Display range (min. value unit max. value)		
0		32
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01085

Parameter Name: C01085 LS_WriteParamList: Index			Data type: INTEGER_32 Index: 23490 _d = 5BC2 _h
Parameter change-over : Parameter for entry 1 ... 32			
Setting range (min. value unit max. value)			
0.000		16000.000	
Subcodes	Lenze setting	Info	
C01085/1	0.000	Parameter for entries 1 ... 32	
C01085/...		• Format: <code number>.<subcode number>	
C01085/32		• Examples: "12.000" = C00012; "26.001" = C00026/1	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C01086

Parameter Name: C01086 LS_WriteParamList: WriteValue_1			Data type: INTEGER_32 Index: 23489 _d = 5BC1 _h
Parameter change-over : Parameter values - value set 1			
Setting range (min. value unit max. value)			
-2147483647		2147483647	
Subcodes	Lenze setting	Info	
C01086/1	0	Parameter values - value set 1	
C01086/...		• Parameter values for the parameters defined in C01085 /1 ... 32.	
C01086/32			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01087

Parameter Name: C01087 LS_WriteParamList: WriteValue_2			Data type: INTEGER_32 Index: 23488 _d = 5BC0 _h
Parameter change-over : Parameter values - value set 2			
Setting range (min. value unit max. value)			
-2147483647		2147483647	
Subcodes	Lenze setting	Info	
C01087/1	0	Parameter values - value set 2	
C01087/...		• Parameter values for the parameters defined in C01085 /1 ... 32.	
C01087/32			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01088

Parameter Name: C01088 LS_WriteParamList: WriteValue_3			Data type: INTEGER_32 Index: 23487 _d = 5BBF _h
Parameter change-over : Parameter values - value set 3			
Setting range (min. value unit max. value)			
-2147483647		2147483647	
Subcodes	Lenze setting	Info	
C01088/1	0	Parameter values - value set 3	
C01088/...		• Parameter values for the parameters defined in C01085 /1 ... 32.	
C01088/32			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01089

Parameter Name: C01089 LS_WriteParamList: WriteValue_4			Data type: INTEGER_32 Index: 23486 _d = 5BBE _h		
Parameter change-over : Parameter values - value set 4					
Setting range (min. value unit max. value)					
-2147483647		2147483647			
Subcodes		Lenze setting		Info	
C01089/1		0		Parameter values - value set 4 • Parameter values for the parameters defined in C01085 /1 ... 32.	
C01089/...					
C01089/32					
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01090

Parameter Name: C01090 LS_ParReadWrite 1-6: Index			Data type: INTEGER_32 Index: 23485 _d = 5BBD _h
Parameter to be read or written. <ul style="list-style-type: none">• Format: <code number>,<subcode number>• For a setting of "0,000", inputs <i>wParIndex</i> and <i>wParSubindex</i> are effective for addressing purposes instead.			
Setting range (min. value unit max. value)			
0.000		16000.000	
Subcodes	Lenze setting	Info	
C01090/1	0.000	LS_ParReadWrite 1 : Index	
C01090/2	0.000	LS_ParReadWrite 2 : Index	
C01090/3	0.000	LS_ParReadWrite 3 : Index	
C01090/4	0.000	LS_ParReadWrite 4 : Index	
C01090/5	0.000	LS_ParReadWrite 5 : Index	
C01090/6	0.000	LS_ParReadWrite 6 : Index	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C01091

Parameter Name:		Data type: UNSIGNED_16 Index: 23484 _d = 5BBC _h
C01091 LS_ParReadWrite 1-6: Cycle time		
Time interval for cyclic reading/writing		
Selection list		
0	0 (by Execute)	
20	20 ms	
50	50 ms	
100	100 ms	
200	200 ms	
500	500 ms	
1000	1 s	
2000	2 s	
5000	5 s	
10000	10 s	
Subcodes	Lenze setting	Info
C01091/1	0: 0 (by Execute)	LS_ParReadWrite 1 : Cycle time
C01091/2	0: 0 (by Execute)	LS_ParReadWrite 2 : Cycle time
C01091/3	0: 0 (by Execute)	LS_ParReadWrite 3 : Cycle time
C01091/4	0: 0 (by Execute)	LS_ParReadWrite 4 : Cycle time
C01091/5	0: 0 (by Execute)	LS_ParReadWrite 5 : Cycle time
C01091/6	0: 0 (by Execute)	LS_ParReadWrite 6 : Cycle time
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01092

Parameter Name:		Data type: UNSIGNED_16 Index: 23483 _d = 5BBB _h	
C01092 LS_ParReadWrite 1-6: FailState			
Error status:			
<ul style="list-style-type: none">• 0 = no error• 33803 0x840B = invalid data type (e.g. STRING)• 33804 0x840C = limit violation• 33806 0x840E = invalid code• 33813 0x8415 = no element of the selection list• 33815 0x8417 = writing of the parameter not permitted• 33816 0x8418 = writing of the parameter only permitted if controller is inhibited• 33829 0x8425 = invalid subcode• 33865 0x8449 = no parameter with subcodes			
Display range (min. value unit max. value)			
0			
Subcodes		Info	
C01092/1		LS_ParReadWrite 1 : Error status	
C01092/2		LS_ParReadWrite 2 : Error status	
C01092/3		LS_ParReadWrite 3 : Error status	
C01092/4		LS_ParReadWrite 4 : Error status	
C01092/5		LS_ParReadWrite 5 : Error status	
C01092/6		LS_ParReadWrite 6 : Error status	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01093

Parameter Name: C01093 - LS_ParReadWrite 1-6: Arithmetic mode		Data type: UNSIGNED_8 Index: 23482 _d = 5BBA _h
The integrated arithmetic function allows for easy arithmetic conversion of the process value to be written or which was read into the format of the target parameter via parameterisable factors and without the need for an additional arithmetic FB.		
Selection list		
0	No arithmetic	
1	In16Bit: LW=+/-32767	
2	In16Bit: HW=+/-; LW=0..65535	
3	In32Bit: HW_LW=+/-2147483647	
Subcodes	Lenze setting	Info
C01093/1	0: no arithmetic	LS_ParReadWrite 1 : Arithmetic mode
C01093/2	0: no arithmetic	LS_ParReadWrite 2 : Arithmetic mode
C01093/3	0: no arithmetic	LS_ParReadWrite 3 : Arithmetic mode
C01093/4	0: no arithmetic	LS_ParReadWrite 4 : Arithmetic mode
C01093/5	0: no arithmetic	LS_ParReadWrite 5 : Arithmetic mode
C01093/6	0: no arithmetic	LS_ParReadWrite 6 : Arithmetic mode
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01094

Parameter Name: C01094 - LS_ParReadWrite 1-6: Numerator		Data type: INTEGER_16 Index: 23481 _d = 5BB9 _h
Arithmetic function : Factor (numerator) for internal conversion in arithmetic modes 1 ... 3.		
Setting range (min. value unit max. value)		
-32767		32767
Subcodes	Lenze setting	Info
C01094/1	1	LS_ParReadWrite 1 : Numerator
C01094/2	1	LS_ParReadWrite 2 : Numerator
C01094/3	1	LS_ParReadWrite 3 : Numerator
C01094/4	1	LS_ParReadWrite 4 : Numerator
C01094/5	1	LS_ParReadWrite 5 : Numerator
C01094/6	1	LS_ParReadWrite 6 : Numerator
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01095

Parameter Name: C01095 - LS_ParReadWrite 1-6: Denominator			Data type: INTEGER_16 Index: 23480 _d = 5BB8 _h
<u>Arithmetic function</u> : Factor (denominator) for internal conversion in arithmetic modes 1 ... 3.			
Setting range (min. value unit max. value)			
1		32767	
Subcodes	Lenze setting	Info	
C01095/1	1	<u>LS_ParReadWrite 1</u> : Denominator	
C01095/2	1	<u>LS_ParReadWrite 2</u> : Denominator	
C01095/3	1	<u>LS_ParReadWrite 3</u> : Denominator	
C01095/4	1	<u>LS_ParReadWrite 4</u> : Denominator	
C01095/5	1	<u>LS_ParReadWrite 5</u> : Denominator	
C01095/6	1	<u>LS_ParReadWrite 6</u> : Denominator	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01100

Parameter Name: C01100 Function L_Counter 1-3		Data type: UNSIGNED_8 Index: 23475 _d = 5BB3 _h
Selection of reset function		
Selection list		
0	Normal counting	
1	Auto reset	
2	Manual reset	
Subcodes	Lenze setting	Info
C01100/1	0: Normal counting	L_Counter 1 : Function
C01100/2	0: Normal counting	L_Counter 2 : Function
C01100/3	0: Normal counting	L_Counter 3 : Function
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01101

Parameter Name: C01101 Comparison L_Counter 1-3		Data type: UNSIGNED_8 Index: 23474 _d = 5BB2 _h
Selection of comparison operation		
Selection list		
0	Greater than or equal to	
1	Less than or equal to	
2	equal to	
Subcodes	Lenze setting	Info
C01101/1	0: Greater than or equal to	L_Counter 1 : Comparison
C01101/2	0: Greater than or equal to	L_Counter 2 : Comparison
C01101/3	0: Greater than or equal to	L_Counter 3 : Comparison
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01108

Parameter Name: C01108 L_SwitchPoint_1: Dead time factor		Data type: UNSIGNED_8 Index: 23467 _d = 5BAB _h
From version 14.00.00		
Selection list		
1	1 µs	
2	10 µs	
3	100 µs	
4	1000 µs	
Subcodes	Lenze setting	Info
C01108/1	2: 10 µs	L_SwitchPoint_1 : Deadtime factor 1
C01108/2	2: 10 µs	L_SwitchPoint_1 : Deadtime factor 2
C01108/3	2: 10 µs	L_SwitchPoint_1 : Deadtime factor 3
C01108/4	2: 10 µs	L_SwitchPoint_1 : Deadtime factor 4
C01108/5	2: 10 µs	L_SwitchPoint_1 : Deadtime factor 5
C01108/6	2: 10 µs	L_SwitchPoint_1 : Deadtime factor 6
C01108/7	2: 10 µs	L_SwitchPoint_1 : Deadtime factor 7
C01108/8	2: 10 µs	L_SwitchPoint_1 : Deadtime factor 8
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01109

Parameter Name: C01109 L_SwitchPointPar_1: Dead time factor		Data type: UNSIGNED_8 Index: 23466 _d = 5BAA _h
From version 14.00.00		
Selection list		
1	1 µs	
2	10 µs	
3	100 µs	
4	1000 µs	
Subcodes	Lenze setting	Info
C01109/1	2: 10 µs	L_SwitchPointPar_1 : Dead time factor 1
C01109/2	2: 10 µs	L_SwitchPointPar_1 : Dead time factor 2
C01109/3	2: 10 µs	L_SwitchPointPar_1 : Dead time factor 3
C01109/4	2: 10 µs	L_SwitchPointPar_1 : Dead time factor 4
C01109/5	2: 10 µs	L_SwitchPointPar_1 : Dead time factor 5
C01109/6	2: 10 µs	L_SwitchPointPar_1 : Dead time factor 6
C01109/7	2: 10 µs	L_SwitchPointPar_1 : Dead time factor 7
C01109/8	2: 10 µs	L_SwitchPointPar_1 : Dead time factor 8
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01110

Parameter Name: C01110 LS_MultiEncoder: Solid measure		Data type: UNSIGNED_8 Index: 23465 _d = 5BA9 _h
From version 02.00.00 Configuration examples can be found in the following chapters: <ul style="list-style-type: none"> • SinCos absolute value encoder with HIPERFACE® protocol • SSI absolute value encoder with Stegmann-SSI protocol 		
Selection list (Lenze setting printed in bold)		Info
0	rotatively unipolar	
1	linearly unipolar	
2	rotatively bipolar	
3	linearly bipolar	
4	Inverted rotatively in unipolar mode	From version 15.00.00
5	Inverted linearly in unipolar mode	
6	Inverted rotatively in bipolar mode	From version 15.00.00
7	Inverted linearly in bipolar mode	From version 15.00.00
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C01111

Parameter Name: C01111 LS_MultiEncoder: Encoder constant		Data type: INTEGER_32 Index: 23464 _d = 5BA8 _h
From version 02.00.00 Configuration examples can be found in the following chapters: <ul style="list-style-type: none"> • SinCos absolute value encoder with HIPERFACE® protocol • SSI absolute value encoder with Stegmann-SSI protocol 		
Setting range (min. value unit max. value)		
1		2147483647
Subcodes	Lenze setting	Info
C01111/1	1	LS_MultiEncoder : Difference - traverse path
C01111/2	1	LS_MultiEncoder : Difference - encoder value
C01111/3	1	LS_MultiEncoder : Traverse path - encoder increment
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C01112

Parameter Name: C01112 LS_MultiEncoder: Position values		Data type: INTEGER_32 Index: 23463 _d = 5BA7 _h
<div> ▶ Encoder/feedback system: Multi-Encoder </div>		
Setting range (min. value unit max. value)		
-214748.3647	units	214748.3647
Subcodes	Lenze setting	Info
C01112/1	0.0000 units	LS_MultiEncoder : Position offset
C01112/2	-214748.3647 units	LS_MultiEncoder : Data area min
C01112/3	214748.3647 units	LS_MultiEncoder : Data area max
C01112/4	0.0000 units	LS_MultiEncoder : Max. position jump • From version 14.00.00
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10000		

C01119

Parameter Name: C01119 LS_MultiEncoder: Current position			Data type: INTEGER_32 Index: 23456 _d = 5BA0 _h		
From version 02.00.00					
▸ Encoder/feedback system: Multi-Encoder					
Display range (min. value unit max. value)					
-214748.3647	units	214748.3647			
Subcodes			Info		
C01119/1			LS_MultiEncoder : Current position		
C01119/2			LS_MultiEncoder : Maximum travel distance		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000					

C01120

Parameter Name: C01120 Sync signal source		Data type: UNSIGNED_8 Index: 23455 _d = 5B9F _h	
Selection of the signal source for device synchronisation			
• The drive can only be synchronised by one source.			
▸ Synchronisation of the internal time base			
Selection list (Lenze setting printed in bold)		Info	
0	Off	Synchronisation off	
1	CAN on board	Synchronisation via CAN bus ▸ Sync telegram	
2	AxisBusIO	Synchronisation via axis bus ▸ Axis bus	
4	MCI	Synchronisation via MCI (communication module)	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01121

Parameter Name:			Data type: UNSIGNED_16 Index: 23454 _d = 5B9E _h		
C01121 Sync cycle time setpoint					
Cycle time setpoint for device synchronisation					
<ul style="list-style-type: none">• Time interval at which the phase control loop (PLL) in the controller expects the synchronisation signals.• The cycle time setpoint must be set according to the cycle of the respective synchronisation source.					
Note:					
<ul style="list-style-type: none">• Only integer multiples of 1000 µs can be set.• Intelligent communication modules usually define the cycle time setpoint derived from the bus cycle. In this case, a manual change is not possible.					
Example: For the CAN bus, a distance of 2 ms has been set between two synchronisation signals. If the CAN bus is to be used as synchronisation source, a synchronisation cycle of 2000 µs must be set in C01121.					
<div>► Synchronisation of the internal time base</div>					
Setting range (min. value unit max. value)				Lenze setting	
1000	µs	20000	1000 µs		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1</div>					

C01122

Parameter | Name:

C01122 | Sync phase position

Data type: UNSIGNED_16

Index: 23453_d = 5B9D_h

Phase position for device synchronisation

- The phase position determines the zero-time of the internal system cycle with regard to the synchronisation signal (bus cycle). Since PDO processing is an inherent part of the system part of the application, the instant of acceptance of the PDOs is postponed as well by a changed phase position.
- With a setting = 0, the system cycle starts simultaneously with the synchronisation signal.
- With a setting > 0, the internal system cycle starts earlier by the set time with regard to the synchronisation signal (the phase position acts negatively).
- Intelligent communication modules define the optimal time with activated synchronisation by themselves. In this case, a manual change is not possible.
- The decisive factor for defining C01122 is the time where all nodes are provided with valid PDOs.

Example: If the phase position is set to 550 µs, the system part of the application starts 550 µs before the arrival of the synchronisation signal.

► [Synchronisation of the internal time base](#)

Setting range (min. value unit max. value)			Lenze setting
0	µs	1000	0 µs

☒ Read access
 ☒ Write access
 ☐ CINH
 ☐ PLC STOP
 ☐ No transfer
 ☐ COM
 ☐ MOT
 Scaling factor: 1

C01123

Parameter Name: C01123 Sync window			Data type: UNSIGNED_16 Index: 23452 _d = 5B9C _h		
<p>Time slot for monitoring the synchronisation signal or the phase position</p> <ul style="list-style-type: none">• The synchronisation signal or the current phase position must be within this time slot around the corresponding expected value (C01122).• With the setting "1000 µs" there will be no monitoring. <p style="text-align: right;">▶ Synchronisation of the internal time base</p>					
Setting range (min. value unit max. value)			Lenze setting		
0		µs	10000		100 µs
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01124

Parameter Name: C01124 Sync correction width		Data type: UNSIGNED_8 Index: 23451 _d = 5B9B _h	
<div>Correction increment for device synchronisation</div> <ul style="list-style-type: none">• If the cycle times of the synchronisation signal differs and phase-locked loop (PLL) differ from each other, this setting defines the measure the phase-locking loop is reset with.• If synchronisation is not reached, select a higher correction constant.• The optimum setting depends on quartz precision and must be determined empirically if required. <div>► Synchronisation of the internal time base</div>			
Selection list (Lenze setting printed in bold)			
1	80ns		
2	160ns		
3	240ns		
4	320ns		
5	400ns		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1</div>			

C01130

Parameter Name: C01130 LS_RetainData: Selection		Data type: UNSIGNED_16 Index: 23445 _d = 5B95 _h		
From version 02.00.00				
Setting range (min. hex value max. hex value)				
0x0000				0xFFFF
Value is bit-coded:				
Bit 0	wIn1			
Bit 1	wIn2			
Bit 2	wIn3			
Bit 3	wIn4			
Bit 4	dnIn1			
Bit 5	dnIn2			
Bit 6	dnIn3			
Bit 7	dnIn4			
Bit 8	bln1			
Bit 9	bln2			
Bit 10	bln3			
Bit 11	bln4			
Bit 12	Reserved			
Bit 13	Reserved			
Bit 14	Reserved			
Bit 15	Reserved			
Subcodes	Lenze setting	Info		
C01130/1	0x000F	LS_RetainData : Selection bSetRetain_1		
C01130/2	0x00F0	LS_RetainData : Selection bSetRetain_2		
C01130/3	0x0F00	LS_RetainData : Selection bSetRetain_3		
C01130/4	0x0FFF	LS_RetainData : Selection bLoadParams		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT				

C01131

Parameter Name: C01131 LS_RetainData: 16Bit data			Data type: UNSIGNED_16 Index: 23444 _d = 5B94 _h
From version 02.00.00			
Setting range (min. value unit max. value)			
0		65535	
Subcodes	Lenze setting	Info	
C01131/1	0	LS_RetainData : wValue1	
C01131/2	0	LS_RetainData : wValue2	
C01131/3	0	LS_RetainData : wValue3	
C01131/4	0	LS_RetainData : wValue4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01132

Parameter Name: C01132 LS_RetainData: 32Bit data			Data type: INTEGER_32 Index: 23443 _d = 5B93 _h		
From version 02.00.00					
Setting range (min. value unit max. value)					
-2147483647		2147483647			
Subcodes	Lenze setting		Info		
C01132/1	0		LS_RetainData: dnValue1		
C01132/2	0		LS_RetainData: dnValue2		
C01132/3	0		LS_RetainData: dnValue3		
C01132/4	0		LS_RetainData: dnValue4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01133

Parameter Name:		Data type: UNSIGNED_8	
C01133 LS_RetainData: Bool data		Index: 23442 _d = 5B92 _h	
From version 02.00.00			
Selection list			
0	False		
1	True		
Subcodes	Lenze setting	Info	
C01133/1	0: FALSE	LS_RetainData : bValue1	
C01133/2	0: FALSE	LS_RetainData : bValue2	
C01133/3	0: FALSE	LS_RetainData : bValue3	
C01133/4	0: FALSE	LS_RetainData : bValue4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01138

Parameter Name: C01138 L_Transient 1-4: Function		Data type: UNSIGNED_8 Index: 23437 _d = 5B8D _h	
Selection of edge evaluation			
Selection list			
0	High edge		
1	Low edge		
2	High and low edge		
Subcodes	Lenze setting	Info	
C01138/1	0: High edge	L_Transient 1 : Function	
C01138/2	0: High edge	L_Transient 2 : Function	
C01138/3	0: High edge	L_Transient 3 : Function	
C01138/4	0: High edge	L_Transient 4 : Function	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01139

Parameter Name: C01139 L_Transient 1-4: Pulse duration			Data type: UNSIGNED_16 Index: 23436 _d = 5B8C _h
Setting range (min. value unit max. value)			
0.000	s	60.000	
Subcodes	Lenze setting	Info	
C01139/1	0.000 s	L_Transient 1 : Pulse duration	
C01139/2	0.000 s	L_Transient 2 : Pulse duration	
C01139/3	0.000 s	L_Transient 3 : Pulse duration	
C01139/4	0.000 s	L_Transient 4 : Pulse duration	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C01140

Parameter Name: C01140 L_Transient 5-8: Function		Data type: UNSIGNED_8 Index: 23435 _d = 5B8B _h
Selection of edge evaluation		
Selection list		
0	High edge	
1	Low edge	
2	High and low edge	
Subcodes	Lenze setting	Info
C01140/1	0: High edge	L_Transient 5 : Function
C01140/2	0: High edge	L_Transient 6 : Function
C01140/3	0: High edge	L_Transient 7 : Function
C01140/4	0: High edge	L_Transient 8 : Function
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01141

Parameter Name: C01141 L_Transient 5-8 pulse duration			Data type: UNSIGNED_16 Index: 23434 _d = 5B8A _h
Setting range (min. value unit max. value)			
0.000	s	60.000	
Subcodes	Lenze setting	Info	
C01141/1	0.000 s	L_Transient 5 : Pulse duration	
C01141/2	0.000 s	L_Transient 6 : Pulse duration	
C01141/3	0.000 s	L_Transient 7 : Pulse duration	
C01141/4	0.000 s	L_Transient 8 : Pulse duration	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C01150

Parameter Name: C01150 L_PhaseIntK: Function		Data type: UNSIGNED_8 Index: 23425 _d = 5B81 _h	
Loading behaviour of the integrator			
Selection list		Info	
0	Loading with level	Load integrator with TRUE level at the input <i>bLoad</i>	
1	Loading with edge	Load integrator with FALSE/TRUE edge at the input <i>bLoad</i>	
2	Loading with level + reset	Load integrator when the comparison value (C01151) is reached or with TRUE level at the <i>bLoad</i> input	
Subcodes	Lenze setting	Info	
C01150/1	0: Loading with level	L_PhaseIntK_1 : Function	
C01150/2	0: Loading with level	L_PhaseIntK_2 : Function	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01151

Parameter Name: C01151 L_PhaseIntK: Compare			Data type: INTEGER_32 Index: 23424 _d = 5B80 _h
Comparison value			
Setting range (min. value unit max. value)			
0		2147418112	
Subcodes	Lenze setting	Info	
C01151/1	0	L_PhaseIntK_1 : Comparison value	
C01151/2	0	L_PhaseIntK_2 : Comparison value	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01152

Parameter Name: C01152 L_SwitchPointPar_1: Dead time			Data type: UNSIGNED_16 Index: 23423 _d = 5B7F _h
From version 12.00.00			
Setting range (min. value unit max. value)			
0		65535	
Subcodes	Lenze setting	Info	
C01152/1	0	L_SwitchPointPar_1 : Dead time 1	
C01152/2	0	L_SwitchPointPar_1 : Dead time 2	
C01152/3	0	L_SwitchPointPar_1 : Dead time 3	
C01152/4	0	L_SwitchPointPar_1 : Dead time 4	
C01152/5	0	L_SwitchPointPar_1 : Dead time 5	
C01152/6	0	L_SwitchPointPar_1 : Dead time 6	
C01152/7	0	L_SwitchPointPar_1 : Dead time 7	
C01152/8	0	L_SwitchPointPar_1 : Dead time 8	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01153

Parameter Name: C01153 L_SwitchPointPar_1: Hysteresis			Data type: UNSIGNED_16 Index: 23422 _d = 5B7E _h		
From version 12.00.00					
Setting range (min. value unit max. value)					
0	Incr.	65535			
Subcodes	Lenze setting	Info			
C01153/1	0 incr.	L_SwitchPointPar_1 : Hysteresis 1			
C01153/2	0 incr.	L_SwitchPointPar_1 : Hysteresis 2			
C01153/3	0 incr.	L_SwitchPointPar_1 : Hysteresis 3			
C01153/4	0 incr.	L_SwitchPointPar_1 : Hysteresis 4			
C01153/5	0 incr.	L_SwitchPointPar_1 : Hysteresis 5			
C01153/6	0 incr.	L_SwitchPointPar_1 : Hysteresis 6			
C01153/7	0 incr.	L_SwitchPointPar_1 : Hysteresis 7			
C01153/8	0 incr.	L_SwitchPointPar_1 : Hysteresis 8			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01154

Parameter Name: C01154 L_SwitchPointPar_1: CenterMode		Data type: UNSIGNED_8 Index: 23421 _d = 5B7D _h	
From version 12.00.00			
Selection list			
0	False		
1	True		
Subcodes	Lenze setting	Info	
C01154/1	0: FALSE	L_SwitchPointPar_1 : CenterMode 1	
C01154/2	0: FALSE	L_SwitchPointPar_1 : CenterMode 2	
C01154/3	0: FALSE	L_SwitchPointPar_1 : CenterMode 3	
C01154/4	0: FALSE	L_SwitchPointPar_1 : CenterMode 4	
C01154/5	0: FALSE	L_SwitchPointPar_1 : CenterMode 5	
C01154/6	0: FALSE	L_SwitchPointPar_1 : CenterMode 6	
C01154/7	0: FALSE	L_SwitchPointPar_1 : CenterMode 7	
C01154/8	0: FALSE	L_SwitchPointPar_1 : CenterMode 8	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01155

Parameter Name: C01155 L_SwitchPointPar_1: Running time			Data type: UNSIGNED_16 Index: 23420 _d = 5B7C _h		
From version 12.00.00					
Setting range (min. value unit max. value)					
0	ms	60000			
Subcodes	Lenze setting		Info		
C01155/1	0 ms		L_SwitchPointPar_1 : Running time 1		
C01155/2	0 ms		L_SwitchPointPar_1 : Running time 2		
C01155/3	0 ms		L_SwitchPointPar_1 : Running time 3		
C01155/4	0 ms		L_SwitchPointPar_1 : Running time 4		
C01155/5	0 ms		L_SwitchPointPar_1 : Running time 5		
C01155/6	0 ms		L_SwitchPointPar_1 : Running time 6		
C01155/7	0 ms		L_SwitchPointPar_1 : Running time 7		
C01155/8	0 ms		L_SwitchPointPar_1 : Running time 8		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01156

Parameter | Name: C01156 | L_SwitchPointPar_1: Status

Data type: INTEGER_16
Index: 23419_d = 5B7B_h

From version 12.00.00

Selection list	
0	OK
10	FB not active
100	Switching points not plausible

Subcodes	Info
C01156/1	L_SwitchPointPar_1 : Status 1
C01156/2	L_SwitchPointPar_1 : Status 2
C01156/3	L_SwitchPointPar_1 : Status 3
C01156/4	L_SwitchPointPar_1 : Status 4
C01156/5	L_SwitchPointPar_1 : Status 5
C01156/6	L_SwitchPointPar_1 : Status 6
C01156/7	L_SwitchPointPar_1 : Status 7
C01156/8	L_SwitchPointPar_1 : Status 8

☒ Read access ☐ Write access ☐ CINH ☐ PLC STOP ☒ No transfer ☐ COM ☐ MOT Scaling factor: 1

C01157

Parameter Name: C01157 L_SwitchPointPar_1:Position			Data type: INTEGER_32 Index: 23418 _d = 5B7A _h		
From version 12.00.00					
Setting range (min. value unit max. value)					
-214748.3647	units	214748.3647			
Subcodes	Lenze setting	Info			
C01157/1	0.0000 units	L_SwitchPointPar_1 : dnSwitchPoint1_p			
C01157/2	0.0000 units	L_SwitchPointPar_1 : dn2ndPoint_Size1_p			
C01157/3	0.0000 units	L_SwitchPointPar_1 : dnSwitchPoint2_p			
C01157/4	0.0000 units	L_SwitchPointPar_1 : dn2ndPoint_Size2_p			
C01157/5	0.0000 units	L_SwitchPointPar_1 : dnSwitchPoint3_p			
C01157/6	0.0000 units	L_SwitchPointPar_1 : dn2ndPoint_Size3_p			
C01157/7	0.0000 units	L_SwitchPointPar_1 : dnSwitchPoint4_p			
C01157/8	0.0000 units	L_SwitchPointPar_1 : dn2ndPoint_Size4_p			
C01157/9	0.0000 units	L_SwitchPointPar_1 : dnSwitchPoint5_p			
C01157/10	0.0000 units	L_SwitchPointPar_1 : dn2ndPoint_Size5_p			
C01157/11	0.0000 units	L_SwitchPointPar_1 : dnSwitchPoint6_p			
C01157/12	0.0000 units	L_SwitchPointPar_1 : dn2ndPoint_Size6_p			
C01157/13	0.0000 units	L_SwitchPointPar_1 : dnSwitchPoint7_p			
C01157/14	0.0000 units	L_SwitchPointPar_1 : dn2ndPoint_Size7_p			
C01157/15	0.0000 units	L_SwitchPointPar_1 : dnSwitchPoint8_p			
C01157/16	0.0000 units	L_SwitchPointPar_1 : dn2ndPoint_Size8_p			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000					

C01158

Parameter Name: C01158 L_SwitchPointPar_1: Invert		Data type: UNSIGNED_16 Index: 23417 _d = 5B79 _h
From version 12.00.00		
Setting range (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		Info
Bit 0	Invert Output1	Bit set = inversion active
Bit 1	Invert Output2	
Bit 2	Invert Output3	
Bit 3	Invert Output4	
Bit 4	Invert Output5	
Bit 5	Invert Output6	
Bit 6	Invert Output7	
Bit 7	Invert Output8	
Bit 8	Reserved	
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	Reserved	
Bit 15	Reserved	
Subcodes	Lenze setting	Info
C01158/1	0x0000	L_SwitchPointPar_1 : Inversion of outputs
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C01190

Parameter Name: C01190 Motor thermal sensor		Data type: UNSIGNED_8 Index: 23385 _d = 5B59 _h
Selection of the thermal sensor for monitoring the motor temperature ▶ Encoder/feedback system: Motor temperature monitoring (KTY)		
Selection list		Info
0	KTY83-110	Lenze standard KTY83-110 (MDSKX, MCS06)
1	Spec. characteristic	Characteristic defined via C01191 and C01192
2	KTY83-110 + 2 x PTC	Lenze standard KTY83-110 + 2 x PTC 150°C (MCS09-MCS19)
4	KTY84-130	Lenze standard KTY83-130
Subcodes	Lenze setting	Info
C01190/1	0: KTY83-110	Type of motor temperature sensor resolver
C01190/2	0: KTY83-110	Type of motor temperature sensor MultiEncoder
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C01191

Parameter Name: C01191 PTC characteristic: Temperature 1/2			Data type: UNSIGNED_8 Index: 23384 _d = 5B58 _h		
The spec. thermal sensor characteristic is selected through the setting C01190 ="1" ▶ Encoder/feedback system: Motor temperature monitoring (KTY)					
Setting range (min. value unit max. value)					
0	°C	255			
Subcodes	Lenze setting	Info			
C01191/1	100 °C	PTC characteristic: Temperature 1			
C01191/2	150 °C	PTC characteristic: Temperature 2			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C01192

Parameter Name: C01192 PTC characteristic: Resistance 1/2			Data type: INTEGER_32 Index: 23383 _d = 5B57 _h		
The spec. thermal sensor characteristic is selected through the setting <u>C01190="1"</u> ▶ <u>Encoder/feedback system: Motor temperature monitoring (KTY)</u>					
Setting range (min. value unit max. value)					
0	Ohm	30000			
Subcodes	Lenze setting		Info		
C01192/1	1070 Ohms		PTC characteristic: Resistance 1		
C01192/2	2225 Ohm		PTC characteristic: Resistance 2		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C01193

Parameter Name: C01193 Motor temp. feedback system		Data type: UNSIGNED_8 Index: 23382 _d = 5B56 _h	
Selection of the feedback system for monitoring the motor temperature ▶ Encoder/feedback system: Motor temperature monitoring (KTY)			
Selection list (Lenze setting printed in bold)			
0	Speed feedback		
1	Resolver input		
2	Encoder input		
5	Res. and enc. parallel		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C01201

Parameter Name: C01201 MCK: Cycle			Data type: INTEGER_32 Index: 23374 _d = 5B4E _h		
Cycle for Modulo measuring system <ul style="list-style-type: none">When the cycle is set to 0 units (Lenze setting), the traversing range is unlimited (classical measuring system).<div>► Activation of the Modulo measuring system</div>					
Setting range (min. value unit max. value)					
0.0000	units	214748.3647			
Subcodes	Lenze setting	Info			
C01201/1	0.0000 units	MCK: Cycle			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000					

C01202

Parameter Name: C01202 MCK: iM motor/process			Data type: UNSIGNED_16 Index: 23373 _d = 5B4D _h
Gearbox factor - motor			
• Entry of the gearbox factor as numerator/denominator ratio (numerator = motor speed and denominator = output speed of gearbox) or from the number of teeth of the gearbox arrangement.			
<div>▶ Machine parameter</div>			
Setting range (min. value unit max. value)			
1		65535	
Subcodes	Lenze setting	Info	
C01202/1	1	MCK: iM: Numerator gearbox factor Z2	
C01202/2	1	MCK: iM: Denominator gearbox factor Z1	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C01203

Parameter Name: C01203 MCK: iG motor/position encoder			Data type: UNSIGNED_16 Index: 23372 _d = 5B4C _h
Gearbox factor - position encoder			
• Entry of the gearbox factor as numerator/denominator ratio, with numerator = motor speed and denominator = position encoder speed.			
<div>▶ Machine parameter</div>			
Setting range (min. value unit max. value)			
1		65535	
Subcodes	Lenze setting	Info	
C01203/1	1	MCK: iG: Numerator (motor speed)	
C01203/2	1	MCK: iG: Denominator (encoder speed)	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C01204

Parameter Name: C01204 MCK: Feed constant			Data type: INTEGER_32 Index: 23371 _d = 5B4B _h
The feed constant corresponds to the movement of the machine during one revolution of the gearbox output shaft.			
<ul style="list-style-type: none"> The value is entered in application units referred to one revolution. 			
▶ Machine parameter			
Setting range (min. value unit max. value)			Lenze setting
0.0001	units/rev.	214748.3647	360.0000 units/rev.
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000			

C01205

Parameter Name: C01205 MCK: Position resolution			Data type: INTEGER_32 Index: 23370 _d = 5B4A _h
Display of the number of increments corresponding to one unit.			
<ul style="list-style-type: none"> 1 motor revolution \equiv 65536 increments 			
▶ Machine parameter			
Display range (min. value unit max. value)			
0.0000	Incr./unit	214748.3647	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000			

C01206

Parameter Name: C01206 MCK: Mounting direction		Data type: UNSIGNED_8 Index: 23369 _d = 5B49 _h	
Inversion for mirrored motor and encoder mounting			
<div>► Machine parameter</div>			
Selection list			
0	not inverted		
1	inverted		
Subcodes	Lenze setting	Info	
C01206/1	0: Not inverted	Motor mounting direction <ul style="list-style-type: none">• Setting for motor mounting turned by 180°.	
C01206/2	0: Not inverted	Position encoder mounting direction <ul style="list-style-type: none">• Setting for position encoder system mounting turned by 180°.	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input checked="" type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1</div>			

C01210

Parameter Name: C01210 MCK: Current positions			Data type: INTEGER_32 Index: 23365 _d = 5B45 _h
Display of current position data of the Motion Control Kernel			
Display range (min. value unit max. value)			
-214748.3647	units	214748.3647	
Subcodes			Info
C01210/1			MCK: Feed • Display of the current feed for positioning profiles as a relative distance.
C01210/2			MCK: Set position • Display of the current setpoint position calculated by the MCK.
C01210/3			MCK: Actual position • Display of the current actual position calculated by an optional encoder system.
C01210/4			MCK: Following error • Display of the current following error as a difference between setpoint position and actual position.
C01210/5			MCK: Positioning accuracy • Display of the current positioning accuracy referred to the actual number of increments of the position encoder.
C01210/6			MCK: Target position
C01210/7			MCK: Set position modulo
C01210/8			MCK: Actual position modulo • From version 12.00.00
C01210/9			MCK: Dist. ref. mark and Ref-TP • From version 14.00.00 • Display of the distance between pre-stop mark/limit switch and TP/MP while homing. ► Distance measurement
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000			

C01211

Parameter Name: C01211 MCK: Speed			Data type: INTEGER_32 Index: 23364 _d = 5B44 _h		
Display of the current speed data					
Display range (min. value unit max. value)					
-214748.3647	units/s	214748.3647			
Subcodes			Info		
C01211/1			MCK: Max. traversing speed 100%_C11 • Display of the maximum traversing speed based on the reference speed set in <u>C00011</u> .		
C01211/2			MCK: Set speed • From version 12.00.00		
C01211/3			MCK: Actual speed • From version 12.00.00		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000					

C01213

Parameter Name: C01213 MCK: Max. traversing distance			Data type: INTEGER_32 Index: 23362 _d = 5B42 _h		
Display of current position limits					
Display range (min. value unit max. value)					
-2147480000	units	2147480000			
Subcodes			Info		
C01213/1			MCK: Max. traversing distance • Display of the maximum distance to be traversed referred to the 32-bit display area (max. 2147483647 increments).		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01215

Parameter Name: C01215 MCK: Following error			Data type: INTEGER_32 Index: 23360 _d = 5B40 _h		
Limits for following error monitoring system					
▸ Following error monitoring system					
Setting range (min. value unit max. value)					
0.0000	units	214748.0000			
Subcodes	Lenze setting	Info			
C01215/1	0.0000 units	MCK: Following error limit 1 <ul style="list-style-type: none">• First limit of the maximum following error for monitoring and response activation.			
C01215/2	0.0000 units	MCK: Following error limit 2 <ul style="list-style-type: none">• Second limit of the maximum following error for monitoring and response activation.			
C01215/3	0.0000 units	MCK: Following error SetPos=ActPos <ul style="list-style-type: none">• From version 14.00.00 ▸ Monitoring of the following error in case of controller inhibit			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000					

C01216

Parameter | Name: **C01216 | MCK: Positioning setting**

Data type: UNSIGNED_8
Index: 23359_d = 5B3F_h

► [Positioning](#)

Setting range (min. hex value max. hex value)		Lenze setting
0x00		0xFF
Value is bit-coded: (<input checked="" type="checkbox"/> = bit set)		Info
Bit 0 <input checked="" type="checkbox"/>	PosAbort at PosInit	1 ≡ When a changeover to "positioning" mode is made, ramping down at the rate of deceleration set in C01251 for normal stopping is carried out.
Bit 1 <input type="checkbox"/>	PosExecute active at PosInit	1 ≡ When a changeover is made to the "positioning" mode, the specified profile is immediately executed if the "MCK PosExecute" control bit has also been set. If the MCK "PosExecute" control bit has not been set, the setpoint is continued.
Bit 2 <input type="checkbox"/>	Reserved	
Bit 3 <input type="checkbox"/>	Reserved	
Bit 4 <input type="checkbox"/>	ProfilStart at PosInit	1 ≡ When it is changed to the "Positioning" operating mode, the defined profile is executed immediately without the need to set the MCK control bit "PosExecute".
Bit 5 <input type="checkbox"/>	Maximum jerk	1 ≡ The maximum jerk is calculated based on the acceleration and S-ramp time of the current profile and the sequence profile. This is then used in an accelerated drive for reducing the acceleration to 0 or for acceleration of the sequence profile. • From version 14.00.00 ► Setting or activation of maximum jerk for traversing profiles
Bit 6 <input type="checkbox"/>	Reserved	
Bit 7 <input type="checkbox"/>	Reserved	

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT

C01218

Parameter | Name: **C01218 | MCK: Position follower setting**

Data type: UNSIGNED_8
Index: 23357_d = 5B3D_h

Settings for "Position follower" mode

[► Position follower](#)

Setting range (min. hex value max. hex value)		Lenze setting
0x00		0xFF
0x0C (decimal: 12)		
Value is bit-coded: (<input checked="" type="checkbox"/> = bit set)		Info
Bit 0 <input type="checkbox"/>	Speed FF control.: nSpeedSetValue_a	1 ≡ speed feedforward control value comes from main setpoint <i>nSpeedSetValue_a</i>
Bit 1 <input type="checkbox"/>	Speed FF control: nSpeedAddValue_v	1 ≡ speed feedforward control value comes from additive speed value <i>nSpeedAddValue_v</i>
Bit 2 <input checked="" type="checkbox"/>	HW limit switch on	1 ≡ Travel range monitoring via hardware limit switch is active. The error response can be parameterised in C00595/1 and C00595/2 .
Bit 3 <input checked="" type="checkbox"/>	SW limit switch on	1 ≡ Travel range monitoring via parameterised software limit positions is active. The error response can be parameterised in C00595/3 and C00595/4 .
Bit 4 <input type="checkbox"/>	Reserved	
Bit 5 <input type="checkbox"/>	Reserved	
Bit 6 <input type="checkbox"/>	Reserved	
Bit 7 <input type="checkbox"/>	Position controller off	1 ≡ Position controller is deactivated. Thus, the compensation of the following error is switched off.

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT

C01219

Parameter Name: C01219 MCK: Speed follower setting			Data type: UNSIGNED_8 Index: 23356 _d = 5B3C _h
Settings for "Speed follower" mode			
			► Speed follower
Setting range (min. hex value max. hex value)			Lenze setting
0x00		0xFF	0x0C (decimal: 12)
Value is bit-coded: (<input checked="" type="checkbox"/> = bit set)			Info
Bit 0 <input type="checkbox"/>	Reserved		
Bit 1 <input type="checkbox"/>	Reserved		
Bit 2 <input checked="" type="checkbox"/>	HW limit switch on		1 ≡ Travel range monitoring via hardware limit switch is active. The error response can be parameterised in C00595/1 and C00595/2 .
Bit 3 <input checked="" type="checkbox"/>	SW limit switch on		1 ≡ Travel range monitoring via parameterised software limit positions is active. The error response can be parameterised in C00595/3 and C00595/4 .
Bit 4 <input type="checkbox"/>	Reserved		
Bit 5 <input type="checkbox"/>	Reserved		
Bit 6 <input type="checkbox"/>	Reserved		
Bit 7 <input type="checkbox"/>	Position controller off		1 ≡ Position controller is deactivated. Thus, the compensation of the following error is switched off.
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT			

C01220

Parameter Name:		Data type: UNSIGNED_16	
C01220 MCK: Ref. setting		Index: 23355 _d = 5B3B _h	
From version 14.00.00			
Settings for "homing" mode			
<div>► Homing</div>			
Setting range (min. hex value max. hex value)			
0x0000		0xFFFF	
Value is bit-coded:		Info	
Bit 0	Reserved		
Bit 1	Reserved		
Bit 2	Reserved		
Bit 3	Reserved		
Bit 4	Start deletes bHomePosAvailable	1 ≡ When homing is started (mode 4 ... 15), the reference information is deleted.	
Bit 5	Maximum jerk	1 ≡ The maximum jerk is calculated based on the acceleration and S-ramp time of the current profile and the sequence profile. This is then used in an accelerated drive for reducing the acceleration to 0 or for acceleration of the sequence profile. ► Setting or activation of maximum jerk for traversing profiles	
Bit 6	Reserved		
Bit 7	Reserved		
Bit 8	Reserved		
Bit 9	Reserved		
Bit 10	Reserved		
Bit 11	Reserved		
Bit 12	Reserved		
Bit 13	Reserved		
Bit 14	Reserved		
Bit 15	Reserved		
Subcodes	Lenze setting	Info	
C01220/1	0x0000	MCK: Ref. setting	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT</div>			

C01221

Parameter Name: C01221 MCK: Ref. mode		Data type: UNSIGNED_8 Index: 23354 _d = 5B3A _h
Selection of the homing mode.		
<div>► Homing</div>		
Selection list (Lenze setting printed in bold)		Info
4	>_Rp_<_TP	Positive direction - reversing on pre-stop mark (pos. edge) - to touch probe <ul style="list-style-type: none">• From version 14.00.00
5	<_Rp_>_TP	Negative direction - reversing on pre-stop mark (pos. edge) - to touch probe <ul style="list-style-type: none">• From version 14.00.00
6	>_Rn_>_TP	Positive direction - via pre-stop mark (neg. edge) - continuing in positive direction - to touch probe
7	<_Rn_<_TP	Negative direction - via pre-stop mark (neg. edge) - continuing in negative direction - to touch probe
8	>_TP	Positive direction - to touch probe
9	<_TP	Negative direction - to touch probe
10	>_Lp_<_TP	Positive direction - reversing on pos. limit switch - to touch probe
11	<_Ln_>_TP	Negative direction - reversing on neg. limit switch - to touch probe
12	>_Lp	Positive direction - to pos. limit switch
13	<_Ln	Negative direction - to neg. limit switch
14	>_Mlim	Positive direction towards torque limit (C01222)
15	<_Mlim	Negative direction towards torque limit (C01222)
100	SetRef	Direct acceptance and setting of the home position <ul style="list-style-type: none">• The measuring system is set based on the home position parameterised in C01227/2 when the drive is at standstill.
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1</div>		

C01222

Parameter Name: C01222 MCK: Ref. M limit mode 14/15			Data type: INTEGER_16 Index: 23353 _d = 5B39 _h	
Torque limit for homing modes 14 and 15 (homing towards positive stop) • 100 % ≡ maximum torque (C00057)				
<div>► Homing</div>				
Setting range (min. value unit max. value)			Lenze setting	
0.00	%	199.99	10.00 %	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 100</div>				

C01223

Parameter Name: C01223 MCK: Ref. waiting time mode 14/15			Data type: UNSIGNED_16 Index: 23352 _d = 5B38 _h		
Blocking time for homing modes 14 and 15 (homing towards positive stop) <ul style="list-style-type: none">• The reference is set if an excess of the torque limit set in C01222 has been detected over a time period defined here.					
<div>▶ Homing</div>					
Setting range (min. value unit max. value)			Lenze setting		
0	ms	65000	100 ms		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01224

Parameter Name: C01224 MCK: Ref. speeds			Data type: INTEGER_32 Index: 23351 _d = 5B37 _h		
Speeds for reference search/homing					
<div>▶ Homing</div>					
Setting range (min. value unit max. value)					
0.0000	unit/s	214748.3647			
Subcodes	Lenze setting		Info		
C01224/1	720.0000 unit/s		MCK: Ref. initial speed <ul style="list-style-type: none">Start speed for quick approach of the limit switch/pre-stop mark (depending on the selected homing mode).		
C01224/2	180.0000 unit/s		MCK: Ref. search speed <ul style="list-style-type: none">Search speed for slower - but more precise - approaching of the touch probe sensor (sensor reference signal).		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 10000</div></div>					

C01225

Parameter Name: C01225 MCK: Ref. accelerations			Data type: INTEGER_32 Index: 23350 _d = 5B36 _h		
Accelerations for reference search/homing					
<div>▶ Homing</div>					
Setting range (min. value unit max. value)					
0.0000	unit/s2	214748.3647			
Subcodes	Lenze setting	Info			
C01225/1	720.0000 unit/s2	MCK: Ref. initial acceleration • Starting acceleration for the starting speed ramps.			
C01225/2	720.0000 unit/s2	MCK: Ref. search acceleration • Search acceleration for the search speed ramps.			
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000</div>					

C01226

Parameter Name: C01226 MCK: Ref. S-ramp time			Data type: UNSIGNED_16 Index: 23349 _d = 5B35 _h		
S-ramp time for reference search/homing • Setting "0 s" ≡ no rounding					
<div>► Homing</div>					
Setting range (min. value unit max. value)					
0.000	s	10.000			
Subcodes	Lenze setting		Info		
C01226/1	0.000 s		MCK: Ref. S-ramp time • S-ramp time for the starting and search speed ramps.		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1000</div></div>					

C01227

Parameter Name: C01227 MCK: Ref. positions			Data type: INTEGER_32 Index: 23348 _d = 5B34 _h		
Positions for determining the zero position of the reference measuring system					
<div>► Homing</div>					
Setting range (min. value unit max. value)					
-214748.3647	unit	214748.3647			
Subcodes	Lenze setting		Info		
C01227/1	0.0000 unit		MCK: Ref. offset reference degree <ul style="list-style-type: none">Relative traverse path by which the drive traverses correctly signed with search speed after detection of the sensor reference signal.		
C01227/2	0.0000 unit		MCK: Ref. home position <ul style="list-style-type: none">Position with which setpoint and actual position are loaded after completion of homing.		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 10000</div></div>					

C01228

Parameter Name: C01228 MCK: Ref. sequence profile			Data type: UNSIGNED_8 Index: 23347 _d = 5B33 _h		
Number of the sequence profile the absolute position of which will be approached after homing.					
<div>► Homing</div>					
Setting range (min. value unit max. value)			Lenze setting		
0		15	0		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>					

C01229

Parameter | Name: Data type: INTEGER_32
Index: 23346_d = 5B32_h

C01229 | MCK: Position limiting values

Software limit position for limiting the valid traversing range

- The error response to leaving the valid traversing range can be parameterised in [C00595/3](#) and [C00595/4](#).

Note:

For limiting the traversing range by means of software limit positions, the home position must be known and the positive software limit position must be higher than the negative software limit position!

▶ [Limit position monitoring](#)

Setting range (min. value unit max. value)			
-214748.3647	units	214748.3647	
Subcodes	Lenze setting	Info	
C01229/1	0.0000 units	MCK: Positive SW limit position (positive travel range limit)	
C01229/2	0.0000 units	MCK: Negative SW limit position (negative travel range limit)	

☒ Read access

☒ Write access

☐ CINH

☐ PLC STOP

☐ No transfer

☐ COM

☐ MOT

Scaling factor: 10000

C01230

Parameter Name: C01230 Manual jog: Setting			Data type: UNSIGNED_8 Index: 23345 _d = 5B31 _h		
Settings for "Manual jog" mode					
▶ Manual jog					
Setting range (min. hex value max. hex value)			Lenze setting		
0x00		0xFF	0x00 (decimal: 0)		
Value is bit-coded: (☑ = bit set)			Info		
Bit 0 ☐	Breakpoints 1..4 on		1 ≡ approach of the parameterised breakpoint in manual jog direction		
Bit 1 ☐	Time-based start of 2nd speed		1 ≡ Automatic change-over to second manual speed after the wating time set in C01235/1 .		
Bit 2 ☐	HW limit switch on		1 ≡ Travel range monitoring via hardware limit switch is active. The error response can be parameterised in C00595/1 and C00595/2 .		
Bit 3 ☐	SW limit switch on		1 ≡ Travel range monitoring via parameterised software limit positions is active. The error response can be parameterised in C00595/3 and C00595/4 .		
Bit 4 ☐	Reserved				
Bit 5 ☐	Maximum jerk		1 ≡ The maximum jerk is calculated based on the acceleration and S-ramp time of the current profile and the sequence profile. This is then used in an accelerated drive for reducing the acceleration to 0 or for acceleration of the sequence profile. • From version 14.00.00 ▶ Setting or activation of maximum jerk for traversing profiles		
Bit 6 ☐	Reserved				
Bit 7 ☐	Position controller off		1 ≡ Position controller is deactivated. Thus, the compensation of the following error is switched off.		
☑ Read access ☑ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT					

C01231

Parameter Name: C01231 MCK: Manual jog speeds			Data type: INTEGER_32 Index: 23344 _d = 5B30 _h		
Manual jog speeds					
▸ Manual jog					
Setting range (min. value unit max. value)					
-214748.3647	units/s	214748.3647			
Subcodes	Lenze setting		Info		
C01231/1	360.0000 units/s		Manual jog: speed 1 • Regular manual speed		
C01231/2	720.0000 units/s		Manual jog: Speed 2 • Second manual speed (can be activated via MCK control word)		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000					

C01232

Parameter Name: C01232 MCK: Manual jog accelerations			Data type: INTEGER_32 Index: 23343 _d = 5B2F _h		
Acceleration/deceleration for manual jog					
<div>▶ Manual jog</div>					
Setting range (min. value unit max. value)					
-214748.3647	units/s2	214748.3647			
Subcodes	Lenze setting	Info			
C01232/1	720.0000 units/s2	Manual jog: Acceleration <ul style="list-style-type: none">• Acceleration for ramp-up to manual speed.			
C01232/2	720.0000 units/s2	Manual jog: Deceleration <ul style="list-style-type: none">• Deceleration for manual speed ramp-down to standstill.			
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 10000</div></div>					

C01233

Parameter Name: C01233 MCK: Manual jog S-ramp time			Data type: UNSIGNED_16 Index: 23342 _d = 5B2E _h		
S-ramp time for manual jog <ul style="list-style-type: none">Setting "0 s" ≡ no rounding					
▸ Manual jog					
Setting range (min. value unit max. value)					
0.000	s	10.000			
Subcodes	Lenze setting		Info		
C01233/1	0.000 s		Manual jog: S-ramp time <ul style="list-style-type: none">S-ramp time for the manual speed ramps.		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C01234

Parameter Name: C01234 MCK: Manual jog breakpoints			Data type: INTEGER_32 Index: 23341 _d = 5B2D _h		
Breakpoint positions for manual jog					
<ul style="list-style-type: none">The drive stops at the parameterised positions if these are located in the manual jog direction and the approaching of the breakpoints is switched on in C01230 via bit 0.					
▶ Manual jog					
Setting range (min. value unit max. value)					
-214748.3647	unit	214748.3647			
Subcodes	Lenze setting		Info		
C01234/1	0.0000 unit		Manual jog: Breakpoint 1		
C01234/2	0.0000 unit		Manual jog: Breakpoint 2		
C01234/3	0.0000 unit		Manual jog: Breakpoint 3		
C01234/4	0.0000 unit		Manual jog: Breakpoint 4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000					

C01235

Parameter Name: C01235 MCK: Manual jog waiting times			Data type: UNSIGNED_16 Index: 23340 _d = 5B2C _h		
Waiting times for manual jog					
▶ Manual jog					
Setting range (min. value unit max. value)					
0.000	s	65.000			
Subcodes	Lenze setting		Info		
C01235/1	5.000 s		Manual jog: Waiting time 2nd speed • Time after which the first manual speed (C01231/1) is accelerated to the second manual speed (C01231/2).		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C01236

Parameter Name: C01236 MCK: Speed follower			Data type: INTEGER_32 Index: 23339 _d = 5B2B _h		
Speeds for position follower					
<div>► Position follower</div>					
Setting range (min. value unit max. value)					
-214748.3647	units/s	214748.3647			
Subcodes	Lenze setting		Info		
C01236/1	360.0000 units/s		PosFollower: Sync. speed • Synchronisation speed for approaching the setpoint position of the master.		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 10000</div></div>					

C01237

Parameter Name: C01237 MCK: Acceleration follower			Data type: INTEGER_32 Index: 23338 _d = 5B2A _h		
Accelerations for position follower					
<div>► Position follower</div>					
Setting range (min. value unit max. value)					
-214748.3647	units/s ²	214748.3647			
Subcodes	Lenze setting	Info			
C01237/1	720.0000 units/s ²	Pos follower: Sync. accel. • Acceleration for ramp-up to synchronisation speed.			
C01237/2	720.0000 units/s ²	Pos follower: Sync. decel. • Deceleration for synchronisation speed ramp-down to standstill (to the setpoint position of the master).			
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 10000</div></div>					

C01238

Parameter Name: C01238 MCK: S-ramp time follower			Data type: UNSIGNED_16 Index: 23337 _d = 5B29 _h		
S-ramp times for position follower <ul style="list-style-type: none">Setting "0 s" ≡ no rounding					
► Position follower					
Setting range (min. value unit max. value)					
0.000	s	10.000			
Subcodes	Lenze setting		Info		
C01238/1	0.000 s		Pos follower: Sync. S-ramp time <ul style="list-style-type: none">S-ramp time for the synchronisation speed ramps.		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C01239

Parameter Name: C01239 Setpoint holding			Data type: UNSIGNED_32 Index: 23336 _d = 5B28 _h		
From version 12.00.00					
▸ Setpoint holding for bus runtime compensation					
Setting range (min. value unit max. value)			Lenze setting		
0	ms	32	0 ms		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01240

Parameter Name: C01240 MCK: Control word		Data type: UNSIGNED_32 Index: 23335 _d = 5B27 _h	
Bit-coded status of the MCK control word			
• The MCK control word is used to control the functions of the Motion Control Kernel.			
<div>► MCK control word</div>			
Display area (min. hex value max. hex value)			
0x00000000	0xFFFFFFFF		
Value is bit-coded:		Info	
Bit 0	OpMode_Bit0	Active operating mode - control bit 0	
Bit 1	OpMode_Bit1	Active operating mode - control bit 1	
Bit 2	OpMode_Bit2	Active operating mode - control bit 2	
Bit 3	OpMode_Bit3	Active operating mode - control bit 4	
Bit 4	ManJogPos	Control bit for manual jog in positive direction	
Bit 5	ManJogNeg	Control bit for manual jog in negative direction	
Bit 6	ManExecute2ndSpeed	Control bit for activation of second manual speed	
Bit 7	ReleaseLimitSwitch	Control bit for retracting the hardware limit positions	
Bit 8	HomStartStop	Control bit for start/stop homing	
Bit 9	HomSetPos	Control bit for setting of home position <ul style="list-style-type: none">• 0->1 ≡ sets position setpoint and actual position value to the home position at the MCK.• This function is independent of the operating modes.	
Bit 10	HomResetPos	Control bit for reset of home position <ul style="list-style-type: none">• 0->1 ≡ resets the information bit for the status "Home position known" (home position not known).• The position displays are not influenced by this.	
Bit 11	EnableSpeedOverride	Control bit for activation of speed override <ul style="list-style-type: none">• 1 ≡ activation of the override speed at the MCK for acceptance in a running speed profile.	
Bit 12	EnableAccOverride	Control bit for activation of acceleration override <ul style="list-style-type: none">• 1 ≡ activation of the override acceleration at the MCK for acceptance in a running speed profile.	
Bit 13	EnableSRampOverride	Control bit for deactivation of S-shaping for speed profiles <ul style="list-style-type: none">• 1 ≡ deactivates S-shaping for speed profiles	
Bit 14	PosTeachSetPos	Control bit for accepting the selected setpoint position in the selected profile <ul style="list-style-type: none">• 0->1 ≡ accepts the setpoint position at the MCK in the profile with the profile number defined via the MCK control word.	
Bit 15	PosTeachActPos	Control bit for accepting the current actual position in the selected profile <ul style="list-style-type: none">• 0->1 ≡ accepts the current actual position in the profile with the profile number defined via the MCK control word.	
Bit 16	PosExecute	Control bit for starting a positioning profile <ul style="list-style-type: none">• 0->1 ≡ starts a positioning profile selected via the control word in the "Positioning" mode.	

Parameter Name: C01240 MCK: Control word		Data type: UNSIGNED_32 Index: 23335 _d = 5B27 _h
Bit 17	PosFinishTarget	Control bit for completing processing of an interrupted positioning profile <ul style="list-style-type: none"> • 0->1 ≡ processing of a positioning profile which has already been started and has been interrupted because of a cancellation condition or a change of the operating mode is completed in the "Positioning" mode when the home position is known. Note: Completion of profile processing through this control is based on the target position detected at the profile start!
Bit 18	PosDisableFollowProfile	Control bit for suppression of the sequence profile <ul style="list-style-type: none"> • 1 ≡ positioning profiles whose profile numbers are entered in profile data sets for sequence profiles are not started after completion of the corresponding profile.
Bit 19	PosStop	Control bit for stopping the positioning profile <ul style="list-style-type: none"> • 0->1 ≡ ("Positioning" mode): Interrupts a running profile through deceleration along the set deceleration ramp to standstill. • 0->1 ≡ ("Stop" mode): Starts a new deceleration to standstill with the parameterised stop ramp.
Bit 20	PosModeBit0	Active positioning mode - control bit 0
Bit 21	PosModeBit1	Active positioning mode - control bit 1
Bit 22	PosModeBit2	Active positioning mode - control bit 2
Bit 23	PosModeBit3	Active positioning mode - control bit 3
Bit 24	ProfileNo_Bit0	Active positioning profile number - control bit 0
Bit 25	ProfileNo_Bit1	Active positioning profile number - control bit 1
Bit 26	ProfileNo_Bit2	Active positioning profile number - control bit 2
Bit 27	ProfileNo_Bit3	Active positioning profile number - control bit 3
Bit 28	ProfileNo_Bit4	Active positioning profile number - control bit 4
Bit 29	ProfileNo_Bit5	Active positioning profile number - control bit 5
Bit 30	ProfileNo_Bit6	Active positioning profile number - control bit 6
Bit 31	ProfileNo_Bit7	Active positioning profile number - control bit 7
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C01241

Parameter Name: C01241 MCK: Status word		Data type: UNSIGNED_32 Index: 23334 _d = 5B26 _h	
Bit-coded status of the MCK status word			
• The MCK status word is used to output status messages of the MotionControlKernel.			
<div>► MCK status word</div>			
Display area (min. hex value max. hex value)			
0x00000000		0xFFFFFFFF	
Value is bit-coded:		Info	
Bit 0	ActOpModeBit00	Active operating mode - status bit 0	
Bit 1	ActOpModeBit01	Active operating mode - status bit 1	
Bit 2	ActOpModeBit02	Active operating mode - status bit 2	
Bit 3	ActOpModeBit03	Active operating mode - status bit 4	
Bit 4	Busy	Status bit - profile generation active <ul style="list-style-type: none">• 1 ≡ Internal profile generation is active. A speed profile is being generated.	
Bit 5	Done	Status bit - profile generation completed <ul style="list-style-type: none">• 1 ≡ Generation of a speed profile with the selected position has been completed.	
Bit 6	AcceleratingActive	Status bit - acceleration process for profile generation active <ul style="list-style-type: none">• 1 ≡ Profile generation phase is in the acceleration process.	
Bit 7	ConstSpeedDuty	Status bit - constant speed for profile generation active <ul style="list-style-type: none">• 1 ≡ Profile generation phase at constant speed active.	
Bit 8	DeceleratingActive	Status bit - deceleration process for profile generation active <ul style="list-style-type: none">• 1 ≡ Profile generation phase is in the deceleration process.	
Bit 9	S_ShapingActive	Status bit - rounding for profile generation active <ul style="list-style-type: none">• 1 ≡ Rounding during acceleration/deceleration active.	
Bit 10	Pos. HW-Limit Detected	Status bit - positive hardware limit detected <ul style="list-style-type: none">• 1 ≡ Positive limit switch has triggered.• Reset only possible via "Manual jog" mode!	
Bit 11	Neg. HW-Limit Detected	Status bit - negative hardware limit detected <ul style="list-style-type: none">• 1 ≡ Negative limit switch has triggered.• Reset only possible via "Manual jog" mode!	
Bit 12	HomPosDone	Status bit - homing completed <ul style="list-style-type: none">• 1 ≡ Homing has been completed.	
Bit 13	HomPosAvailable	Status bit - home position known <ul style="list-style-type: none">• 1 ≡ The home position has been detected and is known in the drive.	
Bit 14	Pos. SW-Limit Detected	Status bit - positive software limit detected <ul style="list-style-type: none">• 1 ≡ Positive software limit position overtravelled.	
Bit 15	Neg. SW-Limit Detected	Status bit - negative software limit detected <ul style="list-style-type: none">• 1 ≡ Negative software limit position overtravelled.	
Bit 16	DwellTime	Status bit - transient effects in target position active <ul style="list-style-type: none">• 1 ≡ Dwell time after reaching the setpoint position is active.	
Bit 17	InTarget	Status bit - actual position is in the target window <ul style="list-style-type: none">• 1 ≡ Dwell time has expired and current actual position is in the set target window.	

Parameter Name: C01241 MCK: Status word		Data type: UNSIGNED_32 Index: 23334 _d = 5B26 _h
Bit 18	PosDone	Status bit - positioning process completed • 1 ≡ Positioning profile has been completed in the "Positioning" mode. Setpoint position is in target.
Bit 19	Reserved	
Bit 20	ActPosMode_Bit00	Active positioning mode - status bit 0
Bit 21	ActPosMode_Bit01	Active positioning mode - status bit 1
Bit 22	ActPosMode_Bit02	Active positioning mode - status bit 2
Bit 23	ActPosMode_Bit03	Active positioning mode - status bit 3
Bit 24	ActProfileNo_Bit00	Active positioning profile - status bit 0
Bit 25	ActProfileNo_Bit01	Active positioning profile - status bit 1
Bit 26	ActProfileNo_Bit02	Active positioning profile - status bit 2
Bit 27	ActProfileNo_Bit03	Active positioning profile - status bit 3
Bit 28	ActProfileNo_Bit04	Active positioning profile - status bit 4
Bit 29	ActProfileNo_Bit05	Active positioning profile - status bit 5
Bit 30	ActProfileNo_Bit06	Active positioning profile - status bit 6
Bit 31	ActProfileNo_Bit07	Active positioning profile - status bit 7
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C01242

Parameter Name: C01242 MCK: Current pos profile number		Data type: UNSIGNED_8 Index: 23333 _d = 5B25 _h
Display of the current profile number of the active profile in the "Positioning" mode		
► Positioning		
Display range (min. value unit max. value)		
0		255
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01243

Parameter Name: C01243 MCK: Current operating mode		Data type: UNSIGNED_8 Index: 23332 _d = 5B24 _h
Display of the active operating mode of the Motion Control Kernel		
► Basic drive functions		
Selection list (read only)		Info
0	Speed follower	Drive traverses according to a preselected speed setpoint
1	Homing	Drive finds its reference measuring system by setting the home position or homing
2	ManualJog	Drive can be traversed manually via initiators, e.g. for cleaning purposes or tool changes.
3	Positioning	Drive traverses according to defined travel profiles and motion processes
4	Stop	Drive is decelerated to standstill along a parameterised deceleration ramp
5	Position follower	Drive traverses according to a preselected position setpoint
15	StandBy	Internal operating mode for quick stop and pulse inhibit
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01244

Parameter | Name:
C01244 | MCK: Target detection - times

Data type: UNSIGNED_16
Index: 23331_d = 5B23_h

Timing for various MCK functions

Setting range (min. value unit max. value)		
0	ms	60000
Subcodes	Lenze setting	Info
C01244/1	100 ms	MCK: Dwell time - target position <ul style="list-style-type: none">Time expiring after reaching the setpoint position for positioning processes and enabling the actual position detection in the target position window. ▶ Target position monitoring
C01244/2	0 ms	MCK: Waiting time following error 1 <ul style="list-style-type: none">From version 02.00.00 ▶ Following error monitoring system
C01244/3	0 ms	MCK: Waiting time following error 2 <ul style="list-style-type: none">From version 02.00.00 ▶ Following error monitoring system

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT Scaling factor: 1

C01245

Parameter Name: C01245 MCK: Target detection - positions			Data type: INTEGER_32 Index: 23330 _d = 5B22 _h
Position settings for various MCK functions			
Setting range (min. value unit max. value)			
0.0000	units	214748.3647	
Subcodes	Lenze setting	Info	
C01245/1	1.0000 units	MCK: Window target position • Window around the target position for comparison with the actual position to see whether the drive is in target. ▶ Target position monitoring	
C01245/2	1.0000 units	MCK: Blocking zone Modulo ▶ Activation of the Modulo measuring system	
C01245/3	0.0000 units	MCKI: Hysteresis position change	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000			

C01246

Parameter Name: C01246 MCK: Select signal source		Data type: UNSIGNED_8 Index: 23329 _d = 5B21 _h
Selection of the touch probe signal source for reference search with touch probe detection <ul style="list-style-type: none"> If the reference signal is to follow a real touch probe, the Touch-Probe-Interface must be configured accordingly. ► Homing 		
Selection list		Info
0	No TP	
3	TP-DigIn3	
4	TP-DigIn4	
5	TP-DigIn5	
6	TP-DigIn6	
7	TP-DigIn7	
8	TP-Z-trace encoder	From version 12.00.00
9	TP-Z-trace resolver	From version 12.00.00
Subcodes	Lenze setting	Info
C01246/1	0: No TP	MCK: Ref. TP signal source Note: In case of setting "0: No TP", the digital input DI3 is used as signal source for reference search. An inversion of DI3 via C00114 is considered.
C01246/2	0: No TP	MCK: Set.Ref. signal source
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01247

Parameter Name: C01247 MCK: Diagnostic word		Data type: UNSIGNED_32 Index: 23328 _d = 5B20 _h
From version 15.00.00		
Display area (min. hex value max. hex value)		
0x00000000	0xFFFFFFFF	
Value is bit-coded:		Info
Bit 0	Traversing range: Limited	1 ≡ The traversing range is limited: <ul style="list-style-type: none"> The software limit positions are set. The reference is known. There is no modulo measuring system available (C01201/1 = 0). Note: This status does not consider whether the software limit positions are activated or deactivated by the settings in the prevailing operating mode.
Bit 1	Traversing range: Modulo	1 ≡ A modulo measuring system is available as a cycle length has been set in C01201/1 .
Bit 2	Reserved	
Bit 3	Reserved	
Bit 4	Reserved	
Bit 5	Reserved	
Bit 6	Reserved	
Bit 7	Reserved	
Bit 8	SpeedNormConstant: Low-Limit	1 ≡ Due to the set machine parameters, an internal calculation constant is limited to a possible minimum. Remedy: Increase reference speed in C00011 .

Parameter Name: C01247 MCK: Diagnostic word		Data type: UNSIGNED_32 Index: 23328 _d = 5B20 _h
Bit 9	SpeedNormConstant: Up-Limit	1 ≡ Due to the set machine parameters, an internal calculation constant is limited to a possible maximum. Remedy: Reduce reference speed in C00011 .
Bit 10	Max. speed limit	1 ≡ Due to the set machine parameters, the maximum speed for specifications in [units/s] are limited to the factor 150 %.
Bit 11	Quick stop is active	1 ≡ Quick stop function is active.
Bit 12	Quick stop standstill is active	1 ≡ Standstill during active quick stop function (no ramp generation).
Bit 13	Reserved	
Bit 14	Reserved	
Bit 15	Reserved	
Bit 16	Reserved	
Bit 17	Reserved	
Bit 18	Reserved	
Bit 19	Reserved	
Bit 20	Reserved	
Bit 21	Reserved	
Bit 22	Reserved	
Bit 23	Reserved	
Bit 24	Reserved	
Bit 25	Reserved	
Bit 26	Reserved	
Bit 27	Reserved	
Bit 28	Reserved	
Bit 29	Reserved	
Bit 30	Reserved	
Bit 31	Reserved	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C01251

Parameter Name: C01251 MCK: Acceleration stop		Data type: INTEGER_32 Index: 23324 _d = 5B1C _h
Acceleration parameter for stop		
Stop		
Setting range (min. value unit max. value)		
-214748.3647	units/s ²	214748.3647
Subcodes	Lenze setting	Info
C01251/1	720.0000 units/s ²	MCK: Stop: Decel. • Deceleration for setpoint speed ramp-down to standstill.
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000		

C01252

Parameter Name: C01252 MCK: S-ramp times stop			Data type: UNSIGNED_16 Index: 23323 _d = 5B1B _h
S-ramp times for stop <ul style="list-style-type: none">Setting "0 s" ≡ no rounding			
► Stop			
Setting range (min. value unit max. value)			
0.000	s	10.000	
Subcodes	Lenze setting		Info
C01252/1	0.000 s		MCK: Stop: S-ramp time <ul style="list-style-type: none">S-ramp time for setpoint speed ramp-down to standstill.
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000			

C01294

Parameter Name: C01294 Mode: Position calculation		Data type: UNSIGNED_8 Index: 23281 _d = 5AF1 _h
From version 12.00.00		
Selection of the conversion mode		
Selection list		
0	dnOut_p=ConvWordsToDInt(HW_L W)	
1	16 bits: LW=+/-32767	
2	16 bits: HW=+/-; LW=0..65535	
3	32Bit: HW_LW=+/-214748.3647	
Subcodes	Lenze setting	Info
C01294/1	0: dnOut_p=ConvWordsToDInt(HW_L W)	L_ConvUnitsToIncr_1 : PosCalcMode
C01294/2	0: dnOut_p=ConvWordsToDInt(HW_L W)	L_ConvUnitsToIncr_2 : PosCalcMode
C01294/3	0: dnOut_p=ConvWordsToDInt(HW_L W)	L_ConvUnitsToIncr_3 : PosCalcMode
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01295

Parameter Name: C01295 L_MCKStateInterface_1: Pos. selection		Data type: UNSIGNED_8 Index: 23280 _d = 5AF0 _h
Selection of the position to be provided at the <i>dnPosOut_p</i> output of the FB L_MckStateInterface		
Selection list (Lenze setting printed in bold)		
0	dnPosIn_p	
1	Current feed	
2	dnSetPos_p	
3	dnActPos_p	
4	dnDeltaPos_p	
5	dnTargetPos_p	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01296

Parameter Name: C01296 Mode: Position calculation		Data type: UNSIGNED_8 Index: 23279 _d = 5AEF _h
		► MCKInterface
Selection list		
0	dnPosOut_p=dnPosIn_p	
1	16 bits: LW=+/-32767	
2	16 bits: HW=+/-; LW=0..65535	
3	32Bit: HW_LW=+/-214748.3647	
Subcodes	Lenze setting	Info
C01296/1	0: dnPosOut_p=dnPosIn_p	L_MckCtrlInterface_1 : PosCalcMode
C01296/2	1: 16Bit: LW=+/-32767	L_MckStateInterface_1 : PosDisplayMode
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01297

Parameter Name: C01297 L_MckCtrlInterface_1: Alternative function		Data type: UNSIGNED_8 Index: 23278 _d = 5AE _E _h
Selection of the alternative function for bit 16 (PosExecute) in the MCK control word ► Alternative functions for "PosExecute" control bit		
Setting range (min. hex value max. hex value)	Lenze setting	
0x00	0xFF	0x03 (decimal: 3)
Value is bit-coded: (<input checked="" type="checkbox"/> = bit set)	Info	
Bit 0 <input checked="" type="checkbox"/>	PosStop with PosExecute = FALSE	1 ≙ Abort positioning with PosExecute • PosExecute="0" stops a running positioning process by ramp-down to standstill.
Bit 1 <input checked="" type="checkbox"/>	HomingStartStop with PosExecute	1 ≙ Start/stop homing with PosExecute • PosExecute="1" starts homing, PosExecute="0" stops homing in the "Homing" mode.
Bit 2 <input type="checkbox"/>	SetProfilPosition with PosExecute	1 ≙ Teach set position with PosExecute • PosExecute="0->1" accepts the setpoint position at the MCK in the profile with the specified profile number.
Bit 3 <input type="checkbox"/>	SetProfilPosition at position change	1 ≙ Automatic acceptance of set position • The set position pending at the MCKInterface is automatically transferred to the profile with the preset profile number if a data change at the corresponding input for the setpoint is detected.
Bit 4 <input type="checkbox"/>	Profile start at position change	From version 02.00.00 1 ≙ Automatic profile start at position change • An automatic PosExecute takes place if the incremental position selection changes and this change is higher than set in the hysteresis for position change (C01245/3).
Bit 5 <input type="checkbox"/>	Reserved	
Bit 6 <input type="checkbox"/>	Reserved	
Bit 7 <input type="checkbox"/>	Reserved	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C01298

Parameter | Name:

C01298 | MCK: Operating mode change with profile no.

Data type: UNSIGNED_8
Index: 23277_d = 5AED_h

FB [L_MckCtrlInterface_1](#): Assignment of an operating mode to a profile

Selection list		Info
0	No change	There will be no changed operating mode when the profile is changed. Instead, the operating mode requested "from outside" via the MCK control word applies.
1	Follower	Change to the "Speed follower" mode
2	Homing	Change to the "Homing" mode
3	ManualJog	Change to the "Manual jog" mode
4	Positioning	Change to the "Positioning" mode
Subcodes	Lenze setting	Info
C01298/1	1: Follower	MCK operating mode at profile no. 0 <ul style="list-style-type: none">Selection of the operating mode for profile 0 at L_MckCtrlInterface_1.
C01298/2	2: Homing	MCK operating mode at profile no. 1 <ul style="list-style-type: none">Selection of the operating mode for profile 1 at L_MckCtrlInterface_1.
C01298/3	3: ManualJog	MCK operating mode at profile no. 2 <ul style="list-style-type: none">Selection of the operating mode for profile 2 at L_MckCtrlInterface_1.
C01298/4	4: Positioning	MCK operating mode at profile no. 3...15 <ul style="list-style-type: none">Selection of the operating mode for profile 3 ... 15 at L_MckCtrlInterface_1.

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT Scaling factor: 1

C01299

Parameter Name: C01299 MCKI: Status MCKInterface		Data type: UNSIGNED_8 Index: 23276 _d = 5AEC _h	
FB L_MckCtrlInterface_1 : Status messages			
Display area (min. hex value max. hex value)			
0x00		0xFF	
Value is bit-coded:			Info
Bit 0	InvalidOperationMode	Invalid operating mode selection • 1 ≡ The selected operating mode is not defined/invalid.	
Bit 1	InvalidPosMode	Invalid positioning mode selection • 1 ≡ The selected positioning mode is not defined/invalid.	
Bit 2	InvalidProfileNo	Invalid profile number selection • 1 ≡ The selected profile number refers to a profile data set that does not exist.	
Bit 3	Reserved		
Bit 4	Reserved		
Bit 5	Reserved		
Bit 6	Reserved		
Bit 7	Reserved		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT			

C01300

Parameter Name: C01300 Profile data: Positioning mode		Data type: UNSIGNED_8 Index: 23275 _d = 5AEB _h
Selection of the positioning mode for profiles 1 ... 15		
<div>► Profile entry</div>		
Selection list		Info
1	Absolute (shortest path)	Absolute positioning <ul style="list-style-type: none">The profile position corresponds to the target position.
2	Continuous	Continuous positioning without approaching a target position
3	Relative	Relative positioning <ul style="list-style-type: none">The profile position determines the distance to be traversed.
4	absolute (Cw)	Clockwise absolute positioning <ul style="list-style-type: none">The zero position of the axis can be exceed in this direction.The profile position corresponds to the target position.
5	absolute (Ccw)	Counter-clockwise absolute positioning <ul style="list-style-type: none">The zero position of the axis can be exceed in this direction.The profile position corresponds to the target position.
8	Absolute (shortest path) to TP	Absolute positioning <ul style="list-style-type: none">The profile position corresponds to the target position.After a touch probe is detected, the TP profile (C01308/1...15) is executed.
9	Continuous to TP	Continuous positioning without approaching a target position <ul style="list-style-type: none">After a touch probe is detected, the TP profile (C01308/1...15) is executed.
10	Relative to TP	Relative positioning <ul style="list-style-type: none">The profile position determines the distance to be traversed.After a touch probe is detected, the TP profile (C01308/1...15) is executed.
11	Absolute (Cw) on TP	Clockwise absolute positioning <ul style="list-style-type: none">The zero position of the axis can be exceed in this direction.The profile position corresponds to the target position.After a touch probe is detected, the TP profile (C01308/1...15) is executed.
12	Absolute (Ccw) on TP	Counter-clockwise absolute positioning <ul style="list-style-type: none">The zero position of the axis can be exceed in this direction.The profile position corresponds to the target position.After a touch probe is detected, the TP profile (C01308/1...15) is executed.
Subcodes	Lenze setting	Info
C01300/1	1: absolute (beeline)	Profiles 1 ... 15: Positioning mode
C01300/...		
C01300/15		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1</div>		

C01301

Parameter Name: C01301 Profile data: Position			Data type: INTEGER_32 Index: 23274 _d = 5AEAh _h		
Selection of the positions for profiles 1 ... 15					
<div>► Profile entry</div>					
Setting range (min. value unit max. value)					
-214748.3647	unit	214748.3647			
Subcodes		Lenze setting	Info		
C01301/1	360.0000 unit		Profiles 1 ... 15: Position		
C01301/...					
C01301/15					
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 10000</div></div>					

C01302

Parameter Name: C01302 Profile data: Speed			Data type: INTEGER_32 Index: 23273 _d = 5AE9 _h		
Selection of the maximum speeds for profiles 1 ... 15					
<div>► Profile entry</div>					
Setting range (min. value unit max. value)					
-214748.3647	unit/s	214748.3647			
Subcodes		Lenze setting	Info		
C01302/1		360.0000 unit/s	Profiles 1 ... 15: Speed		
C01302/...					
C01302/15					
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 10000</div></div>					

C01303

Parameter Name: C01303 Profile data: Acceleration			Data type: INTEGER_32 Index: 23272 _d = 5AE8 _h		
Selection of the accelerations for profiles 1 ... 15					
<div>► Profile entry</div>					
Setting range (min. value unit max. value)					
-214748.3647	unit/s2	214748.3647			
Subcodes		Lenze setting	Info		
C01303/1		720.0000 unit/s2	Profiles 1 ... 15: Acceleration		
C01303/...					
C01303/15					
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000					

C01304

Parameter Name: C01304 Profile data: Deceleration			Data type: INTEGER_32 Index: 23271 _d = 5AE7 _h		
Selection of the decelerations for profiles 1 ... 15					
<div>▶ Profile entry</div>					
Setting range (min. value unit max. value)					
-214748.3647	unit/s2	214748.3647			
Subcodes	Lenze setting	Info			
C01304/1	720.0000 unit/s2	Profiles 1 ... 15: Deceleration			
C01304/...					
C01304/15					
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 10000</div></div>					

C01305

Parameter Name: C01305 Profile data: Final speed			Data type: INTEGER_32 Index: 23270 _d = 5AE6 _h		
Selection of the final speeds for profiles 1 ... 15					
• For profile linkage with overchange.					
<div>▶ Profile entry</div>					
Setting range (min. value unit max. value)					
-214748.3647	unit/s	214748.3647			
Subcodes	Lenze setting	Info			
C01305/1	0.0000 unit/s	Profiles 1 ... 15: Final speed			
C01305/...					
C01305/15					
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 10000</div></div>					

C01306

Parameter Name: C01306 Profile data: S-ramp time			Data type: UNSIGNED_16 Index: 23269 _d = 5AE5 _h		
Selection of the S-ramp times for profiles 1 ... 15					
<ul style="list-style-type: none">• The maximum S-ramp time is the time in which the maximum acceleration or the maximum deceleration is reached along a ramp (jerk limitation).					
<div>▶ Profile entry</div>					
Setting range (min. value unit max. value)					
0.000	s	10.000			
Subcodes	Lenze setting		Info		
C01306/1	0.000 s		Profiles 1 ... 15: S-ramp time		
C01306/...					
C01306/15					
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1000</div></div>					

C01307

Parameter Name: C01307 Profile data: Sequence profile			Data type: UNSIGNED_8 Index: 23268 _d = 5AE4 _h
Selection of the sequence profile numbers for profiles 1 ... 15 • For profile linkage			
<div>► Profile entry</div>			
Setting range (min. value unit max. value)			
0		15	
Subcodes	Lenze setting	Info	
C01307/1	0	Profiles 1 ... 15: Sequence profile	
C01307/...			
C01307/15			
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C01308

Parameter Name:		Data type: UNSIGNED_8	
C01308 Profile data: TP profile		Index: 23267 _d = 5AE3 _h	
Selection of the touch-probe profile numbers for profile 1 ... 15			
• Only relevant for positioning modes with touch-probe.			
► Profile entry			
Setting range (min. value unit max. value)			
0		15	
Subcodes	Lenze setting	Info	
C01308/1	0	Profile 1 ... 15: TP profile	
C01308/...			
C01308/15			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01309

Parameter | Name: C01309 | Profile data: TP signal source

Data type: UNSIGNED_8
Index: 23266_d = 5AE2_h

Selection of the touch-probe signal sources for profile 1 ... 15

• Only relevant for positioning modes with touch-probe.

[► Profile entry](#)

Selection list	
3	TP-DigIn3
4	TP-DigIn4
5	TP-DigIn5
6	TP-DigIn6
7	TP-DigIn7
8	TP-Z-trace encoder
9	TP-Z-trace resolver

Subcodes	Lenze setting	Info
C01309/1	3: TP-DigIn3	Profiles 1 ... 15: Sequence profile
C01309/...		
C01309/15		

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT Scaling factor: 1

C01350

Parameter Name: C01350 ACDrive: Drive mode		Data type: UNSIGNED_8 Index: 23225 _d = 5AB9 _h
Selection list		
1	Speed mode	
3	Torque mode	
Subcodes	Lenze setting	Info
C01350/1	1: Speed mode	ACDrive: Drive mode
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01351

Parameter Name: C01351 ACDrive: Control word		Data type: UNSIGNED_16 Index: 23224 _d = 5AB8 _h
From version 13.00.00 Display of the "AC Drive Profile" control word for the controller <ul style="list-style-type: none"> Detailed information on the "AC Drive Profile" can be found in the EtherNet/IP™ communication manual. <ul style="list-style-type: none"> ▶ Actuating drive speed (AC Drive Profile) 		
Display area (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		Info
Bit 0	Run Forward	Relationships between Run1 and Run2 and trigger events can be found in the chapter "Run/Stop Event" .
Bit 1	Run Backward	
Bit 2	Fault Reset	0->1 ≡ Reset error 0 ≡ No response
Bit 3	Reserved	
Bit 4	Reserved	
Bit 5	NetCtrl	Run/Stop control: 0 ≡ via local setting in the device or terminal 1 ≡ via fieldbus (e.g. by the scanner)
Bit 6	NetRef	Reference speed/reference torque: 0 ≡ via local setting in the device or terminal 1 ≡ via fieldbus (e.g. by the scanner)
Bit 7	Reserved	
Bit 8	Reserved	
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	Reserved	
Bit 15	Reserved	
Subcodes		Info
C01351/1		ACDrive: Control word
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C01352

Parameter Name: C01352 ACDrive: Status word		Data type: UNSIGNED_16 Index: 23223 _d = 5AB7 _h	
From version 13.00.00			
Display of the "AC Drive Profile" status word of the controller			
• Detailed information on the "AC Drive Profile" can be found in the EtherNet/IP™ communication manual.			
► Actuating drive speed (AC Drive Profile)			
Display area (min. hex value max. hex value)			
0x0000		0xFFFF	
Value is bit-coded:		Info	
Bit 0	Faulted	0 ≡ No errors 1 ≡ Errors have occurred	
Bit 1	Warning	0 ≡ No warnings 1 ≡ Warnings have occurred	
Bit 2	Running1 (Fwd)	Relationships between Run1 and Run2 and trigger events can be found in the chapter " Run/Stop Event ".	
Bit 3	Running2 (Rev)		
Bit 4	Ready	0 ≡ Different status than in case of "1" 1 ≡ Ready or Enabled or Stopping	
Bit 5	Ctrl from Net	Run/Stop control: 0 ≡ via local setting in the device or terminal 1 ≡ via fieldbus (e.g. by the scanner)	
Bit 6	Ref from Net	Reference speed/reference torque: 0 ≡ via local setting in the device or terminal 1 ≡ via fieldbus (e.g. by the scanner)	
Bit 7	At Reference	1 ≡ Currently, the controller runs with the reference speed or reference torque (depending on the "drive mode" set in C01350/1).	
Bit 8	DriveState_0	The "Drive State" is coded as follows: 0: Manufacturer-specific (not used with 8400) 1: Start-up (drive initialisation) 2: Not_Ready (mains voltage switched off) 3: Ready (mains voltage switched-on) 4: Enabled (drive has received "Run" command) 5: Stopping (drive has received "Stop" command and is stopped) 6: Fault_Stop (drive is stopped due to an error) 7: Faulted (errors have occurred)	
Bit 9	DriveState_1		
Bit 10	DriveState_2		
Bit 11	DriveState_3		
Bit 12	DriveState_4		
Bit 13	DriveState_5		
Bit 14	DriveState_6		
Bit 15	DriveState_7		
Subcodes		Info	
C01352/1		ACDrive: Status word	
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT			

C01353

Parameter Name: C01353 ACDrive: Setpoint scaling			Data type: INTEGER_8 Index: 23222 _d = 5AB6 _h
From version 13.00.00			
▸ Actuating drive speed (AC Drive Profil): Scaling of the speed and torque values			
Setting range (min. value unit max. value)			
-128		127	
Subcodes	Lenze setting	Info	
C01353/1	0	ACDrive: Speed scaling	
C01353/2	0	ACDrive: Torque scaling	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01400

Parameter Name: C01400 L_Sequencer_1: Sequence step		Data type: UNSIGNED_16 Index: 23175 _d = 5A87 _h	
From version 12.00.00			
In the subcodes, the calls of the actions required for the positioning program are stored. In this way, the basic sequence (with the exception of the branches) is defined.			
<div>▸ L_Sequencer_1 (sequence control)</div>			
Setting range (min. value unit max. value)			
0			
Subcodes	Lenze setting	Info	
C01400/1	0	L_Sequencer_1 : Action in sequence step 1	
C01400/...		...	
C01400/100		L_Sequencer_1 : Action in sequence step 100	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C01401

Parameter Name: C01401 L_Sequencer_1: Current step			Data type: UNSIGNED_16 Index: 23174 _d = 5A86 _h		
From version 12.00.00					
▸ L_Sequencer_1 (sequence control)					
Display range (min. value unit max. value)					
0		100			
Subcodes			Info		
C01401/1			L_Sequencer_1 : Current step		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01402

Parameter Name: C01402 L_Sequencer_1: Sequence control: Status			Data type: UNSIGNED_16 Index: 23173 _d = 5A85 _h		
From version 12.00.00 0 - READY: Positioning program ready to start/Program end reached. 1 - RUN: Positioning program running. 2 - PAUSE: Current step interrupted, pause active. 3 - BREAK: Positioning program interrupted. 4 - RESET: Positioning program reset.					
<div>► L_Sequencer_1 (sequence control)</div>					
Display range (min. value unit max. value)					
0		4			
Subcodes			Info		
C01402/1			L_Sequencer_1 : Sequence control: Status		
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>					

C01403

Parameter | Name: C01403 | L_Sequencer_1: Sequence control: Control word

Data type: UNSIGNED_16
Index: 23172_d = 5A84_h

From version 12.00.00

Bit-coded code for controlling the sequencer with a PC or master control via the parameter channel. Setting a bit to "1" activates the corresponding function:

- Bit 0: Start
- Bit 1: Pause
- Bit 2: Break
- Bit 3: Cancel
- Bit 4: Reset
- Bit 5: NextStep

[► L_Sequencer_1 \(sequence control\)](#)

Setting range (min. value unit max. value)		
0		64
Subcodes	Lenze setting	Info
C01403/1	0	L_Sequencer_1 : Sequence control: Control word

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT Scaling factor: 1

C01404

Parameter Name: C01404 L_Sequencer_1: Step for bCancel = TRUE			Data type: UNSIGNED_16 Index: 23171 _d = 5A83 _h		
From version 12.00.00					
▸ L_Sequencer_1 (sequence control)					
Setting range (min. value unit max. value)					
0		101			
Subcodes	Lenze setting		Info		
C01404/1	0		L_Sequencer_1 : Step for bCancel = TRUE		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01405

Parameter Name: C01405 L_Sequencer_1: PSInput		Data type: UNSIGNED_16 Index: 23170 _d = 5A82 _h
From version 12.00.00		► L_Sequencer_1: "Positioning" action
Selection list		
0	Waiting function deactivated	
1	Input 1(wDigitalInp. Bit00)	
2	Input 2(wDigitalInp. Bit01)	
3	Input 3(wDigitalInp. Bit02)	
4	Input 4(wDigitalInp. Bit03)	
5	Input 5(wDigitalInp. Bit04)	
6	Input 6(wDigitalInp. Bit05)	
7	Input 7(wDigitalInp. Bit06)	
8	Input 8(wDigitalInp. Bit07)	
9	Input 9(wDigitalInp. Bit08)	
10	Input 10(wDigitalInp. Bit09)	
11	Input 11(wDigitalInp. Bit10)	
12	Input 12(wDigitalInp. Bit11)	
13	Input 13(wDigitalInp. Bit12)	
14	Input 14(wDigitalInp. Bit13)	
15	Input 15(wDigitalInp. Bit14)	
16	Input 16(wDigitalInp. Bit15)	
Subcodes	Lenze setting	Info
C01405/1	0: Waiting function deactivated	L_Sequencer_1 : Pos. action 1: Start with
C01405/...		...
C01405/50		L_Sequencer_1 : Pos. action 50: Start with
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01406

Parameter Name: C01406 L_Sequencer_1: PSLevel		Data type: UNSIGNED_8 Index: 23169 _d = 5A81 _h
From version 12.00.00		► L_Sequencer_1: "Positioning" action
Setting range (min. value unit max. value)		
0		
Subcodes	Lenze setting	Info
C01406/1	0	L_Sequencer_1 : Pos. action 1: input polarity
C01406/...		...
C01406/50		L_Sequencer_1 : Pos. action 50: input polarity
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01407

Parameter Name: C01407 L_Sequencer_1: PSProfil			Data type: UNSIGNED_16 Index: 23168 _d = 5A80 _h
From version 12.00.00			
<div>► L_Sequencer_1: "Positioning" action</div>			
Setting range (min. value unit max. value)			
0		15	
Subcodes	Lenze setting	Info	
C01407/1	0	L_Sequencer_1 : Pos. action 1: Profile number	
C01407/...		...	
C01407/50		L_Sequencer_1 : Pos. action 50: Profile number	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C01408

Parameter Name: C01408 L_Sequencer_1: PSSStep			Data type: UNSIGNED_16 Index: 23167 _d = 5A7F _h
From version 12.00.00			► L_Sequencer_1: "Positioning" action
Setting range (min. value unit max. value)			
0		100	
Subcodes	Lenze setting	Info	
C01408/1	0	L_Sequencer_1 : Pos. action 1: Jump destination	
C01408/...		...	
C01408/50		L_Sequencer_1 : Pos. action 50: Jump destination	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01409

Parameter Name: C01409 L_Sequencer_1: PS_WD_Time			Data type: UNSIGNED_32 Index: 23166 _d = 5A7E _h
From version 12.00.00			
<div>► L_Sequencer_1: "Positioning" action</div>			
Setting range (min. value unit max. value)			
0.000		2147480.000	
Subcodes	Lenze setting	Info	
C01409/1	0.000	L_Sequencer_1 : Pos. action 1: Monitoring time	
C01409/...		...	
C01409/50		L_Sequencer_1 : Pos. action 50: Monitoring time	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1000</div></div>			

C01410

Parameter Name: C01410 L_Sequencer_1: PS_WD_Step			Data type: UNSIGNED_16 Index: 23165 _d = 5A7D _h
From version 12.00.00			
<div>► L_Sequencer_1: "Positioning" action</div>			
Setting range (min. value unit max. value)			
0		100	
Subcodes	Lenze setting	Info	
C01410/1	0	L_Sequencer_1 : Pos. action 1: Jump destination monit.	
C01410/...		...	
C01410/50		L_Sequencer_1 : Pos. action 50: Jump destination monit.	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C01411

Parameter Name: C01411 L_Sequencer_1: SwitchOut1		Data type: UNSIGNED_16 Index: 23164 _d = 5A7C _h
From version 12.00.00		▶ L_Sequencer_1: "Switching" action
Selection list		
0	Deactivated	
1	Output 1 (wDigitalOutp. Bit00)	
2	Output 2 (wDigitalOutp. Bit01)	
3	Output 3 (wDigitalOutp. Bit02)	
4	Output 4 (wDigitalOutp. Bit03)	
5	Output 5 (wDigitalOutp. Bit04)	
6	Output 6 (wDigitalOutp. Bit05)	
7	Output 7 (wDigitalOutp. Bit06)	
8	Output 8 (wDigitalOutp. Bit07)	
9	Output 9 (wDigitalOutp. Bit08)	
10	Output 10 (wDigitalOutp. Bit09)	
11	Output 11 (wDigitalOutp. Bit10)	
12	Output 12 (wDigitalOutp. Bit11)	
13	Output 13 (wDigitalOutp. Bit12)	
14	Output 14 (wDigitalOutp. Bit13)	
15	Output 15 (wDigitalOutp. Bit14)	
16	Output 16 (wDigitalOutp. Bit15)	
Subcodes	Lenze setting	Info
C01411/1	0: Deactivated	L_Sequencer_1 : Switch. act. 1: output switch. A
C01411/...		...
C01411/16		L_Sequencer_1 : Switch. act. 16: output switch. A
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01412

Parameter Name: C01412 L_Sequencer_1: SwitchLevel1			Data type: UNSIGNED_8 Index: 23163 _d = 5A7B _h		
From version 12.00.00					
<div>► L_Sequencer_1: "Switching" action</div>					
Setting range (min. value unit max. value)					
0		1			
Subcodes	Lenze setting		Info		
C01412/1	0		L_Sequencer_1 : Switch. act. 1: pol. switch. A		
C01412/...			...		
C01412/16			L_Sequencer_1 : Switch. act. 16: pol. switch. A		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>					

C01413

Parameter Name: C01413 L_Sequencer_1: SwitchOut2		Data type: UNSIGNED_16 Index: 23162 _d = 5A7A _h	
From version 12.00.00			
<div>▸ L_Sequencer_1: "Switching" action</div>			
Selection list			
0	Deactivated		
1	Output 1 (wDigitalOutp. Bit00)		
2	Output 2 (wDigitalOutp. Bit01)		
3	Output 3 (wDigitalOutp. Bit02)		
4	Output 4 (wDigitalOutp. Bit03)		
5	Output 5 (wDigitalOutp. Bit04)		
6	Output 6 (wDigitalOutp. Bit05)		
7	Output 7 (wDigitalOutp. Bit06)		
8	Output 8 (wDigitalOutp. Bit07)		
9	Output 9 (wDigitalOutp. Bit08)		
10	Output 10 (wDigitalOutp. Bit09)		
11	Output 11 (wDigitalOutp. Bit10)		
12	Output 12 (wDigitalOutp. Bit11)		
13	Output 13 (wDigitalOutp. Bit12)		
14	Output 14 (wDigitalOutp. Bit13)		
15	Output 15 (wDigitalOutp. Bit14)		
16	Output 16 (wDigitalOutp. Bit15)		
Subcodes	Lenze setting	Info	
C01413/1	0: Deactivated	L_Sequencer_1 : Switch. act. 1: output switch. B	
C01413/...		...	
C01413/16		L_Sequencer_1 : Switch. act. 16: output switch. B	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C01414

Parameter Name: C01414 L_Sequencer_1: SwitchLevel2			Data type: UNSIGNED_8 Index: 23161 _d = 5A79 _h
From version 12.00.00			
<div>► L_Sequencer_1: "Switching" action</div>			
Setting range (min. value unit max. value)			
0			
Subcodes	Lenze setting	Info	
C01414/1	0	L_Sequencer_1 : Switch. act. 1: pol. switch. B	
C01414/...		...	
C01414/16		L_Sequencer_1 : Switch. act. 16: pol. switch. B	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C01415

Parameter Name: C01415 L_Sequencer_1: BranchIn		Data type: UNSIGNED_16 Index: 23160 _d = 5A78 _h
From version 12.00.00		► L_Sequencer_1: "Branch" action
Selection list		
0	Unconditional branch	
1	Input 1(wDigitalInp. Bit00)	
2	Input 2(wDigitalInp. Bit01)	
3	Input 3(wDigitalInp. Bit02)	
4	Input 4(wDigitalInp. Bit03)	
5	Input 5(wDigitalInp. Bit04)	
6	Input 6(wDigitalInp. Bit05)	
7	Input 7(wDigitalInp. Bit06)	
8	Input 8(wDigitalInp. Bit07)	
9	Input 9(wDigitalInp. Bit08)	
10	Input 10(wDigitalInp. Bit09)	
11	Input 11(wDigitalInp. Bit10)	
12	Input 12(wDigitalInp. Bit11)	
13	Input 13(wDigitalInp. Bit12)	
14	Input 14(wDigitalInp. Bit13)	
15	Input 15(wDigitalInp. Bit14)	
16	Input 16(wDigitalInp. Bit15)	
Subcodes	Lenze setting	Info
C01415/1	0: Unconditional branch	L_Sequencer_1 : Branch act. 1: Input for jump
C01415/...		...
C01415/16		L_Sequencer_1 : Branch act. 16: Input for jump
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01416

Parameter Name: C01416 L_Sequencer_1: BranchLevel			Data type: UNSIGNED_8 Index: 23159 _d = 5A77 _h		
From version 12.00.00					
<div>► L_Sequencer_1: "Branch" action</div>					
Setting range (min. value unit max. value)					
0		1			
Subcodes	Lenze setting		Info		
C01416/1	0		L_Sequencer_1 : Branch act. 1: Input polarity		
C01416/...			...		
C01416/16			L_Sequencer_1 : Branch act. 16: Input polarity		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01417

Parameter Name: C01417 L_Sequencer_1: BranchStep			Data type: UNSIGNED_16 Index: 23158 _d = 5A76 _h		
From version 12.00.00					
<div>► L_Sequencer_1: "Branch" action</div>					
Setting range (min. value unit max. value)					
0		100			
Subcodes	Lenze setting		Info		
C01417/1	0		L_Sequencer_1 : Branch act.1: Jump destination		
C01417/...			...		
C01417/16			L_Sequencer_1 : Branch act. 16: Jump destination		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>					

C01418

Parameter Name: C01418 L_Sequencer_1: BranchStep1			Data type: UNSIGNED_16 Index: 23157 _d = 5A75 _h		
From version 12.00.00					
▸ L_Sequencer_1: "Variable branch" action					
Setting range (min. value unit max. value)					
0		100			
Subcodes	Lenze setting		Info		
C01418/1	0		L_Sequencer_1 : Var. branch 1: Jump destin. 1		
C01418/2	0		L_Sequencer_1 : Var. branch 2: Jump destin. 1		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01419

Parameter Name: C01419 L_Sequencer_1: BranchStep2			Data type: UNSIGNED_16 Index: 23156 _d = 5A74 _h
From version 12.00.00			
▶ L_Sequencer_1: "Variable branch" action			
Setting range (min. value unit max. value)			
0		100	
Subcodes	Lenze setting	Info	
C01419/1	0	L_Sequencer_1 : Var. branch 1: Jump destin. 2	
C01419/2	0	L_Sequencer_1 : Var. branch 2: Jump destin. 2	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01420

Parameter Name: C01420 L_Sequencer_1: BranchStep3			Data type: UNSIGNED_16 Index: 23155 _d = 5A73 _h
From version 12.00.00			▶ L_Sequencer_1: "Variable branch" action
Setting range (min. value unit max. value)			
0		100	
Subcodes	Lenze setting	Info	
C01420/1	0	L_Sequencer_1 : Var. branch 1: Jump destin. 3	
C01420/2	0	L_Sequencer_1 : Var. branch 2: Jump destin. 3	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01421

Parameter Name: C01421 L_Sequencer_1: BranchStep4			Data type: UNSIGNED_16 Index: 23154 _d = 5A72 _h
From version 12.00.00			► L_Sequencer_1: "Variable branch" action
Setting range (min. value unit max. value)			
0			
Subcodes	Lenze setting	Info	
C01421/1	0	L_Sequencer_1 : Var. branch1: Jump destin. 4	
C01421/2	0	L_Sequencer_1 : Var. branch 2: Jump destin. 4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01422

Parameter Name: C01422 L_Sequencer_1: BranchStep5			Data type: UNSIGNED_16 Index: 23153 _d = 5A71 _h
From version 12.00.00			▶ L_Sequencer_1: "Variable branch" action
Setting range (min. value unit max. value)			
0			
Subcodes	Lenze setting	Info	
C01422/1	0	L_Sequencer_1 : Var. branch 1: Jump destin. 5	
C01422/2	0	L_Sequencer_1 : Var. branch 2: Jump destin. 5	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01423

Parameter Name: C01423 L_Sequencer_1: BranchStep6			Data type: UNSIGNED_16 Index: 23152 _d = 5A70 _h
From version 12.00.00			
▶ L_Sequencer_1: "Variable branch" action			
Setting range (min. value unit max. value)			
0		100	
Subcodes	Lenze setting	Info	
C01423/1	0	L_Sequencer_1 : Var. branch1: Jump destin. 6	
C01423/2	0	L_Sequencer_1 : Var. branch2: Jump destin. 6	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01424

Parameter Name: C01424 L_Sequencer_1: BranchStep7			Data type: UNSIGNED_16 Index: 23151 _d = 5A6F _h
From version 12.00.00			
<div>► L_Sequencer_1: "Variable branch" action</div>			
Setting range (min. value unit max. value)			
0		100	
Subcodes	Lenze setting	Info	
C01424/1	0	L_Sequencer_1 : Var. branch1: Jump destin. 7	
C01424/2	0	L_Sequencer_1 : Var. branch 2: Jump destin. 7	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C01425

Parameter Name: C01425 L_Sequencer_1: BranchStep8			Data type: UNSIGNED_16 Index: 23150 _d = 5A6E _h
From version 12.00.00			
<div>► L_Sequencer_1: "Variable branch" action</div>			
Setting range (min. value unit max. value)			
0		100	
Subcodes	Lenze setting	Info	
C01425/1	0	L_Sequencer_1 : Var. branch 1: Jump destin. 8	
C01425/2	0	L_Sequencer_1 : Var. branch 2: Jump destin. 8	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C01426

Parameter Name: C01426 L_Sequencer_1: BranchStep9			Data type: UNSIGNED_16 Index: 23149 _d = 5A6D _h
From version 12.00.00			
▸ L_Sequencer_1: "Variable branch" action			
Setting range (min. value unit max. value)			
0			
Subcodes	Lenze setting	Info	
C01426/1	0	L_Sequencer_1 : Var. branch 1: Jump destin. 9	
C01426/2	0	L_Sequencer_1 : Var. branch2: Jump destin. 9	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01427

Parameter Name: C01427 L_Sequencer_1: BranchStep10			Data type: UNSIGNED_16 Index: 23148 _d = 5A6C _h		
From version 12.00.00					
▶ L_Sequencer_1: "Variable branch" action					
Setting range (min. value unit max. value)					
0		100			
Subcodes	Lenze setting		Info		
C01427/1	0		L_Sequencer_1 : Var. branch1: Jump destin. 10		
C01427/2	0		L_Sequencer_1 : Var. branch 2: Jump destin. 10		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01428

Parameter Name: C01428 L_Sequencer_1: BranchStep11			Data type: UNSIGNED_16 Index: 23147 _d = 5A6B _h		
From version 12.00.00					
▶ L_Sequencer_1: "Variable branch" action					
Setting range (min. value unit max. value)					
0		100			
Subcodes	Lenze setting		Info		
C01428/1	0		L_Sequencer_1 : Var. branch 1: Jump destin. 11		
C01428/2	0		L_Sequencer_1 : Var. branch 2: Jump destin. 11		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01429

Parameter Name: C01429 L_Sequencer_1: BranchStep12			Data type: UNSIGNED_16 Index: 23146 _d = 5A6A _h		
From version 12.00.00					
▸ L_Sequencer_1: "Variable branch" action					
Setting range (min. value unit max. value)					
0		100			
Subcodes	Lenze setting		Info		
C01429/1	0		L_Sequencer_1 : Var. branch 1: Jump destin. 12		
C01429/2	0		L_Sequencer_1 : Var. branch2: Jump destin. 12		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01430

Parameter Name: C01430 L_Sequencer_1: BranchStep13			Data type: UNSIGNED_16 Index: 23145 _d = 5A69 _h		
From version 12.00.00					
▸ L_Sequencer_1: "Variable branch" action					
Setting range (min. value unit max. value)					
0		100			
Subcodes	Lenze setting		Info		
C01430/1	0		L_Sequencer_1 : Var. branch 1: Jump destin. 13		
C01430/2	0		L_Sequencer_1 : Var. branch 2: Jump destin. 13		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01431

Parameter Name: C01431 L_Sequencer_1: BranchStep14			Data type: UNSIGNED_16 Index: 23144 _d = 5A68 _h
From version 12.00.00			
▶ L_Sequencer_1: "Variable branch" action			
Setting range (min. value unit max. value)			
0		100	
Subcodes	Lenze setting	Info	
C01431/1	0	L_Sequencer_1 : Var. branch 1: Jump destin. 14	
C01431/2	0	L_Sequencer_1 : Var. branch 2: Jump destin. 14	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01432

Parameter Name: C01432 L_Sequencer_1: BranchStep15			Data type: UNSIGNED_16 Index: 23143 _d = 5A67 _h
From version 12.00.00			
▸ L_Sequencer_1: "Variable branch" action			
Setting range (min. value unit max. value)			
0			
Subcodes	Lenze setting	Info	
C01432/1	0	L_Sequencer_1 : Var. branch 1: Jump destin. 15	
C01432/2	0	L_Sequencer_1 : Var. branch 2: Jump destin. 15	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01433

Parameter Name: C01433 L_Sequencer_1: BranchStep16			Data type: UNSIGNED_16 Index: 23142 _d = 5A66 _h
From version 12.00.00			
▶ L_Sequencer_1: "Variable branch" action			
Setting range (min. value unit max. value)			
0		100	
Subcodes	Lenze setting	Info	
C01433/1	0	L_Sequencer_1 : Var. branch 1: Jump destin. 16	
C01433/2	0	L_Sequencer_1 : Var. branch 2: Jump destin. 16	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01434

Parameter Name: C01434 L_Sequencer_1: BranchStep17			Data type: UNSIGNED_16 Index: 23141 _d = 5A65 _h
From version 12.00.00			
▶ L_Sequencer_1: "Variable branch" action			
Setting range (min. value unit max. value)			
0			
Subcodes	Lenze setting	Info	
C01434/1	0	L_Sequencer_1 : Var. branch 1: Jump destin. 17	
C01434/2	0	L_Sequencer_1 : Var. branch 2: Jump destin. 17	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01435

Parameter Name: C01435 L_Sequencer_1: BranchStep18			Data type: UNSIGNED_16 Index: 23140 _d = 5A64 _h
From version 12.00.00			
▶ L_Sequencer_1: "Variable branch" action			
Setting range (min. value unit max. value)			
0		100	
Subcodes	Lenze setting	Info	
C01435/1	0	L_Sequencer_1 : Var. branch 1: Jump destin. 18	
C01435/2	0	L_Sequencer_1 : Var. branch 2: Jump destin. 18	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01436

Parameter Name: C01436 L_Sequencer_1: BranchStep19			Data type: UNSIGNED_16 Index: 23139 _d = 5A63 _h
From version 12.00.00			
<div>► L_Sequencer_1: "Variable branch" action</div>			
Setting range (min. value unit max. value)			
0			
Subcodes	Lenze setting	Info	
C01436/1	0	L_Sequencer_1 : Var. branch 1: Jump destin. 19	
C01436/2	0	L_Sequencer_1 : Var. branch 2: Jump destin. 19	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C01437

Parameter Name: C01437 L_Sequencer_1: BranchStep20			Data type: UNSIGNED_16 Index: 23138 _d = 5A62 _h
From version 12.00.00			
<div>► L_Sequencer_1: "Variable branch" action</div>			
Setting range (min. value unit max. value)			
0			
Subcodes	Lenze setting	Info	
C01437/1	0	L_Sequencer_1 : Var. branch 1: Jump destin. 20	
C01437/2	0	L_Sequencer_1 : Var. branch 2: Jump destin. 20	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C01438

Parameter Name: C01438 L_Sequencer_1: Wartezeit			Data type: UNSIGNED_32 Index: 23137 _d = 5A61 _h		
From version 12.00.00					
<div>▶ L_Sequencer_1: "Waiting" action</div>					
Setting range (min. value unit max. value)					
0.000	s	2127480.000			
Subcodes	Lenze setting		Info		
C01438/1	0.000 s		L_Sequencer_1 : Wait. act. 1: Waiting time		
C01438/...			...		
C01438/8			L_Sequencer_1 : Wait. act. 8: Waiting time		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1000</div></div>					

C01439

Parameter Name: C01439 L_Sequencer_1: Wait Eingang f. Weiter		Data type: UNSIGNED_16 Index: 23136 _d = 5A60 _h	
From version 12.00.00			
<div>▶ L_Sequencer_1: "Waiting" action</div>			
Selection list			
0	Input deactivated		
1	Input 1(wDigitalInp. Bit00)		
2	Input 2(wDigitalInp. Bit01)		
3	Input 3(wDigitalInp. Bit02)		
4	Input 4(wDigitalInp. Bit03)		
5	Input 5(wDigitalInp. Bit04)		
6	Input 6(wDigitalInp. Bit05)		
7	Input 7(wDigitalInp. Bit06)		
8	Input 8(wDigitalInp. Bit07)		
9	Input 9(wDigitalInp. Bit08)		
10	Input 10(wDigitalInp. Bit09)		
11	Input 11(wDigitalInp. Bit10)		
12	Input 12(wDigitalInp. Bit11)		
13	Input 13(wDigitalInp. Bit12)		
14	Input 14(wDigitalInp. Bit13)		
15	Input 15(wDigitalInp. Bit14)		
16	Input 16(wDigitalInp. Bit15)		
Subcodes	Lenze setting	Info	
C01439/1	0: Input deactivated	L_Sequencer_1 : Wait. act. 1: Input for "Next"	
C01439/...		...	
C01439/8		L_Sequencer_1 : Wait. act. 8: Input for "Next"	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1</div>			

C01440

Parameter Name: C01440 L_Sequencer_1: WaitLevel			Data type: UNSIGNED_8 Index: 23135 _d = 5A5F _h
From version 12.00.00			
<div>► L_Sequencer_1: "Waiting" action</div>			
Setting range (min. value unit max. value)			
0		1	
Subcodes	Lenze setting	Info	
C01440/1	0	L_Sequencer_1 : Wait. act. 1: Input polarity	
C01440/...		...	
C01440/8		L_Sequencer_1 : Wait. act. 8: Input polarity	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C01441

Parameter Name: C01441 L_Sequencer_1: SetZählernummer			Data type: UNSIGNED_16 Index: 23134 _d = 5A5E _h
From version 12.00.00			▶ L_Sequencer_1: "Counter setting" action
Setting range (min. value unit max. value)			
0		5	
Subcodes	Lenze setting	Info	
C01441/1	1	L_Sequencer_1 : Counter set act. 1: Counter no.	
C01441/...		...	
C01441/5		L_Sequencer_1 : Counter set act. 5: Counter no.	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01442

Parameter Name: C01442 L_Sequencer_1: SetZählerStartwert			Data type: INTEGER_32 Index: 23133 _d = 5A5D _h
From version 12.00.00			▶ L_Sequencer_1: "Counter setting" action
Setting range (min. value unit max. value)			
-2147483647		2147483647	
Subcodes	Lenze setting	Info	
C01442/1	0	L_Sequencer_1 : Counter set act. 1: Starting value	
C01442/...		...	
C01442/5		L_Sequencer_1 : Counter set act. 5: Starting value	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01443

Parameter Name: C01443 L_Sequencer_1: Aktueller Zählerstand			Data type: INTEGER_32 Index: 23132 _d = 5A5C _h		
From version 12.00.00					
▶ L_Sequencer_1: "Counter setting" action					
Display range (min. value unit max. value)					
-2147483647		2147483647			
Subcodes			Info		
C01443/1			L_Sequencer_1 : Counter 1: Current counter content		
C01443/...			...		
C01443/5			L_Sequencer_1 : Counter 5: Current counter content		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01444

Parameter Name: C01444 L_Sequencer_1: ZählerNummer			Data type: UNSIGNED_16 Index: 23131 _d = 5A5B _h		
From version 12.00.00					
▶ L_Sequencer_1: "Counting" action					
Setting range (min. value unit max. value)					
0		5			
Subcodes	Lenze setting		Info		
C01444/1	1		L_Sequencer_1 : Count. act. 1: Counter no.		
C01444/...			...		
C01444/8			L_Sequencer_1 : Count. act. 8: Counter no.		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01445

Parameter Name: C01445 L_Sequencer_1: SchrittwertZähler			Data type: INTEGER_32 Index: 23130 _d = 5A5A _h		
From version 12.00.00					
▶ L_Sequencer_1: "Counting" action					
Setting range (min. value unit max. value)					
-2147483647		2147483647			
Subcodes	Lenze setting		Info		
C01445/1	1		L_Sequencer_1 : Count. act. 1: Step value		
C01445/...			...		
C01445/8			L_Sequencer_1 : Count. act. 8: Step value		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01446

Parameter Name: C01446 L_Sequencer_1: ZählerVergleichswert			Data type: INTEGER_32 Index: 23129 _d = 5A59 _h
From version 12.00.00			
<div>► L_Sequencer_1: "Counting" action</div>			
Setting range (min. value unit max. value)			
-2147483647		2147483647	
Subcodes	Lenze setting	Info	
C01446/1	0	L_Sequencer_1 : Count. act. 1: comparison value	
C01446/...		...	
C01446/8		L_Sequencer_1 : Count. act. 8: comparison value	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>			

C01447

Parameter Name: C01447 L_Sequencer_1: ZählerSprungziel			Data type: UNSIGNED_16 Index: 23128 _d = 5A58 _h	
From version 12.00.00				
<div>► L_Sequencer_1: "Counting" action</div>				
Setting range (min. value unit max. value)				
0		100		
Subcodes	Lenze setting		Info	
C01447/1	0		L_Sequencer_1 : Count. act. 1: Jump destination	
C01447/...			...	
C01447/8			L_Sequencer_1 : Count. act. 8: Jump destination	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>				

C01448

Parameter Name: C01448 L_Sequencer_1: ZählerVergleichsfunktion		Data type: UNSIGNED_16 Index: 23127 _d = 5A57 _h	
From version 12.00.00			
▶ L_Sequencer_1: "Counting" action			
Selection list			
1	Counter content = comparison value		
2	Counter content > comparison value		
3	Counter content >= comparison value		
4	Counter content < comparison value		
5	Counter content <= comparison value		
Subcodes	Lenze setting	Info	
C01448/1	1: Counter content = comparison value	L_Sequencer_1 : Count. act. 1: Comparison op.	
C01448/...		...	
C01448/8		L_Sequencer_1 : Count. act. 8: Comaprison op.	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01449

Parameter Name: C01449 L_Sequencer_1: Standby Eingang f. Ende		Data type: UNSIGNED_16 Index: 23126 _d = 5A56 _h
From version 12.00.00		► L_Sequencer_1: "Standby" action
Selection list		
1	Input 1(wDigitalInp. Bit00)	
2	Input 2(wDigitalInp. Bit01)	
3	Input 3(wDigitalInp. Bit02)	
4	Input 4(wDigitalInp. Bit03)	
5	Input 5(wDigitalInp. Bit04)	
6	Input 6(wDigitalInp. Bit05)	
7	Input 7(wDigitalInp. Bit06)	
8	Input 8(wDigitalInp. Bit07)	
9	Input 9(wDigitalInp. Bit08)	
10	Input 10(wDigitalInp. Bit09)	
11	Input 11(wDigitalInp. Bit10)	
12	Input 12(wDigitalInp. Bit11)	
13	Input 13(wDigitalInp. Bit12)	
14	Input 14(wDigitalInp. Bit13)	
15	Input 15(wDigitalInp. Bit14)	
16	Input 16(wDigitalInp. Bit15)	
Subcodes	Lenze setting	Info
C01449/1	1: Input 1(wDigitalInp. Bit00)	L_Sequencer_1 : Standby act. 1: Input for "End"
C01449/...		...
C01449/5		L_Sequencer_1 : Standby act. 5: Input for "End"
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01450

Parameter Name: C01450 L_Sequencer_1: Standby PolaritätEingang		Data type: UNSIGNED_8 Index: 23125 _d = 5A55 _h
From version 12.00.00		► L_Sequencer_1: "Standby" action
Setting range (min. value unit max. value)		
0	1	
Subcodes	Lenze setting	Info
C01450/1	0	L_Sequencer_1 : Standby act. 1: Input polarity
C01450/...		...
C01450/5		L_Sequencer_1 : Standby act. 5: Input polarity
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01451

Parameter Name:		Data type: UNSIGNED_16 Index: 23124 _d = 5A54 _h	
C01451 L_Sequencer_1: Standby Modusfolger			
From version 12.00.00			
▶ L_Sequencer_1: "Standby" action			
Selection list			
0	Speed follower		
1	Position follower		
Subcodes	Lenze setting	Info	
C01451/1	0: Speed follower	L_Sequencer_1 : Standby act. 1: Follower mode	
C01451/...		...	
C01451/5		L_Sequencer_1 : Standby act. 5: Follower mode	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01452

Parameter Name: C01452 L_Sequencer_1: StandbySollwert			Data type: INTEGER_16 Index: 23123 _d = 5A53 _h		
From version 12.00.00					
<div>► L_Sequencer_1: "Standby" action</div>					
Setting range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes	Lenze setting	Info			
C01452/1	0.00 %	L_Sequencer_1 : Standby act. 1: Setpoint			
C01452/...		...			
C01452/5		L_Sequencer_1 : Standby act. 5: Setpoint			
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100</div>					

C01453

Parameter Name: C01453 L_Sequencer_1: Bool signal			Data type: UNSIGNED_8 Index: 23122 _d = 5A52 _h		
From version 12.00.00					
<div>► L_Sequencer_1 (sequence control)</div>					
Display range (min. value unit max. value)					
0		1			
Subcodes			Info		
C01453/1			L_Sequencer_1 : bStart		
C01453/2			L_Sequencer_1 : bPause		
C01453/3			L_Sequencer_1 : bNextStep		
C01453/4			L_Sequencer_1 : bCancel		
C01453/5			L_Sequencer_1 : bBreak		
C01453/6			L_Sequencer_1 : bReset		
C01453/7			L_Sequencer_1 : bProgramBusy		
C01453/8			L_Sequencer_1 : bStateReady		
C01453/9			L_Sequencer_1 : bStateRun		
C01453/10			L_Sequencer_1 : bStatePause		
C01453/11			L_Sequencer_1 : bStateBreak		
C01453/12			L_Sequencer_1 : bStateReset		
C01453/13			L_Sequencer_1 : bStateDone		
C01453/14			L_Sequencer_1 : bWatchDogAcitve		
C01453/15			L_Sequencer_1 : bErrBranch		
C01453/16			L_Sequencer_1 : bErrActive		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01454

Parameter Name: C01454 L_Sequencer_1: INT signal			Data type: INTEGER_16 Index: 23121 _d = 5A51 _h		
From version 12.00.00					
▸ L_Sequencer_1 (sequence control)					
Display range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes			Info		
C01454/1			L_Sequencer_1 : nSet_a		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C01455

Parameter Name: C01455 L_Sequencer_1: Word signal			Data type: UNSIGNED_16 Index: 23120 _d = 5A50 _h		
From version 12.00.00					
► L_Sequencer_1 (sequence control)					
Display range (min. value unit max. value)					
0		65535			
Subcodes			Info		
C01455/1			L_Sequencer_1 : wStartStep		
C01455/2			L_Sequencer_1 : wBranch1		
C01455/3			L_Sequencer_1 : wBranch2		
C01455/4			L_Sequencer_1 : wDigitalInputs		
C01455/5			L_Sequencer_1 : wMotionState1		
C01455/6			L_Sequencer_1 : wMotionState2		
C01455/7			L_Sequencer_1 : wMckPosCtrl1		
C01455/8			L_Sequencer_1 : wMckPosCtrl2		
C01455/9			L_Sequencer_1 : wAuxCtrl		
C01455/10			L_Sequencer_1 : wState		
C01455/11			L_Sequencer_1 : wActStep		
C01455/12			L_Sequencer_1 : wDigitalOutputs		
C01455/13			L_Sequencer_1 : wProfileNumber		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01460

Parameter Name: C01460 L_ConvActPos: TConst			Data type: UNSIGNED_16 Index: 23115 _d = 5A4B _h		
From version 12.00.00					
Setting range (min. value unit max. value)					
0	ms	1000			
Subcodes	Lenze setting		Info		
C01460/1	10 ms		L_ConvActPos_1 : TConst		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01461

Parameter Name: C01461 L_ConvActPos: MaxPos/MinPos			Data type: INTEGER_16 Index: 23114 _d = 5A4A _h		
From version 12.00.00					
Setting range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes	Lenze setting	Info			
C01461/1	100.00 %	L_ConvActPos_1 : MaxPos			
C01461/2	-100.00 %	L_ConvActPos_1 : MinPos			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C01462

Parameter Name: C01462 L_ConvActPos: Length			Data type: UNSIGNED_32 Index: 23113 _d = 5A49 _h		
From version 12.00.00					
Setting range (min. value unit max. value)					
0	mm	100000			
Subcodes	Lenze setting		Info		
C01462/1	0 mm		L_ConvActPos 1 : Length		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01463

Parameter Name: C01463 L_ConvActPos: UpperRef/LowerRef			Data type: INTEGER_16 Index: 23112 _d = 5A48 _h		
From version 12.00.00					
Setting range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes	Lenze setting		Info		
C01463/1	90.00 %		L_ConvActPos 1 : UpperRef		
C01463/2	-90.01 %		L_ConvActPos 1 : LowerRef		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C01464

Parameter Name: C01464 L_ConvActPos: WindowSetPos			Data type: INTEGER_16 Index: 23111 _d = 5A47 _h		
From version 12.00.00					
Setting range (min. value unit max. value)					
0.00	%	199.99			
Subcodes	Lenze setting		Info		
C01464/1	10.00 %		L_ConvActPos 1 : WindowSetPos		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C01465

Parameter Name: C01465 L_ConvActPos: DelayTime			Data type: UNSIGNED_16 Index: 23110 _d = 5A46 _h		
From version 12.00.00					
Setting range (min. value unit max. value)					
0.000	s	50.000			
Subcodes	Lenze setting		Info		
C01465/1	0.100 s		L_ConvActPos 1 : DelayTime		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C01466

Parameter Name: C01466 L_ConvActPos: TConstVAdd			Data type: UNSIGNED_16 Index: 23109 _d = 5A45 _h		
From version 12.00.00					
Setting range (min. value unit max. value)					
0	ms	1000			
Subcodes	Lenze setting		Info		
C01466/1	10 ms		L_ConvActPos 1 : TConstVAdd		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01467

Parameter Name: C01467 L_ConvActPos: DeadBand			Data type: INTEGER_16 Index: 23108 _d = 5A44 _h		
From version 12.00.00					
Setting range (min. value unit max. value)					
0.00	%	100.00			
Subcodes	Lenze setting		Info		
C01467/1	1.00 %		L_ConvActPos 1 : DeadBand		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C01468

Parameter Name: C01468 L_ConvActPos: Damping			Data type: UNSIGNED_16 Index: 23107 _d = 5A43 _h		
From version 12.00.00					
Setting range (min. value unit max. value)					
0.00		10.00			
Subcodes	Lenze setting		Info		
C01468/1	0.00		<u>L_ConvActPos_1</u> : Damping		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C01469

Parameter Name: C01469 L_MFail: Vp			Data type: UNSIGNED_16 Index: 23106 _d = 5A42 _h		
From version 12.00.00					
Setting range (min. value unit max. value)					
0.001		31.000			
Subcodes	Lenze setting		Info		
C01469/1	1.000		L_MFail_1 : Vp		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C01470

Parameter Name: C01470 L_MFail: Tn			Data type: UNSIGNED_16 Index: 23105 _d = 5A41 _h		
From version 12.00.00					
Setting range (min. value unit max. value)					
1	ms	60000			
Subcodes	Lenze setting	Info			
C01470/1	20 ms	L_MFail 1 : U DC-bus controller reset time			
C01470/2	20 ms	L_MFail 1 : Acceleration time			
C01470/3	20 ms	L_MFail 1 : Retrigger time			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01501

Parameter Name: C01501 Resp. to communication error with MCI		Data type: UNSIGNED_8 Index: 23074 _d = 5A22 _h	
Configuration of monitoring functions for the communication module			
Selection list			
0	No Reaction		
1	Fault		
2	Trouble		
3	TroubleQuickStop		
4	WarningLocked		
5	Warning		
6	Information		
Subcodes	Lenze setting	Info	
C01501/1	0: No Reaction	Resp. to MCI connection error • Response to a communication error of the attached communication module.	
C01501/2	0: No Reaction	Resp. to MCI invalid module • Response to an unplugged or incompatible communication module	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01670

Parameter Name: C01670 L_ComparePhi 1-5: Function		Data type: UNSIGNED_8 Index: 22905 _d = 5979 _h
Selection of comparison operation		
• If the statement of the selected comparison operation is true, the binary <i>bOut</i> output will be set to TRUE.		
Selection list		
1	In1 = In2	
2	In1 > In2	
3	In1 < In2	
4	In1 = In2	
5	In1 > In2	
6	In1 < In2	
Subcodes	Lenze setting	Info
C01670/1	1: In1 = In2	L_ComparePhi 1 : Function
C01670/2	1: In1 = In2	L_ComparePhi 2 : Function
C01670/3	1: In1 = In2	L_ComparePhi 3 : Function
C01670/4	1: In1 = In2	L_ComparePhi 4 : Function
C01670/5	1: In1 = In2	L_ComparePhi 5 : Function
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01671

Parameter Name: C01671 L_ComparePhi 1-5: Hysteresis		Data type: INTEGER_32 Index: 22904 _d = 5978 _h
Hysteresis for the comparison function		
Setting range (min. value unit max. value)		
0	Incr.	
		1073741824
Subcodes	Lenze setting	Info
C01671/1	0 incr.	L_ComparePhi 1 : Hysteresis
C01671/2	0 incr.	L_ComparePhi 2 : Hysteresis
C01671/3	0 incr.	L_ComparePhi 3 : Hysteresis
C01671/4	0 incr.	L_ComparePhi 4 : Hysteresis
C01671/5	0 incr.	L_ComparePhi 5 : Hysteresis
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C01672

Parameter Name: C01672 L_ComparePhi 1-5: Window			Data type: INTEGER_32 Index: 22903 _d = 5977 _h		
Window for the comparison operation					
Setting range (min. value unit max. value)					
0	Incr.	1073741824			
Subcodes	Lenze setting		Info		
C01672/1	0 incr.		L_ComparePhi 1 : Window		
C01672/2	0 incr.		L_ComparePhi 2 : Window		
C01672/3	0 incr.		L_ComparePhi 3 : Window		
C01672/4	0 incr.		L_ComparePhi 4 : Window		
C01672/5	0 incr.		L_ComparePhi 5 : Window		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C01751

Parameter Name:		Data type: UNSIGNED_8
C01751 Service code inverter characteristic		Index: 22824 _d = 5928 _h
This code is for device-internal use only and must not be written to by the user!		

C01752

Parameter Name:		Data type: UNSIGNED_8
C01752	Service par. inverter charact. function	Index: 22823 _d = 5927 _h
This code is for device-internal use only and must not be written to by the user!		

C01755

Parameter Name:	Data type: INTEGER_16
C01755 Service par. inverter charact. factor	Index: 22820 _d = 5924 _h
This code is for device-internal use only and must not be written to by the user!	

C01763

Parameter Name:	Data type: INTEGER_16
C01763 Service code -clamp threshold	Index: 22812 _d = 591C _h
This code is for device-internal use only and must not be written to by the user!	

C01764

Parameter Name:		Data type: UNSIGNED_8
C01764	Service par. clamp time	Index: 22811 _d = 591B _h
This code is for device-internal use only and must not be written to by the user!		

C01765

Parameter Name:	Data type: UNSIGNED_16
C01765 Service code - difference threshold UG	Index: 22810 _d = 591A _h
This code is for device-internal use only and must not be written to by the user!	

C01770

Parameter Name: C01770 Filter time - earth-fault detect. is running			Data type: UNSIGNED_8 Index: 22805 _d = 5915 _h	
Setting range (min. value unit max. value)			Lenze setting	
0	ms	250	2 ms	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1				

C01771

Parameter Name: C01771 BU-Osc: Cycle time selection			Data type: UNSIGNED_8 Index: 22804 _d = 5914 _h	
This code is for device-internal use only and must not be written to by the user!				

C01772

Parameter Name: C01772 BU-Osc: Trigger channel selection			Data type: UNSIGNED_8 Index: 22803 _d = 5913 _h	
This code is for device-internal use only and must not be written to by the user!				

C01773

Parameter Name: C01773 BU-Osc: Trigger command			Data type: UNSIGNED_8 Index: 22802 _d = 5912 _h	
This code is for device-internal use only and must not be written to by the user!				

C01774

Parameter Name: C01774 BU-Osc: Trigger mode			Data type: UNSIGNED_8 Index: 22801 _d = 5911 _h	
This code is for device-internal use only and must not be written to by the user!				

C01775

Parameter Name: C01775 BU-Osc: Trigger		Data type: INTEGER_16 Index: 22800 _d = 5910 _h
This code is for device-internal use only and must not be written to by the user!		

C01902

Parameter Name:		Data type: UNSIGNED_16 Index: 22673 _d = 5891 _h	
C01902 Diagnostics X6: Max. baud rate			
Maximally permissible baud rate in the standard device after determination of the baud rate at the diagnostic interface X6			
Selection list (Lenze setting printed in bold)			
192	19.200 Bd		
384	38.400 Bd		
576	57.600 Bd		
750	75.000 Bd		
1152	115.200 Bd		
1500	150.000 Bd		
2500	250.000 Bd		
3750	375.000 Bd		
7500	750.000 Bd		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01903

Parameter Name: C01903 Diagnostics X6: Change baud rate		Data type: UNSIGNED_8 Index: 22672 _d = 5890 _h	
New baud rate determination at the diagnostic interface X6			
Selection list (Lenze setting printed in bold)			
0	Ignore changes		
1	Negotiate baud rate		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C01905

Parameter Name: C01905 Diagnostics X6: Current baud rate			Data type: UNSIGNED_32 Index: 22670 _d = 588E _h	
Current baud rate at the diagnostic interface X6				
Display range (min. value unit max. value)				
0	Bd	3000000		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1				

C02200

Parameter Name: C02200 LS_WriteParamList: Function		Data type: UNSIGNED_8 Index: 22375 _d = 5767 _h	
From version 12.00.00 Configuration of which parameter lists are to be subject to the " Parameter change-over " function.			
Selection list			
0	Off		
1	On		
Subcodes	Lenze setting	Info	
C02200/1	1: On	Definable parameter list	
C02200/2	0: Off	Motor data parameter list	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C02210

Parameter Name: C02210 LS_WriteParamList: Motor control			Data type: UNSIGNED_8 Index: 22365 _d = 575D _h
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Selection list			
1	SC: Servo control PSM		
2	SC: Servo control ASM		
3	SLPSM: Sensorless PSM		
4	SLVC: Vector control		
6	VFCplus: V/f linear		
7	VFCplus: V/f linear + encoder		
8	VFCplus: V/f quadr		
9	VFCplus: V/f quadr + encoder		
10	VFCplus: V/f definable		
11	VFCplusEco: V/f energy-saving		
Subcodes	Lenze setting	Info	
C02210/1	6: VFCplus: V/f linear	LS_WriteParamList : c6_val1	
C02210/2	6: VFCplus: V/f linear	LS_WriteParamList : c6_val2	
C02210/3	6: VFCplus: V/f linear	LS_WriteParamList : c6_val3	
C02210/4	6: VFCplus: V/f linear	LS_WriteParamList : c6_val3	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C02212

Parameter Name: C02212 LS_WriteParamList: VFC: V/f base frequency			Data type: UNSIGNED_16 Index: 22363 _d = 575B _h
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Setting range (min. value unit max. value)			
7.5	Hz	2600.0	
Subcodes	Lenze setting	Info	
C02212/1	50.0 Hz	LS_WriteParamList : c15_val1	
C02212/2	50.0 Hz	LS_WriteParamList : c15_val2	
C02212/3	50.0 Hz	LS_WriteParamList : c15_val3	
C02212/4	50.0 Hz	LS_WriteParamList : c15_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10			

C02213

Parameter Name: C02213 LS_WriteParamList: VFC: Vmin boost			Data type: UNSIGNED_16 Index: 22362 _d = 575A _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	%	100.00			
Subcodes	Lenze setting	Info			
C02213/1	1.60 %	LS_WriteParamList : c16_val1			
C02213/2	1.60 %	LS_WriteParamList : c16_val2			
C02213/3	1.60 %	LS_WriteParamList : c16_val3			
C02213/4	1.60 %	LS_WriteParamList : c16_val4			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02214

Parameter Name: C02214 LS_WriteParamList: Switching frequency		Data type: UNSIGNED_8 Index: 22361 _d = 5759 _h	
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Selection list			
1	4 kHz var./drive-optimised		
2	8 kHz var./drive-optimised		
3	16 kHz var./drive-optimised		
5	2 kHz constant/drive-optimised		
6	4 kHz constant/drive-optimised		
7	8 kHz constant/drive-optimised		
8	16 kHz constant/drive-optimised		
11	4 kHz var./min. Pv		
12	8 kHz var./min. Pv		
13	16 kHz var./min. Pv		
15	2 kHz constant/min. Pv		
16	4 kHz constant/min. Pv		
17	8 kHz constant/min. Pv		
18	16 kHz constant/min. Pv		
21	8 kHz var./drive-opt./4 kHz min		
22	16 kHz var./drive-opt./4 kHz min		
23	16 kHz var./drive-opt./8 kHz min		
31	8 kHz var./min. Pv/4 kHz min		
32	16 kHz var./min. Pv/4 kHz min		
33	16 kHz var./min. Pv/8 kHz min		
Subcodes	Lenze setting		Info
C02214/1	2: 8 kHz var./drive-opt.		LS_WriteParamList : c18_val1
C02214/2	2: 8 kHz var./drive-opt.	LS_WriteParamList : c18_val2	
C02214/3	2: 8 kHz var./drive-opt.	LS_WriteParamList : c18_val3	
C02214/4	2: 8 kHz var./drive-opt.	LS_WriteParamList : c18_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C02215

Parameter Name: C02215 LS_WriteParamList: Auto-DCB: Threshold			Data type: UNSIGNED_16 Index: 22360 _d = 5758 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0	rpm	60000			
Subcodes	Lenze setting		Info		
C02215/1	3 rpm		LS_WriteParamList : c19_val1		
C02215/2	3 rpm		LS_WriteParamList : c19_val2		
C02215/3	3 rpm		LS_WriteParamList : c19_val3		
C02215/4	3 rpm		LS_WriteParamList : c19_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C02216

Parameter Name: C02216 LS_WriteParamList: Slip compensation			Data type: INTEGER_16 Index: 22359 _d = 5757 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
-100.00	%	100.00			
Subcodes	Lenze setting		Info		
C02216/1	2.67 %		LS_WriteParamList : c21_val1		
C02216/2	2.67 %		LS_WriteParamList : c21_val2		
C02216/3	2.67 %		LS_WriteParamList : c21_val3		
C02216/4	2.67 %		LS_WriteParamList : c21_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02217

Parameter Name: C02217 LS_WriteParamList: I_{max} in motor mode			Data type: UNSIGNED_16 Index: 22358 _d = 5756 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	A	655.35			
Subcodes	Lenze setting		Info		
C02217/1	47.00 A		LS_WriteParamList : c22_val1		
C02217/2	47.00 A		LS_WriteParamList : c22_val2		
C02217/3	47.00 A		LS_WriteParamList : c22_val3		
C02217/4	47.00 A		LS_WriteParamList : c22_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02218

Parameter Name: C02218 LS_WriteParamList: I_{max} in generator mode			Data type: INTEGER_16 Index: 22357 _d = 5755 _h
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Setting range (min. value unit max. value)			
0.00	%	100.00	
Subcodes	Lenze setting	Info	
C02218/1	100.00 %	LS_WriteParamList : c23_val1	
C02218/2	100.00 %	LS_WriteParamList : c23_val2	
C02218/3	100.00 %	LS_WriteParamList : c23_val3	
C02218/4	100.00 %	LS_WriteParamList : c23_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C02219

Parameter Name: C02219 LS_WriteParamList: DC braking: Current			Data type: INTEGER_16 Index: 22356 _d = 5754 _h
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Setting range (min. value unit max. value)			
0.00	%	200.00	
Subcodes	Lenze setting	Info	
C02219/1	50.00 %	LS_WriteParamList : c36_val1	
C02219/2	50.00 %	LS_WriteParamList : c36_val2	
C02219/3	50.00 %	LS_WriteParamList : c36_val3	
C02219/4	50.00 %	LS_WriteParamList : c36_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C02220

Parameter Name: C02220 LS_WriteParamList: Vp speed controller			Data type: UNSIGNED_16 Index: 22355 _d = 5753 _h
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Setting range (min. value unit max. value)			
0.00		600.00	
Subcodes	Lenze setting	Info	
C02220/1	15.00	LS_WriteParamList : c70_s1_val1	
C02220/2	15.00	LS_WriteParamList : c70_s1_val2	
C02220/3	15.00	LS_WriteParamList : c70_s1_val3	
C02220/4	15.00	LS_WriteParamList : c70_s1_val4	
C02220/5	6.00	LS_WriteParamList : c70_s2_val1	
C02220/6	6.00	LS_WriteParamList : c70_s2_val2	
C02220/7	6.00	LS_WriteParamList : c70_s2_val3	
C02220/8	6.00	LS_WriteParamList : c70_s2_val4	
C02220/9	3.00	LS_WriteParamList : c70_s3_val1	
C02220/10	3.00	LS_WriteParamList : c70_s3_val2	
C02220/11	3.00	LS_WriteParamList : c70_s3_val3	
C02220/12	3.00	LS_WriteParamList : c70_s3_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C02221

Parameter | Name: C02221 | LS_WriteParamList: Ti speed controller

Data type: UNSIGNED_16
Index: 22354_d = 5752_h

From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional [motor data change-over](#)

Setting range (min. value unit max. value)			
0.0	ms	6000.0	
Subcodes	Lenze setting	Info	
C02221/1	100.0 ms	LS_WriteParamList : c71_s1_val1	
C02221/2	100.0 ms	LS_WriteParamList : c71_s1_val2	
C02221/3	100.0 ms	LS_WriteParamList : c71_s1_val3	
C02221/4	100.0 ms	LS_WriteParamList : c71_s1_val4	
C02221/5	50.0 ms	LS_WriteParamList : c71_s2_val1	
C02221/6	50.0 ms	LS_WriteParamList : c71_s2_val2	
C02221/7	50.0 ms	LS_WriteParamList : c71_s2_val3	
C02221/8	50.0 ms	LS_WriteParamList : c71_s2_val4	
C02221/9	100.0 ms	LS_WriteParamList : c71_s3_val1	
C02221/10	100.0 ms	LS_WriteParamList : c71_s3_val2	
C02221/11	100.0 ms	LS_WriteParamList : c71_s3_val3	
C02221/12	100.0 ms	LS_WriteParamList : c71_s3_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10			

C02222

Parameter Name: C02222 LS_WriteParamList: SC: Tdn speed controller			Data type: UNSIGNED_16 Index: 22353 _d = 5751 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	ms	3.00			
Subcodes	Lenze setting	Info			
C02222/1	0.00 ms	LS_WriteParamList : c72_val1			
C02222/2	0.00 ms	LS_WriteParamList : c72_val2			
C02222/3	0.00 ms	LS_WriteParamList : c72_val3			
C02222/4	0.00 ms	LS_WriteParamList : c72_val4			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02223

Parameter Name: C02223 LS_WriteParamList: Imax/M controller gain			Data type: UNSIGNED_16 Index: 22352 _d = 5750 _h
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Setting range (min. value unit max. value)			
0.00		100.00	
Subcodes	Lenze setting	Info	
C02223/1	0.25	LS_WriteParamList : c73_s1_val1	
C02223/2	0.25	LS_WriteParamList : c73_s1_val2	
C02223/3	0.25	LS_WriteParamList : c73_s1_val3	
C02223/4	0.25	LS_WriteParamList : c73_s1_val4	
C02223/5	1.25	LS_WriteParamList : c73_s2_val1	
C02223/6	1.25	LS_WriteParamList : c73_s2_val2	
C02223/7	1.25	LS_WriteParamList : c73_s2_val3	
C02223/8	1.25	LS_WriteParamList : c73_s2_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C02224

Parameter Name: C02224 LS_WriteParamList: Imax/M controller reset time		Data type: UNSIGNED_16 Index: 22351 _d = 574F _h
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over		
Setting range (min. value unit max. value)		
0	ms 9990	
Subcodes	Lenze setting	Info
C02224/1	65 ms	LS_WriteParamList: c74_s1_val1
C02224/2	65 ms	LS_WriteParamList: c74_s1_val2
C02224/3	65 ms	LS_WriteParamList: c74_s1_val3
C02224/4	65 ms	LS_WriteParamList: c74_s1_val4
C02224/5	30 ms	LS_WriteParamList: c74_s2_val1
C02224/6	30 ms	LS_WriteParamList: c74_s2_val2
C02224/7	30 ms	LS_WriteParamList: c74_s2_val3
C02224/8	30 ms	LS_WriteParamList: c74_s2_val4
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C02225

Parameter Name: C02225 LS_WriteParamList: Vp current controller			Data type: UNSIGNED_16 Index: 22350 _d = 574E _h
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Setting range (min. value unit max. value)			
0.00	V/A	500.00	
Subcodes	Lenze setting	Info	
C02225/1	7.00 V/A	LS_WriteParamList: c75_val1	
C02225/2	7.00 V/A	LS_WriteParamList: c75_val2	
C02225/3	7.00 V/A	LS_WriteParamList: c75_val3	
C02225/4	7.00 V/A	LS_WriteParamList: c75_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C02226

Parameter Name: C02226 LS_WriteParamList: Ti current controller			Data type: UNSIGNED_16 Index: 22349 _d = 574D _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	ms	500.00			
Subcodes	Lenze setting		Info		
C02226/1	10.61 ms		LS_WriteParamList: c76_val1		
C02226/2	10.61 ms		LS_WriteParamList: c76_val2		
C02226/3	10.61 ms		LS_WriteParamList: c76_val3		
C02226/4	10.61 ms		LS_WriteParamList: c76_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02227

Parameter Name: C02227 LS_WriteParamList: SC: Vp field controller			Data type: UNSIGNED_16 Index: 22348 _d = 574C _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00		500.00			
Subcodes	Lenze setting		Info		
C02227/1	12.80		LS_WriteParamList : c77_val1		
C02227/2	12.80		LS_WriteParamList : c77_val2		
C02227/3	12.80		LS_WriteParamList : c77_val3		
C02227/4	12.80		LS_WriteParamList : c77_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02228

Parameter Name: C02228 LS_WriteParamList: SC: Tn field controller			Data type: UNSIGNED_16 Index: 22347 _d = 574B _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.0	ms	6000.0			
Subcodes	Lenze setting		Info		
C02228/1	256.0 ms		LS_WriteParamList : c78_val1		
C02228/2	256.0 ms		LS_WriteParamList : c78_val2		
C02228/3	256.0 ms		LS_WriteParamList : c78_val3		
C02228/4	256.0 ms		LS_WriteParamList : c78_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C02229

Parameter | Name:
C02229 | LS_WriteParamList: SC: Settings

Data type: UNSIGNED_8
Index: 22346_d = 574A_h

From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional [motor data change-over](#)

Selection list		
0	Off	
1	On	
Subcodes	Lenze setting	Info
C02229/1	0: Off	LS_WriteParamList : c79_s1_val1
C02229/2	0: Off	LS_WriteParamList : c79_s1_val2
C02229/3	0: Off	LS_WriteParamList : c79_s1_val3
C02229/4	0: Off	LS_WriteParamList : c79_s1_val4
C02229/5	1: On	LS_WriteParamList : c79_s2_val1
C02229/6	1: On	LS_WriteParamList : c79_s2_val2
C02229/7	1: On	LS_WriteParamList : c79_s2_val3
C02229/8	1: On	LS_WriteParamList : c79_s2_val4
C02229/9	0: Off	LS_WriteParamList : c79_s3_val1
C02229/10	0: Off	LS_WriteParamList : c79_s3_val2
C02229/11	0: Off	LS_WriteParamList : c79_s3_val3
C02229/12	0: Off	LS_WriteParamList : c79_s3_val4
C02229/13	1: On	LS_WriteParamList : c79_s4_val1
C02229/14	1: On	LS_WriteParamList : c79_s4_val2
C02229/15	1: On	LS_WriteParamList : c79_s4_val3
C02229/16	1: On	LS_WriteParamList : c79_s4_val4

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☒ MOT Scaling factor: 1

C02230

Parameter Name:			Data type: INTEGER_16
C02230 LS_WriteParamList: Override point of field weakening			Index: 22345 _d = 5749 _h
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Setting range (min. value unit max. value)			
-500	Hz	500	
Subcodes	Lenze setting	Info	
C02230/1	0 Hz	LS_WriteParamList : c80_val1	
C02230/2	0 Hz	LS_WriteParamList : c80_val2	
C02230/3	0 Hz	LS_WriteParamList : c80_val3	
C02230/4	0 Hz	LS_WriteParamList : c80_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C02231

Parameter Name: C02231 LS_WriteParamList: Rated motor power			Data type: UNSIGNED_16 Index: 22344 _d = 5748 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	kW	500.00			
Subcodes	Lenze setting		Info		
C02231/1	11.00 kW		LS_WriteParamList : c81_val1		
C02231/2	11.00 kW		LS_WriteParamList : c81_val2		
C02231/3	11.00 kW		LS_WriteParamList : c81_val3		
C02231/4	11.00 kW		LS_WriteParamList : c81_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02232

Parameter Name: C02232 LS_WriteParamList: Motor rotor resistance			Data type: UNSIGNED_32 Index: 22343 _d = 5747 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0	mOhm	200000			
Subcodes	Lenze setting		Info		
C02232/1	276 mOhm		LS_WriteParamList : c82_val1		
C02232/2	276 mOhm		LS_WriteParamList : c82_val2		
C02232/3	276 mOhm		LS_WriteParamList : c82_val3		
C02232/4	276 mOhm		LS_WriteParamList : c82_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C02233

Parameter Name: C02233 LS_WriteParamList: Motor stator resistance			Data type: UNSIGNED_32 Index: 22342 _d = 5746 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0	mOhm	200000			
Subcodes	Lenze setting		Info		
C02233/1	330 mOhm		LS_WriteParamList : c84_val1		
C02233/2	330 mOhm		LS_WriteParamList : c84_val2		
C02233/3	330 mOhm		LS_WriteParamList : c84_val3		
C02233/4	330 mOhm		LS_WriteParamList : c84_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C02234

Parameter Name: C02234 LS_WriteParamList: Motor stator leakage inductance			Data type: UNSIGNED_16 Index: 22341 _d = 5745 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	mH	650.00			
Subcodes	Lenze setting		Info		
C02234/1	3.50 mH		LS_WriteParamList : c85_val1		
C02234/2	3.50 mH		LS_WriteParamList : c85_val2		
C02234/3	3.50 mH		LS_WriteParamList : c85_val3		
C02234/4	3.50 mH		LS_WriteParamList : c85_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02236

Parameter Name:			Data type: UNSIGNED_16 Index: 22339 _d = 5743 _h		
C02236 LS_WriteParamList: Rated motor speed					
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
50	rpm	60000			
Subcodes	Lenze setting		Info		
C02236/1	1460 rpm		LS_WriteParamList : c87_val1		
C02236/2	1460 rpm		LS_WriteParamList : c87_val2		
C02236/3	1460 rpm		LS_WriteParamList : c87_val3		
C02236/4	1460 rpm		LS_WriteParamList : c87_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C02237

Parameter Name: C02237 LS_WriteParamList: Rated motor current			Data type: UNSIGNED_16 Index: 22338 _d = 5742 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.20	A	320.00			
Subcodes	Lenze setting		Info		
C02237/1	21.00 A		LS_WriteParamList : c88_val1		
C02237/2	21.00 A		LS_WriteParamList : c88_val2		
C02237/3	21.00 A		LS_WriteParamList : c88_val3		
C02237/4	21.00 A		LS_WriteParamList : c88_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02238

Parameter Name: C02238 LS_WriteParamList: Rated motor frequency			Data type: UNSIGNED_16 Index: 22337 _d = 5741 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
1	Hz	1000			
Subcodes	Lenze setting		Info		
C02238/1	50 Hz		LS_WriteParamList : c89_val1		
C02238/2	50 Hz		LS_WriteParamList : c89_val2		
C02238/3	50 Hz		LS_WriteParamList : c89_val3		
C02238/4	50 Hz		LS_WriteParamList : c89_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C02239

Parameter Name:			Data type: UNSIGNED_16 Index: 22336 _d = 5740 _h		
C02239 LS_WriteParamList: Rated motor voltage					
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0	V	5000			
Subcodes	Lenze setting		Info		
C02239/1	400 V		LS_WriteParamList : c90_val1		
C02239/2	400 V		LS_WriteParamList : c90_val2		
C02239/3	400 V		LS_WriteParamList : c90_val3		
C02239/4	400 V		LS_WriteParamList : c90_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C02240

Parameter Name: C02240 LS_WriteParamList: Motor cosine phi			Data type: UNSIGNED_8 Index: 22335 _d = 573F _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.40		1.00			
Subcodes	Lenze setting		Info		
C02240/1	0.85		LS_WriteParamList : c91_val1		
C02240/2	0.85		LS_WriteParamList : c91_val2		
C02240/3	0.85		LS_WriteParamList : c91_val3		
C02240/4	0.85		LS_WriteParamList : c91_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02241

Parameter Name: C02241 LS_WriteParamList: Motor magnetizing inductance			Data type: UNSIGNED_16 Index: 22334 _d = 573E _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.0	mH	6500.0			
Subcodes	Lenze setting		Info		
C02241/1	81.0 mH		LS_WriteParamList : c92_val1		
C02241/2	81.0 mH		LS_WriteParamList : c92_val2		
C02241/3	81.0 mH		LS_WriteParamList : c92_val3		
C02241/4	81.0 mH		LS_WriteParamList : c92_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C02242

Parameter Name:			Data type: UNSIGNED_16 Index: 22333 _d = 573D _h		
C02242 LS_WriteParamList: Motor magnetising current					
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	A	320.00			
Subcodes	Lenze setting		Info		
C02242/1	8.50 A		LS_WriteParamList : c95_val1		
C02242/2	8.50 A		LS_WriteParamList : c95_val2		
C02242/3	8.50 A		LS_WriteParamList : c95_val3		
C02242/4	8.50 A		LS_WriteParamList : c95_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02244

Parameter Name: C02244 LS_WriteParamList: Auto-DCB: Hold time			Data type: UNSIGNED_32 Index: 22331 _d = 573B _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.000	s	999.000			
Subcodes	Lenze setting		Info		
C02244/1	0.500 s		LS_WriteParamList : c106_val1		
C02244/2	0.500 s		LS_WriteParamList : c106_val2		
C02244/3	0.500 s		LS_WriteParamList : c106_val3		
C02244/4	0.500 s		LS_WriteParamList : c106_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C02245

Parameter Name: C02245 LS_WriteParamList: DC braking: Hold time			Data type: UNSIGNED_32 Index: 22330 _d = 573A _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.000	s	999.000			
Subcodes	Lenze setting		Info		
C02245/1	998.999 s		LS_WriteParamList : c107_val1		
C02245/2	998.999 s		LS_WriteParamList : c107_val2		
C02245/3	998.999 s		LS_WriteParamList : c107_val3		
C02245/4	998.999 s		LS_WriteParamList : c107_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1000					

C02246

Parameter Name: C02246 LS_WriteParamList: Setting of motor overload (I²t)			Data type: INTEGER_16 Index: 22329 _d = 5739 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	%	250.00			
Subcodes	Lenze setting		Info		
C02246/1	100.00 %		LS_WriteParamList : c120_val1		
C02246/2	100.00 %		LS_WriteParamList : c120_val2		
C02246/3	100.00 %		LS_WriteParamList : c120_val3		
C02246/4	100.00 %		LS_WriteParamList : c120_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02249

Parameter Name: C02249 LS_WriteParamList: Oscillation damping influence			Data type: UNSIGNED_16 Index: 22326 _d = 5736 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	%	250.00			
Subcodes	Lenze setting		Info		
C02249/1	5.00 %		LS_WriteParamList : c234_val1		
C02249/2	5.00 %		LS_WriteParamList : c234_val2		
C02249/3	5.00 %		LS_WriteParamList : c234_val3		
C02249/4	5.00 %		LS_WriteParamList : c234_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02250

Parameter Name: C02250 LS_WriteParamList: Filter time - oscill. damping			Data type: UNSIGNED_8 Index: 22325 _d = 5735 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
2	ms	250			
Subcodes	Lenze setting		Info		
C02250/1	32 ms		LS_WriteParamList : c235_val1		
C02250/2	32 ms		LS_WriteParamList : c235_val2		
C02250/3	32 ms		LS_WriteParamList : c235_val3		
C02250/4	32 ms		LS_WriteParamList : c235_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C02251

Parameter Name:			Data type: UNSIGNED_8 Index: 22324 _d = 5734 _h		
C02251 LS_WriteParamList: Oscillation damping field weakening					
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0		40			
Subcodes	Lenze setting		Info		
C02251/1	14		LS_WriteParamList : c236_val1		
C02251/2	14		LS_WriteParamList : c236_val2		
C02251/3	14		LS_WriteParamList : c236_val3		
C02251/4	14		LS_WriteParamList : c236_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C02252

Parameter Name: C02252 LS_WriteParamList: Kp position controller			Data type: UNSIGNED_16 Index: 22323 _d = 5733 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	1/s	500.00			
Subcodes	Lenze setting		Info		
C02252/1	5.00 1/s		LS_WriteParamList : c254_val1		
C02252/2	5.00 1/s		LS_WriteParamList : c254_val2		
C02252/3	5.00 1/s		LS_WriteParamList : c254_val3		
C02252/4	5.00 1/s		LS_WriteParamList : c254_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02256

Parameter Name: C02256 LS_WriteParamList: Moment of inertia			Data type: UNSIGNED_32 Index: 22319 _d = 572F _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	kg cm^2	6000000.00			
Subcodes	Lenze setting		Info		
C02256/1	0.00 kg cm^2		LS_WriteParamList : c273_val1		
C02256/2	0.00 kg cm^2		LS_WriteParamList : c273_val2		
C02256/3	0.00 kg cm^2		LS_WriteParamList : c273_val3		
C02256/4	0.00 kg cm^2		LS_WriteParamList : c273_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02260

Parameter | Name:

C02260 | LS_WriteParamList: Speed sensor selection

Data type: UNSIGNED_8

Index: 22315_d = 572B_h

From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional [motor data change-over](#)

Selection list		
0	No sensor	
1	Sensor signal FreqIn12	
2	Encoder signal FreqIn67	
3	Multi encoder	
4	Resolver	
5	Encoder signal FreqIn1267	
Subcodes	Lenze setting	Info
C02260/1	0: No sensor	LS_WriteParamList: c495_val1
C02260/2	0: No sensor	LS_WriteParamList: c495_val2
C02260/3	0: No sensor	LS_WriteParamList: c495_val3
C02260/4	0: No sensor	LS_WriteParamList: c495_val4

☒ Read access
 ☒ Write access
 ☐ CINH
 ☐ PLC STOP
 ☐ No transfer
 ☐ COM
 ☒ MOT
 Scaling factor: 1

C02261

Parameter Name: C02261 LS_WriteParamList: SC: Field feedforward control			Data type: UNSIGNED_16 Index: 22314 _d = 572A _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0	%	600			
Subcodes	Lenze setting		Info		
C02261/1	200 %		LS_WriteParamList : c576_val1		
C02261/2	200 %		LS_WriteParamList : c576_val2		
C02261/3	200 %		LS_WriteParamList : c576_val3		
C02261/4	200 %		LS_WriteParamList : c576_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C02262

Parameter Name: C02262 LS_WriteParamList: SC: Vp field weakening controller			Data type: UNSIGNED_16 Index: 22313 _d = 5729 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.0000		2.0000			
Subcodes	Lenze setting		Info		
C02262/1	0.0010		LS_WriteParamList : c577_val1		
C02262/2	0.0010		LS_WriteParamList : c577_val2		
C02262/3	0.0010		LS_WriteParamList : c577_val3		
C02262/4	0.0010		LS_WriteParamList : c577_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10000					

C02263

Parameter Name: C02263 LS_WriteParamList: SC: Tn field weakening controller			Data type: UNSIGNED_16 Index: 22312 _d = 5728 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.1	ms	6000.0			
Subcodes	Lenze setting		Info		
C02263/1	20.0 ms		LS_WriteParamList : c578_val1		
C02263/2	20.0 ms		LS_WriteParamList : c578_val2		
C02263/3	20.0 ms		LS_WriteParamList : c578_val3		
C02263/4	20.0 ms		LS_WriteParamList : c578_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10					

C02264

Parameter Name: C02264 LS_WriteParamList: Empfindlichkeit Sollwertvorsteuerung		Data type: UNSIGNED_8 Index: 22311 _d = 5727 _h	
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Selection list			
0	Inactive		
1	15 bits		
2	14 bits		
3	13 bits		
4	12 bits		
5	11 Bit		
6	10 Bit		
7	9 Bit		
Subcodes	Lenze setting	Info	
C02264/1	0: Inactive	LS_WriteParamList : C653_s1_val1	
C02264/2	0: Inactive	LS_WriteParamList : C653_s1_val2	
C02264/3	0: Inactive	LS_WriteParamList : C653_s1_val3	
C02264/4	0: Inactive	LS_WriteParamList : C653_s1_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C02272

Parameter Name:		Data type: UNSIGNED_8 Index: 22303 _d = 571F _h	
C02272 LS_WriteParamList: Motor phase direction of rotation			
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Selection list			
0	not inverted		
1	inverted		
Subcodes	Lenze setting	Info	
C02272/1	0: Not inverted	LS_WriteParamList : c905_val1	
C02272/2	0: Not inverted	LS_WriteParamList : c905_val2	
C02272/3	0: Not inverted	LS_WriteParamList : c905_val3	
C02272/4	0: Not inverted	LS_WriteParamList : c905_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input checked="" type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C02273

Parameter Name:		Data type: INTEGER_16 Index: 22302 _d = 571E _h	
C02273 LS_WriteParamList: Speed limitation			
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Setting range (min. value unit max. value)			
0.00	%	175.00	
Subcodes	Lenze setting	Info	
C02273/1	120.00 %	LS_WriteParamList : c909_s1_val1	
C02273/2	120.00 %	LS_WriteParamList : c909_s1_val2	
C02273/3	120.00 %	LS_WriteParamList : c909_s1_val3	
C02273/4	120.00 %	LS_WriteParamList : c909_s1_val4	
C02273/5	120.00 %	LS_WriteParamList : c909_s2_val1	
C02273/6	120.00 %	LS_WriteParamList : c909_s2_val2	
C02273/7	120.00 %	LS_WriteParamList : c909_s2_val3	
C02273/8	120.00 %	LS_WriteParamList : c909_s2_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C02274

Parameter Name: C02274 LS_WriteParamList: Frequency limitation			Data type: UNSIGNED_16 Index: 22301 _d = 571D _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0	Hz	1300			
Subcodes	Lenze setting		Info		
C02274/1	1000 Hz		LS_WriteParamList : c910_s1_val1		
C02274/2	1000 Hz		LS_WriteParamList : c910_s1_val2		
C02274/3	1000 Hz		LS_WriteParamList : c910_s1_val3		
C02274/4	1000 Hz		LS_WriteParamList : c910_s1_val4		
C02274/5	1000 Hz		LS_WriteParamList : c910_s2_val1		
C02274/6	1000 Hz		LS_WriteParamList : c910_s2_val2		
C02274/7	1000 Hz		LS_WriteParamList : c910_s2_val3		
C02274/8	1000 Hz		LS_WriteParamList : c910_s2_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C02275

Parameter Name: C02275 LS_WriteParamList: Motor cable length			Data type: UNSIGNED_16 Index: 22300 _d = 571C _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.0	m	1000.0			
Subcodes	Lenze setting		Info		
C02275/1	5.0 m		LS_WriteParamList : c915_val1		
C02275/2	5.0 m		LS_WriteParamList : c915_val2		
C02275/3	5.0 m		LS_WriteParamList : c915_val3		
C02275/4	5.0 m		LS_WriteParamList : c915_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C02276

Parameter Name: C02276 LS_WriteParamList: Motor cable cross-section			Data type: UNSIGNED_16 Index: 22299 _d = 571B _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.50	mm^2	100.00			
Subcodes	Lenze setting		Info		
C02276/1	6.00 mm^2		LS_WriteParamList : c916_val1		
C02276/2	6.00 mm^2		LS_WriteParamList : c916_val2		
C02276/3	6.00 mm^2		LS_WriteParamList : c916_val3		
C02276/4	6.00 mm^2		LS_WriteParamList : c916_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02278

Parameter Name: C02278 LS_WriteParamList: PSM: Maximum motor current field weakening			Data type: UNSIGNED_16 Index: 22297 _d = 5719 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	%	500.00			
Subcodes	Lenze setting		Info		
C02278/1	30.00 %		LS_WriteParamList : c938_val1		
C02278/2	30.00 %		LS_WriteParamList : c938_val2		
C02278/3	30.00 %		LS_WriteParamList : c938_val3		
C02278/4	30.00 %		LS_WriteParamList : c938_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02279

Parameter Name: C02279 LS_WriteParamList: Ultimate motor current			Data type: UNSIGNED_16 Index: 22296 _d = 5718 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.0	A	3000.0			
Subcodes	Lenze setting		Info		
C02279/1	3000.0 A		LS_WriteParamList : c939_val1		
C02279/2	3000.0 A		LS_WriteParamList : c939_val2		
C02279/3	3000.0 A		LS_WriteParamList : c939_val3		
C02279/4	3000.0 A		LS_WriteParamList : c939_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C02280

Parameter Name: C02280 LS_WriteParamList: Max. motor speed			Data type: UNSIGNED_16 Index: 22295 _d = 5717 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
50	rpm	65000			
Subcodes	Lenze setting		Info		
C02280/1	60000 rpm		LS_WriteParamList: c965_val1		
C02280/2	60000 rpm		LS_WriteParamList: c965_val2		
C02280/3	60000 rpm		LS_WriteParamList: c965_val3		
C02280/4	60000 rpm		LS_WriteParamList: c965_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C02281

Parameter Name: C02281 LS_WriteParamList: VFC: Time const. slip comp.			Data type: UNSIGNED_16 Index: 22294 _d = 5716 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
1	ms	6000			
Subcodes	Lenze setting		Info		
C02281/1	100 ms		LS_WriteParamList : c966_val1		
C02281/2	100 ms		LS_WriteParamList : c966_val2		
C02281/3	100 ms		LS_WriteParamList : c966_val3		
C02281/4	100 ms		LS_WriteParamList : c966_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C02284

Parameter Name: C02284 LS_WriteParamList: VFC: limitation V/f +encoder			Data type: UNSIGNED_16 Index: 22291 _d = 5713 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	Hz	100.00			
Subcodes	Lenze setting	Info			
C02284/1	10.00 Hz	LS_WriteParamList : c971_s1_val1			
C02284/2	10.00 Hz	LS_WriteParamList : c971_s1_val2			
C02284/3	10.00 Hz	LS_WriteParamList : c971_s1_val3			
C02284/4	10.00 Hz	LS_WriteParamList : c971_s1_val4			
C02284/5	100.00 Hz	LS_WriteParamList : c971_s2_val1			
C02284/6	100.00 Hz	LS_WriteParamList : c971_s2_val2			
C02284/7	100.00 Hz	LS_WriteParamList : c971_s2_val3			
C02284/8	100.00 Hz	LS_WriteParamList : c971_s2_val4			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02285

Parameter Name: C02285 LS_WriteParamList: VFC: Vp V/f +encoder			Data type: UNSIGNED_16 Index: 22290 _d = 5712 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.000	Hz/Hz	64.000			
Subcodes	Lenze setting		Info		
C02285/1	0.100 Hz/Hz		LS_WriteParamList : c972_val1		
C02285/2	0.100 Hz/Hz		LS_WriteParamList : c972_val2		
C02285/3	0.100 Hz/Hz		LS_WriteParamList : c972_val3		
C02285/4	0.100 Hz/Hz		LS_WriteParamList : c972_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1000					

C02286

Parameter Name: C02286 LS_WriteParamList: VFC: Ti V/f +encoder			Data type: UNSIGNED_16 Index: 22289 _d = 5711 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.0	ms	6000.0			
Subcodes	Lenze setting		Info		
C02286/1	100.0 ms		LS_WriteParamList: c973_val1		
C02286/2	100.0 ms		LS_WriteParamList: c973_val2		
C02286/3	100.0 ms		LS_WriteParamList: c973_val3		
C02286/4	100.0 ms		LS_WriteParamList: c973_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C02287

Parameter Name:			Data type: UNSIGNED_16 Index: 22288 _d = 5710 _h		
C02287 LS_WriteParamList: VFC-ECO: Vp CosPhi controller					
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.000	Hz/Hz	64.000			
Subcodes	Lenze setting		Info		
C02287/1	0.500 Hz/Hz		LS_WriteParamList : c975_val1		
C02287/2	0.500 Hz/Hz		LS_WriteParamList : c975_val2		
C02287/3	0.500 Hz/Hz		LS_WriteParamList : c975_val3		
C02287/4	0.500 Hz/Hz		LS_WriteParamList : c975_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1000					

C02288

Parameter Name: C02288 LS_WriteParamList: VFC-ECO: Ti CosPhi controller			Data type: UNSIGNED_16 Index: 22287 _d = 570F _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.0	ms	6000.0			
Subcodes	Lenze setting		Info		
C02288/1	200.0 ms		LS_WriteParamList: c976_val1		
C02288/2	200.0 ms		LS_WriteParamList: c976_val2		
C02288/3	200.0 ms		LS_WriteParamList: c976_val3		
C02288/4	200.0 ms		LS_WriteParamList: c976_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C02289

Parameter Name: C02289 LS_WriteParamList: VFC-ECO: Minimum voltage U/f			Data type: INTEGER_16 Index: 22286 _d = 570E _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
20.00	%	100.00			
Subcodes	Lenze setting		Info		
C02289/1	20.00 %		LS_WriteParamList : c977_val1		
C02289/2	20.00 %		LS_WriteParamList : c977_val2		
C02289/3	20.00 %		LS_WriteParamList : c977_val3		
C02289/4	20.00 %		LS_WriteParamList : c977_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02290

Parameter Name:			Data type: UNSIGNED_8 Index: 22285 _d = 570D _h		
C02290 LS_WriteParamList: VFC-ECO: Voltage reduction ramp					
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.0	s	5.0			
Subcodes	Lenze setting		Info		
C02290/1	0.8 s		LS_WriteParamList : c982_val1		
C02290/2	0.8 s		LS_WriteParamList : c982_val2		
C02290/3	0.8 s		LS_WriteParamList : c982_val3		
C02290/4	0.8 s		LS_WriteParamList : c982_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C02291

Parameter Name: C02291 LS_WriteParamList: SLVC: Field current controller gain			Data type: INTEGER_16 Index: 22284 _d = 570C _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	%	20.00			
Subcodes	Lenze setting		Info		
C02291/1	0.50 %		LS_WriteParamList : c985_val1		
C02291/2	0.50 %		LS_WriteParamList : c985_val2		
C02291/3	0.50 %		LS_WriteParamList : c985_val3		
C02291/4	0.50 %		LS_WriteParamList : c985_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02292

Parameter Name: C02292 LS_WriteParamList: SLVC: Cross current controller gain			Data type: INTEGER_16 Index: 22283 _d = 570B _h
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Setting range (min. value unit max. value)			
0.00	%	20.00	
Subcodes	Lenze setting	Info	
C02292/1	0.00 %	LS_WriteParamList : c986_val1	
C02292/2	0.00 %	LS_WriteParamList : c986_val2	
C02292/3	0.00 %	LS_WriteParamList : c986_val3	
C02292/4	0.00 %	LS_WriteParamList : c986_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100			

C02293

Parameter Name: C02293 LS_WriteParamList: Inverter motor brake: nAdd			Data type: INTEGER_16 Index: 22282 _d = 570A _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0	rpm	1000			
Subcodes	Lenze setting		Info		
C02293/1	80 rpm		LS_WriteParamList : c987_val1		
C02293/2	80 rpm		LS_WriteParamList : c987_val2		
C02293/3	80 rpm		LS_WriteParamList : c987_val3		
C02293/4	80 rpm		LS_WriteParamList : c987_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C02294

Parameter Name: C02294 LS_WriteParamList: Inverter motor brake: PT1 filter time			Data type: INTEGER_16 Index: 22281 _d = 5709 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.0	ms	100.0			
Subcodes	Lenze setting		Info		
C02294/1	0.0 ms		LS_WriteParamList : c988_val1		
C02294/2	0.0 ms		LS_WriteParamList : c988_val2		
C02294/3	0.0 ms		LS_WriteParamList : c988_val3		
C02294/4	0.0 ms		LS_WriteParamList : c988_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 10					

C02295

Parameter Name:		Data type: UNSIGNED_8 Index: 22280 _d = 5708 _h	
C02295 LS_WriteParamList: Flying restart fct.: Activation			
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Selection list			
0	Off		
1	On		
Subcodes	Lenze setting	Info	
C02295/1	0: Off	LS_WriteParamList : c990_val1	
C02295/2	0: Off	LS_WriteParamList : c990_val2	
C02295/3	0: Off	LS_WriteParamList : c990_val3	
C02295/4	0: Off	LS_WriteParamList : c990_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input checked="" type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C02296

Parameter Name:		Data type: UNSIGNED_16 Index: 22279 _d = 5707 _h	
C02296 LS_WriteParamList: Flying restart fct.: process			
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Selection list			
0	0...+n Start: +10 Hz		
1	-n...0 Start: -10 Hz		
2	-n...+n Start: +10 Hz		
3	-n...+n Start: -10 Hz		
4	-n...+n Start: Cx992		
Subcodes	Lenze setting	Info	
C02296/1	2: -n...+n Start: +10 Hz	LS_WriteParamList : c991_val1	
C02296/2	2: -n...+n Start: +10 Hz	LS_WriteParamList : c991_val2	
C02296/3	2: -n...+n Start: +10 Hz	LS_WriteParamList : c991_val3	
C02296/4	2: -n...+n Start: +10 Hz	LS_WriteParamList : c991_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C02297

Parameter Name:			Data type: INTEGER_16 Index: 22278 _d = 5706 _h		
C02297 LS_WriteParamList: Flying restart: Start frequency					
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
-200	Hz	200			
Subcodes	Lenze setting		Info		
C02297/1	10 Hz		LS_WriteParamList : c992_val1		
C02297/2	10 Hz		LS_WriteParamList : c992_val2		
C02297/3	10 Hz		LS_WriteParamList : c992_val3		
C02297/4	10 Hz		LS_WriteParamList : c992_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C02298

Parameter Name: C02298 LS_WriteParamList: Flying restart fct: Int. time			Data type: UNSIGNED_16 Index: 22277 _d = 5705 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.0	ms	6000.0			
Subcodes	Lenze setting		Info		
C02298/1	300.0 ms		LS_WriteParamList: c993_val1		
C02298/2	300.0 ms		LS_WriteParamList: c993_val2		
C02298/3	300.0 ms		LS_WriteParamList: c993_val3		
C02298/4	300.0 ms		LS_WriteParamList: c993_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C02299

Parameter Name:			Data type: INTEGER_16 Index: 22276 _d = 5704 _h		
C02299 LS_WriteParamList: Flying restart fct.: Current					
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	%	100.00			
Subcodes	Lenze setting		Info		
C02299/1	25.00 %		LS_WriteParamList : c994_val1		
C02299/2	25.00 %		LS_WriteParamList : c994_val2		
C02299/3	25.00 %		LS_WriteParamList : c994_val3		
C02299/4	25.00 %		LS_WriteParamList : c994_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02300

Parameter Name: C02300 LS_WriteParamList: SLPSM: Controlled current setpoint			Data type: UNSIGNED_16 Index: 22275 _d = 5703 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
5.00	%	400.00			
Subcodes	Lenze setting		Info		
C02300/1	100.00 %		LS_WriteParamList : c995_s1_val1		
C02300/2	100.00 %		LS_WriteParamList : c995_s1_val2		
C02300/3	100.00 %		LS_WriteParamList : c995_s1_val3		
C02300/4	100.00 %		LS_WriteParamList : c995_s1_val4		
C02300/5	20.00 %		LS_WriteParamList : c995_s2_val1		
C02300/6	20.00 %		LS_WriteParamList : c995_s2_val2		
C02300/7	20.00 %		LS_WriteParamList : c995_s2_val3		
C02300/8	20.00 %		LS_WriteParamList : c995_s2_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02301

Parameter Name: C02301 LS_WriteParamList: SLPSM: Switching speed			Data type: INTEGER_16 Index: 22274 _d = 5702 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	%	100.00			
Subcodes	Lenze setting		Info		
C02301/1	13.00 %		LS_WriteParamList : c996_s1_val1		
C02301/2	13.00 %		LS_WriteParamList : c996_s1_val2		
C02301/3	13.00 %		LS_WriteParamList : c996_s1_val3		
C02301/4	13.00 %		LS_WriteParamList : c996_s1_val4		
C02301/5	8.00 %		LS_WriteParamList : c996_s2_val1		
C02301/6	8.00 %		LS_WriteParamList : c996_s2_val2		
C02301/7	8.00 %		LS_WriteParamList : c996_s2_val3		
C02301/8	8.00 %		LS_WriteParamList : c996_s2_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C02302

Parameter Name: C02302 LS_WriteParamList: SLPSM: Filter time - rotor position			Data type: INTEGER_16 Index: 22273 _d = 5701 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.00	%	100.00			
Subcodes	Lenze setting		Info		
C02302/1	5.00 %		LS_WriteParamList : c997_val1		
C02302/2	5.00 %		LS_WriteParamList : c997_val2		
C02302/3	5.00 %		LS_WriteParamList : c997_val3		
C02302/4	5.00 %		LS_WriteParamList : c997_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C02303

Parameter Name: C02303 LS_WriteParamList: SLPSM: Filter time rotor position			Data type: INTEGER_16 Index: 22272 _d = 5700 _h		
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over					
Setting range (min. value unit max. value)					
0.5	ms	20.0			
Subcodes	Lenze setting		Info		
C02303/1	3.0 ms		LS_WriteParamList : c998_s1_val1		
C02303/2	3.0 ms		LS_WriteParamList : c998_s1_val2		
C02303/3	3.0 ms		LS_WriteParamList : c998_s1_val3		
C02303/4	3.0 ms		LS_WriteParamList : c998_s1_val4		
C02303/5	5.0 ms		LS_WriteParamList : c998_s2_val1		
C02303/6	5.0 ms		LS_WriteParamList : c998_s2_val2		
C02303/7	5.0 ms		LS_WriteParamList : c998_s2_val3		
C02303/8	5.0 ms		LS_WriteParamList : c998_s2_val4		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C02304

Parameter Name: C02304 LS_WriteParamList: SPSM: PLL gain			Data type: INTEGER_16 Index: 22271 _d = 56FF _h
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Setting range (min. value unit max. value)			
0	%	1000	
Subcodes	Lenze setting	Info	
C02304/1	400 %	LS_WriteParamList : c999_val1	
C02304/2	400 %	LS_WriteParamList : c999_val2	
C02304/3	400 %	LS_WriteParamList : c999_val3	
C02304/4	400 %	LS_WriteParamList : c999_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C02305

Parameter Name: C02305 LS_WriteParamList: PSM: Ppp saturation characteristic			Data type: UNSIGNED_8 Index: 22270 _d = 56FE _h
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Setting range (min. value unit max. value)			
0	%	255	
Subcodes	Lenze setting	Info	
C02305/1	100 %	LS_WriteParamList : c2853_s1_val1	
C02305/2	100 %	LS_WriteParamList : c2853_s1_val2	
C02305/3	100 %	LS_WriteParamList : c2853_s1_val3	
C02305/4	100 %	LS_WriteParamList : c2853_s1_val4	
C02305/5	100 %	LS_WriteParamList : c2853_s2_val1	
C02305/6	100 %	LS_WriteParamList : c2853_s2_val2	
C02305/7	100 %	LS_WriteParamList : c2853_s2_val3	
C02305/8	100 %	LS_WriteParamList : c2853_s2_val4	
C02305/9	100 %	LS_WriteParamList : c2853_s3_val1	
C02305/10	100 %	LS_WriteParamList : c2853_s3_val2	
C02305/11	100 %	LS_WriteParamList : c2853_s3_val3	
C02305/12	100 %	LS_WriteParamList : c2853_s3_val4	
C02305/13	100 %	LS_WriteParamList : c2853_s4_val1	
C02305/14	100 %	LS_WriteParamList : c2853_s4_val2	
C02305/15	100 %	LS_WriteParamList : c2853_s4_val3	
C02305/16	100 %	LS_WriteParamList : c2853_s4_val4	
C02305/17	100 %	LS_WriteParamList : c2853_s5_val1	
C02305/18	100 %	LS_WriteParamList : c2853_s5_val2	
C02305/19	100 %	LS_WriteParamList : c2853_s5_val3	
C02305/20	100 %	LS_WriteParamList : c2853_s5_val4	
C02305/21	100 %	LS_WriteParamList : c2853_s6_val1	
C02305/22	100 %	LS_WriteParamList : c2853_s6_val2	
C02305/23	100 %	LS_WriteParamList : c2853_s6_val3	
C02305/24	100 %	LS_WriteParamList : c2853_s6_val4	
C02305/25	100 %	LS_WriteParamList : c2853_s7_val1	
C02305/26	100 %	LS_WriteParamList : c2853_s7_val2	

Parameter Name:		Data type: UNSIGNED 8 Index: 22270 _d = 56FE _h
C02305 LS_WriteParamList: PSM: Ppp saturation characteristic		
C02305/27	100 %	LS_WriteParamList: c2853_s7_val3
C02305/28	100 %	LS_WriteParamList: c2853_s7_val4
C02305/29	100 %	LS_WriteParamList: c2853_s8_val1
C02305/30	100 %	LS_WriteParamList: c2853_s8_val2
C02305/31	100 %	LS_WriteParamList: c2853_s8_val3
C02305/32	100 %	LS_WriteParamList: c2853_s8_val4
C02305/33	100 %	LS_WriteParamList: c2853_s9_val1
C02305/34	100 %	LS_WriteParamList: c2853_s9_val2
C02305/35	100 %	LS_WriteParamList: c2853_s9_val3
C02305/36	100 %	LS_WriteParamList: c2853_s9_val4
C02305/37	100 %	LS_WriteParamList: c2853_s10_val1
C02305/38	100 %	LS_WriteParamList: c2853_s10_val2
C02305/39	100 %	LS_WriteParamList: c2853_s10_val3
C02305/40	100 %	LS_WriteParamList: c2853_s10_val4
C02305/41	100 %	LS_WriteParamList: c2853_s11_val1
C02305/42	100 %	LS_WriteParamList: c2853_s11_val2
C02305/43	100 %	LS_WriteParamList: c2853_s11_val3
C02305/44	100 %	LS_WriteParamList: c2853_s11_val4
C02305/45	100 %	LS_WriteParamList: c2853_s12_val1
C02305/46	100 %	LS_WriteParamList: c2853_s12_val2
C02305/47	100 %	LS_WriteParamList: c2853_s12_val3
C02305/48	100 %	LS_WriteParamList: c2853_s12_val4
C02305/49	100 %	LS_WriteParamList: c2853_s13_val1
C02305/50	100 %	LS_WriteParamList: c2853_s13_val2
C02305/51	100 %	LS_WriteParamList: c2853_s13_val3
C02305/52	100 %	LS_WriteParamList: c2853_s13_val4
C02305/53	100 %	LS_WriteParamList: c2853_s14_val1
C02305/54	100 %	LS_WriteParamList: c2853_s14_val2
C02305/55	100 %	LS_WriteParamList: c2853_s14_val3
C02305/56	100 %	LS_WriteParamList: c2853_s14_val4
C02305/57	100 %	LS_WriteParamList: c2853_s15_val1
C02305/58	100 %	LS_WriteParamList: c2853_s15_val2
C02305/59	100 %	LS_WriteParamList: c2853_s15_val3
C02305/60	100 %	LS_WriteParamList: c2853_s15_val4
C02305/61	100 %	LS_WriteParamList: c2853_s16_val1
C02305/62	100 %	LS_WriteParamList: c2853_s16_val2
C02305/63	100 %	LS_WriteParamList: c2853_s16_val3
C02305/64	100 %	LS_WriteParamList: c2853_s16_val4
C02305/65	100 %	LS_WriteParamList: c2853_s17_val1
C02305/66	100 %	LS_WriteParamList: c2853_s17_val2
C02305/67	100 %	LS_WriteParamList: c2853_s17_val3
C02305/68	100 %	LS_WriteParamList: c2853_s17_val4
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C02306

Parameter Name:		Data type: UNSIGNED_16	
C02306 LS_WriteParamList: PSM: Imax Ppp saturation characteristic		Index: 22269 _d = 56FD _h	
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Setting range (min. value unit max. value)			
0.0	A	3000.0	
Subcodes	Lenze setting	Info	
C02306/1	3000.0 A	LS_WriteParamList : c2855_val1	
C02306/2	3000.0 A	LS_WriteParamList : c2855_val2	
C02306/3	3000.0 A	LS_WriteParamList : c2855_val3	
C02306/4	3000.0 A	LS_WriteParamList : c2855_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10			

C02307

Parameter Name:		Data type: UNSIGNED_8 Index: 22268 _d = 56F _{Ch}	
C02307 LS_WriteParamList: PSM: Activate Ppp saturation char.			
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Selection list			
0	Off		
1	On		
Subcodes	Lenze setting	Info	
C02307/1	0: Off	LS_WriteParamList : c2859_val1	
C02307/2	0: Off	LS_WriteParamList : c2859_val	
C02307/3	0: Off	LS_WriteParamList : c2859_val	
C02307/4	0: Off	LS_WriteParamList : c2859_val	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C02311

Parameter Name:			Data type: INTEGER_8 Index: 22264 _d = 56F8 _h
C02311 LS_WriteParamList: PLI without motion: Adaptation of time duration			
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Setting range (min. value unit max. value)			
-10		10	
Subcodes	Lenze setting	Info	
C02311/1	0	LS_WriteParamList : c2872_s1_val1	
C02311/2	0	LS_WriteParamList : c2872_s1_val2	
C02311/3	0	LS_WriteParamList : c2872_s1_val3	
C02311/4	0	LS_WriteParamList : c2872_s1_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C02312

Parameter | Name:

C02312 | LS_WriteParamList: PLI without motion

Data type: UNSIGNED_16

Index: 22263_d = 56F7_h

From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional [motor data change-over](#)

Setting range (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		
Bit 0	for SLPSM with controller enable	
Bit 1	for SC PSM with mains on	
Bit 2	for SC PSM with controller enable	
Bit 3	for SC PSM once after fault reset	
Bit 4	Reserved	
Bit 5	Reserved	
Bit 6	Reserved	
Bit 7	Reserved	
Bit 8	Reserved	
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	Reserved	
Bit 15	Reserved	
Subcodes	Lenze setting	Info
C02312/1	0x0001	LS_WriteParamList : c2874_s1_val1
C02312/2	0x0001	LS_WriteParamList : c2874_s1_val2
C02312/3	0x0001	LS_WriteParamList : c2874_s1_val3
C02312/4	0x0001	LS_WriteParamList : c2874_s1_val4

☒ Read access
 ☒ Write access
 ☐ CINH
 ☐ PLC STOP
 ☐ No transfer
 ☐ COM
 ☒ MOT

C02313

Parameter Name: C02313 LS_WriteParamList: PLI without motion: Adaptation of ident angle			Data type: INTEGER_8 Index: 22262 _d = 56F6 _h
From version 12.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over			
Setting range (min. value unit max. value)			
-100	°	100	
Subcodes	Lenze setting	Info	
C02313/1	0 °	LS_WriteParamList : c2875_s1_val1	
C02313/2	0 °	LS_WriteParamList : c2875_s1_val2	
C02313/3	0 °	LS_WriteParamList : c2875_s1_val3	
C02313/4	0 °	LS_WriteParamList : c2875_s1_val4	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C02314

Parameter Name: C02314 Reserved	Data type: UNSIGNED_8 Index: 22261 _d = 56F5 _h
This code is for device-internal use only and must not be written to by the user!	

C02315

Parameter Name:		Data type: UNSIGNED_8 Index: 22260 _d = 56F4 _h
C02315 LS_WriteParamList: Manual entry of motor type		
From version 14.00.00 onwards: Parameter values (1st value ... 4th value) for optional motor data change-over		
Selection list		
0	Automatic	
1	ASM	
2	PSM	
Subcodes	Lenze setting	Info
C02315/1	0: Automatic	LS_WriteParamList : c1001_s1_val1
C02315/2	0: Automatic	LS_WriteParamList : c1001_s1_val2
C02315/3	0: Automatic	LS_WriteParamList : c1001_s1_val3
C02315/4	0: Automatic	LS_WriteParamList : c1001_s1_val4
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C02430

Parameter Name: C02430 Axis bus address and no. of nodes		Data type: UNSIGNED_8 Index: 22145 _d = 5681 _h	
From version 02.00.00			
<div>► Data transfer axis bus</div>			
Setting range (min. value unit max. value)			
0			
Subcodes	Lenze setting	Info	
C02430/1	0	Axis bus address <ul style="list-style-type: none">• 0 ≡ Node is disconnected from the axis bus• 1 ≡ Master• 2 ... 62 ≡ slave 1 ... slave 61	
C02430/2	2	Axis bus no. of nodes <ul style="list-style-type: none">• Number of slaves connected to the axis bus.• Setting only required for the master.	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1</div>			

C02431

Parameter Name: C02431 Axis bus time settings			Data type: UNSIGNED_16 Index: 22144 _d = 5680 _h		
From version 02.00.00					
▶ Data transfer axis bus					
Setting range (min. value unit max. value)					
0	ms	65000			
Subcodes	Lenze setting	Info			
C02431/1	3000 ms	Axis bus decel. boot-up • Delay during status change from "Boot-up" to "Operational".			
C02431/2	1000 ms	Axis bus decel. BusOff recovery • Delay after which the "BusOff" status is reset automatically. ▶ Data error monitoring.			
C02431/3	1000 ms	Axis bus monitoring time ▶ Data error monitoring.			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C02435

Parameter Name: C02435 Axis bus status		Data type: UNSIGNED_8 Index: 22140 _d = 567C _h	
From version 02.00.00			
		Data transfer axis bus	
Selection list (read only)			
0	PDO active		
1	SDO active		
2	Reserved		
3	Reserved		
4	BootUp		
5	Stopped		
6	Reserved		
7	Off		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C02436

Parameter Name: C02436 Axis bus error status		Data type: UNSIGNED_8 Index: 22139 _d = 567B _h	
From version 02.00.00			
<div>► Data transfer axis bus</div>			
Selection list (read only)			
0	No Error		
1	Warning ErrActive		
2	Warning ErrPassive		
3	Bus off		
4	Reserved		
5	Reserved		
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1</div>			

C02437

Parameter Name: C02437 Axis bus MessageError		Data type: UNSIGNED_8 Index: 22138 _d = 567A _h	
From version 02.00.00			
		Data transfer axis bus	
Selection list (read only)			
0	No Error		
1	StuffError		
2	FormError		
3	AckError		
4	Bit1Error		
5	Bit0Error		
6	CRCErrror		
7	Reserved		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C02438

Parameter Name: C02438 CAB_Tx_Rx_diagnosis			Data type: UNSIGNED_16 Index: 22137 _d = 5679 _h				
From version 12.00.00						▶ Data transfer axis bus	
Display range (min. value unit max. value)							
0							
Subcodes				Info			
C02438/1				Axis bus Tx_Error			
C02438/2				Axis bus Rx_Error			
C02438/3				Axis bus transmitting meter			
C02438/4				Axis bus receiving meter			
<input checked="" type="checkbox"/> Read access						<input type="checkbox"/> Write access	
<input type="checkbox"/> CINH						<input type="checkbox"/> PLC STOP	
<input checked="" type="checkbox"/> No transfer						<input checked="" type="checkbox"/> COM	
<input type="checkbox"/> MOT						Scaling factor: 1	

C02440

Parameter Name: C02440 AxisBusIO slave/master		Data type: UNSIGNED_8 Index: 22135 _d = 5677 _h	
From version 02.00.00			
Selection list		Axis bus	
0	Off		
1	Master		
2	Slave		
3	IO		
Subcodes	Lenze setting	Info	
C02440/1	0: Off	Axis bus IO function	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input checked="" type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C02442

Parameter Name: C02442 CAB decoupling inputs		Data type: UNSIGNED_16 Index: 22133 _d = 5675 _h
From version 12.00.00		
Bit-coded selection of the events causing the decoupling of the receive data of the data transfer axis bus. ► Data transfer axis bus		
Setting range (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		
Bit 0	BusOff_MsgErr	
Bit 1	Warning	
Bit 2	NodeStopped	
Bit 3	Reserved	
Bit 4	Reserved	
Bit 5	Reserved	
Bit 6	Reserved	
Bit 7	Reserved	
Bit 8	Reserved	
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	Trouble	
Bit 15	Fault	
Subcodes	Lenze setting	Info
C02442/1	0x0000	Decoupling inputs from the axis bus
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C02443

Parameter | Name: C02443 | CAB decoupling value

Data type: UNSIGNED_16
Index: 22132_d = 5674_h

From version 12.00.00

Definition of the value the receive data of the data transfer axis bus are to have in the decoupled state.

► [Data transfer axis bus](#)

Setting range (min. value unit max. value)		
0		65535
Subcodes	Lenze setting	Info
C02443/1	0	LS_AxisBusIn : wLine1 DiscVal
C02443/2	0	LS_AxisBusIn : wLine2 DiscVal
C02443/3	0	LS_AxisBusIn : wLine3 DiscVal
C02443/4	0	LS_AxisBusIn : wCas1 DiscVal
C02443/5	0	LS_AxisBusIn : wCas2 DiscVal
C02443/6	0	LS_AxisBusIn : wCas3 DiscVal
C02443/7	0	LS_AxisBusIn : wCas4 DiscVal
C02443/8	0	LS_AxisBusAux : wAuxIn1 DiscVal
C02443/9	0	LS_AxisBusAux : wAuxIn2 DiscVal
C02443/10	0	LS_AxisBusAux : wAuxIn3 DiscVal
C02443/11	0	LS_AxisBusAux : wAuxIn4 DiscVal

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT Scaling factor: 1

C02444

Parameter | Name: C02444 | CAB configuration

Data type: UNSIGNED_16
Index: 22131_d = 5673_h

From version 12.00.00

Bit-coded settings

► [Data transfer axis bus](#)

Setting range (min. hex value max. hex value)		
0x0000	0xFFFF	
Value is bit-coded:		Info
Bit 0	Edge detection SetFail	0 ≡ input <i>bSetFail_DigOut</i> is level-sensitive. 1 ≡ input <i>bSetFail_DigOut</i> is edge-sensitive.
Bit 1	Reserved	
Bit 2	Reserved	
Bit 3	Reserved	
Bit 4	Reserved	
Bit 5	Reserved	
Bit 6	Reserved	
Bit 7	Reserved	
Bit 8	Reserved	
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	same Cobld for all Cas	
Bit 15	500 kbps	
Subcodes	Lenze setting	Info
C02444/1	0x0000	Axis bus configuration

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT

C02580

Parameter | Name:

C02580 | Holding brake: Operating mode

Data type: UNSIGNED_8

Index: 21995_d = 55EB_h

Selection of the operating mode for holding brake control

▸ [Holding brake control](#)

Selection list (Lenze setting printed in bold)		Info
0	Brake control off	No holding brake is used. Internal control is switched off.
11	Manually controlled	The holding brake is released and closed via a control bit in the MCK control word.
12	Autom. controlled	The holding brake is automatically released and closed via speed setpoint comparisons.
13	Semi-automat. controlled	The holding brake is released and closed via a control bit in the MCK control word. <ul style="list-style-type: none">• In contrast to the manual operation (mode 11)• the feedforward control is active in this mode, preventing a sagging e.g. in case of a hoist.• the brake in this mode also closes when the controller is inhibited in order to prevent the axis in a hoist from falling.

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT Scaling factor: 1

C02581

Parameter Name: C02581 Holding brake: Speed thresholds			Data type: INTEGER_16 Index: 21994 _d = 55EA _h
Speed setpoint threshold and hysteresis for automatic holding brake control			
Setting range (min. value unit max. value)			▶ Holding brake control
-199.99	%	199.99	
Subcodes	Lenze setting	Info	
C02581/1	5.00 %	Holding brake: Switching threshold <ul style="list-style-type: none">Switching threshold of the speed setpoint from which on the holding brake is released/applied automatically.	
C02581/2	1.00 %	Holding brake: Hyst.release <ul style="list-style-type: none">Hysteresis for holding brake release.Release threshold = switching threshold + release hysteresis	
C02581/3	1.00 %	Holding brake: Hyst. close <ul style="list-style-type: none">Hysteresis for holding brake application.Application threshold = switching threshold - application hysteresis	
C02581/4	0.00 %	Holding brake: FF control starting value 1	
C02581/5	0.00 %	Holding brake: FF control starting value 2	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100			

C02582

Parameter | Name:

C02582 | Holding brake: Setting

Data type: UNSIGNED_8

Index: 21993_d = 55E9_h

Activation of functional holding brake control options

Holding brake control

Setting range (min. hex value max. hex value)		Lenze setting
0x00		0xFF
0x40 (decimal: 64)		
Value is bit-coded: (☑ = bit set)		Info
Bit 0 ☐	bMBrakeReleaseOut invert.	Activation of inverted control <ul style="list-style-type: none">1 ≡ Inverted logic of the control signal for the holding brake control switching element.
Bit 1 ☐	Horizontal brake protection	Brake response in case of pulse inhibit <ul style="list-style-type: none">1 ≡ In the case of a pulse inhibit, the actual speed value is monitored which must reach the "Close" threshold value to cause the holding brake to be applied. Note: <ul style="list-style-type: none">This function is only active if bit 3 (horizontal/winding technology) is set as well. The function is used in order that, when the controller is inhibited, the holding brake of a drive with horizontal traverse path does not wear out during rotation.With vertical motion (bit 3 = 0), this function is not active. Especially with hoists and activated pulse inhibit of the controller, an immediate application of the brake is essential for safety-related reasons!
Bit 2 ☐	with hoist inv. feedfwd. control	Direction of feedforward control with vertical/hoist technology: <ul style="list-style-type: none">0 ≡ Positive direction1 ≡ Negative direction Note: Reversal (Ccw) is then considered.
Bit 3 ☐	Horizontal application	Direction of movement of the axis <ul style="list-style-type: none">0 ≡ The axis performs vertical movements. Gravitational acceleration causes movements.1 ≡ The direction of the axis is horizontal or rotary. The gravitational acceleration does not cause any movement.
Bit 4 ☐	Feedforward control C2581	Selection of the feedforward control value <ul style="list-style-type: none">0 ≡ Automatic selection.The torque saved at the last stop is used.1 ≡ Manual selection.bMBrakeStartValue2 = FALSE: The feedforward control value 1 set in C02581/4 is used.bMBrakeStartValue2 = TRUE: The feedforward control value set in C02581/5 is used.
Bit 5 ☐	Feedback monitoring	Activation of status monitoring <ul style="list-style-type: none">1 ≡ The bMBrakeApplied input for status detection of the brake (via a switching contact at the brake) is monitored after the waiting time set in C02589/3 has expired.

Parameter Name: C02582 Holding brake: Setting		Data type: UNSIGNED_8 Index: 21993 _d = 55E9 _h
Bit 6 <input checked="" type="checkbox"/>	SyncRampe L_NSet_1	<p>From version 02.00.00</p> <p>Selection of the ramp time for the synchronisation process to setpoint speed after the brake opening time has elapsed</p> <p>Revised behaviour from version 02.00.00:</p> <ul style="list-style-type: none"> • 1 ≡ The ramp time of the effective acceleration of the ramp function generator (L_NSet_1) is used (Lenze setting). • 0 ≡ As before, the ramp time set in C02610/1 is used. <p>Note:</p> <p>The changeover can be dynamically both via the ramp parameter and via bit 6.</p>
Bit 7 <input type="checkbox"/>	Reserved	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT		

C02589

Parameter Name: C02589 Holding brake: Time system		Data type: UNSIGNED_16 Index: 21986 _d = 55E2 _h
<p>Operating times of the holding brake</p> <ul style="list-style-type: none"> • The electromechanical delay times of the holding brake are specified in the data sheets or on the holding brake nameplate. <p style="text-align: right;">▶ Holding brake control</p>		
Setting range (min. value unit max. value)		
0	ms	60000
Subcodes	Lenze setting	Info
C02589/1	100 ms	<p>Holding brake: Application time</p> <ul style="list-style-type: none"> • Time in which the holding brake is completely applied from the beginning of control and in which the controller is inhibited.
C02589/2	100 ms	<p>Holding brake: Release time</p> <ul style="list-style-type: none"> • Time in which the holding brake is completely released from the beginning of control.
C02589/3	100 ms	<p>Holding brake: Waiting time status</p> <ul style="list-style-type: none"> • Time after which all transient reactions are completed and the switching status of the holding brake is stable. Beginning of monitoring the feedback signal for the switching status of the holding brake.
C02589/4	0 ms	Holding brake: Ramp time FF ctrl
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1		

C02593

Parameter | Name:

C02593 | Holding brake: Activation time

Data type: UNSIGNED_32

Index: 21982_d = 55DE_h

Time parameter for the delay of trigger signals of the holding brake control

▶ [Holding brake control](#)

Setting range (min. value unit max. value)			
0.000	s	3600.000	
Subcodes	Lenze setting	Info	
C02593/1	0.000 s	Holding brake: Actual value monitoring <ul style="list-style-type: none"> • Time in which the actual value is supposed to reach the threshold for closing the brake if the setpoint has already reached the threshold. • Time > 0 s: If the actual speed value has not reached the threshold within the time for brake application, the holding brake is applied by control. • Time = 0 s: The brake is only applied by control when the actual speed has reached the application threshold. 	
C02593/2	0.000 s	Holding brake: Application delay <ul style="list-style-type: none"> • Time by which the control process for holding brake application is delayed. The time expires when the speed setpoint has reached the switching threshold for application. • With positioning processes, a continuous application and release of the holding brake can thus be suppressed for the set time. 	
C02593/3	0.000 s	Holding brake: Reserved	
C02593/4	0.000 s	Holding brake: Reserved	

☒ Read access
 ☒ Write access
 ☐ CINH
 ☐ PLC STOP
 ☐ No transfer
 ☐ COM
 ☐ MOT
 Scaling factor: 1000

C02607

Parameter | Name: **C02607 | Holding brake: Status**

Data type: UNSIGNED_16
Index: 21968_d = 55D0_h

Switching status of the holding brake control

▶ [Holding brake control](#)

Display area (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		Info
Bit 0	Brake applied	1 ≡ Holding brake is completely closed
Bit 1	Brake released	1 ≡ Holding brake is completely released
Bit 2	Feedforward control active	1 ≡ Feedforward control for holding of the load via the motor is active before the holding brake releases.
Bit 3	Closing active	1 ≡ The brake closing time (C02589/1) expires
Bit 4	Forced release active	1 ≡ In case of automatic operation of the holding brake control, the brake is directly released via the MCK input <i>bMBrakeRelease</i> = TRUE
Bit 5	Release active	1 ≡ The brake release time (C02589/2) expires
Bit 6	Setpoint synchronisation active	1 ≡ A speed setpoint at the MCK is approached along a defined ramp after brake release
Bit 7	Signalling contact error	1 ≡ The status monitoring has tripped
Bit 8	Reserved	
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	Reserved	
Bit 15	Reserved	

☒ Read access ☐ Write access ☐ CINH ☐ PLC STOP ☒ No transfer ☐ COM ☐ MOT

C02610

Parameter | Name: **C02610 | MCK: Accel./decel. times**

Data type: UNSIGNED_32
Index: 21965_d = 55CD_h

Ramp times for speed setpoint synchronisation

Setting range (min. value unit max. value)		
0.000	s	999.999
Subcodes	Lenze setting	Info
C02610/1	2.000 s	<p>Holding brake: ramp time synchr.</p> <ul style="list-style-type: none">• Ramp time for the synchronisation process to setpoint speed after the brake opening time has elapsed <p>Revised behaviour from version 02.00.00:</p> <ul style="list-style-type: none">• The setting made here is only effective if bit 6 "SyncRampe L_NSet_1" in C02582 is set to "0".• In the Lenze setting of C02582 (Bit 6 = "1"), the ramp time of the effective acceleration of the ramp function generator (L_NSet_1) is used. <p>► Holding brake control</p>
C02610/2	2.000 s	<p>MCK: Ramp time synchr. setpoint</p> <ul style="list-style-type: none">• Time for synchronisation ramps between setpoint jumps occurring through the exceedance of minimum and maximum speed setpoint limit ranges.
C02610/3	2.000 s	MCK: SM stopping ramp

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT Scaling factor: 1000

C02611

Parameter | Name:
C02611 | MCK: Limitations

Data type: INTEGER_16
Index: 21964_d = 55CC_h

Speed setpoint limits for the determination of limited validity ranges

Note:
Traversing with setpoints through resulting blocking zones is executed with the ramp set in [C02610/2](#).
▶ [Speed Min/Max](#)

Setting range (min. value unit max. value)			
0.00	%	199.99	
Subcodes	Lenze setting	Info	
C02611/1	199.99 %	MCK: Pos. max. speed • Upper limit of the speed setpoint limitation in positive direction of rotation.	
C02611/2	0.00 %	MCK: Pos. min. speed • Lower limit of the speed setpoint limitation in positive direction of rotation.	
C02611/3	0.00 %	MCK: Neg. min. speed • Lower limit of the speed setpoint limitation in negative direction of rotation.	
C02611/4	199.99 %	MCK: Neg. max. speed • Upper limit of the speed setpoint limitation in negative direction of rotation.	
C02611/5	0.50 %	MCK: Max. speed • From version 12.00.00 • Maximum value for transferring the current speed to the speed setpoint when the internal operating mode " StandBy " is exited.	

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT Scaling factor: 100

C02652

Parameter Name: C02652 Settings of measuring system			Data type: UNSIGNED_16 Index: 21923 _d = 55A3 _h
From version 02.00.00			
Setting range (min. hex value max. hex value)			Lenze setting
0x0000		0xFFFF	0x0000 (decimal: 0)
Value is bit-coded: (☑ = bit set)			Info
Bit 0 ☐	Actual MCTRL position received at mains switch-off	► Actual "MCTRL position received at mains switch-off"	
Bit 1 ☐	Delete reference when machine data is changed	From version 12.00.00 ► Status bit "HomPosAvailable"	
Bit 2 ☐	Adapting "LS_MultiEncoder: Offset" to home position		
Bit 3 ☐	Reference reconstruction after encoder error removal		
Bit 4 ☐	Reserved		
Bit 5 ☐	Reserved		
Bit 6 ☐	Reserved		
Bit 7 ☐	Reserved		
Bit 8 ☐	Reserved		
Bit 9 ☐	Reserved		
Bit 10 ☐	Reserved		
Bit 11 ☐	Reserved		
Bit 12 ☐	Reserved		
Bit 13 ☐	Reserved		
Bit 14 ☐	Reserved		
Bit 15 ☐	Reserved		
☑ Read access ☑ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT			

C02810

Parameter Name: C02810 TP: Edge selection			Data type: UNSIGNED_8 Index: 21765 _d = 5505 _h
			► Touch-probe detection
Selection list			
0	Off		
1	Rising		
2	Falling		
3	Rising and falling		
Subcodes	Lenze setting	Info	
C02810/1	0: Off	Reserved	
C02810/2	0: Off	Reserved	
C02810/3	0: Off	TPDigIn3: Edge selection	
C02810/4	0: Off	TPDigIn4: Edge selection	
C02810/5	0: Off	TPDigIn5: Edge selection	
C02810/6	0: Off	TPDigIn6: Edge selection	
C02810/7	0: Off	TPDigIn7: Edge selection	
C02810/8	0: Off	TPEncoderZtrack: Edge selection • From version 12.00.00	
C02810/9	0: Off	TPResolverZtrack: Edge selection • From version 12.00.00	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C02811

Parameter Name: C02811 TP: Sensor delay			Data type: UNSIGNED_16 Index: 21764 _d = 5504 _h
			► Touch-probe detection
Setting range (min. value unit max. value)			
0	µs	6999	
Subcodes	Lenze setting	Info	
C02811/1	0 µs	Reserved	
C02811/2	0 µs	Reserved	
C02811/3	0 µs	TPDigIn3: Sensor delay	
C02811/4	0 µs	TPDigIn4: Sensor delay	
C02811/5	0 µs	TPDigIn5: Sensor delay	
C02811/6	0 µs	TPDigIn6: Sensor delay	
C02811/7	0 µs	TPDigIn7: Sensor delay	
C02811/8	0 µs	TPEncoderZTrack: Sensor delay • From version 12.00.00	
C02811/9	0 µs	TPResolverZTrack: Sensor delay • From version 12.00.00	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1			

C02812

Parameter | Name:
C02812 | TP: Position offset

Data type: INTEGER_32
Index: 21763_d = 5503_h

▶ [Touch-probe detection](#)

Setting range (min. value unit max. value)			
-214748.3647	units	214748.3647	
Subcodes	Lenze setting	Info	
C02812/1	0.0000 units	Reserved	
C02812/2	0.0000 units	Reserved	
C02812/3	0.0000 units	TPDigIn3: Pos offset	
C02812/4	0.0000 units	TPDigIn4: Pos offset	
C02812/5	0.0000 units	TPDigIn5: Pos offset	
C02812/6	0.0000 units	TPDigIn6: Pos offset	
C02812/7	0.0000 units	TPDigIn7: Pos offset	
C02812/8	0.0000 units	TPEncoderZTrack: Pos offset • From version 12.00.00	
C02812/9	0.0000 units	TPResolverZTrack: Pos offset • From version 12.00.00	

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT Scaling factor: 10000

C02813

Parameter Name: C02813 TP: Pos. window start			Data type: INTEGER_32 Index: 21762 _d = 5502 _h		
<div>▶ Touch-probe detection</div>					
Setting range (min. value unit max. value)					
-214748.3647	units	214748.3647			
Subcodes	Lenze setting		Info		
C02813/1	-214748.3647 units		TPDigIn3: Window start		
C02813/2	-214748.3647 units		TPDigIn4: Window start		
C02813/3	-214748.3647 units		TPDigIn5: Window start		
C02813/4	-214748.3647 units		TPEncoderZTrack: Window start • From version 12.00.00		
C02813/5	-214748.3647 units		TPResolverZTrack: Window start • From version 12.00.00		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 10000</div></div>					

C02814

Parameter Name: C02814 TP: Pos. window end			Data type: INTEGER_32 Index: 21761 _d = 5501 _h		
<div>▶ Touch-probe detection</div>					
Setting range (min. value unit max. value)					
-214748.3647	units	214748.3647			
Subcodes	Lenze setting	Info			
C02814/1	214748.3647 units	TPDigIn3: Window end			
C02814/2	214748.3647 units	TPDigIn4: Window end			
C02814/3	214748.3647 units	TPDigIn5: Window end			
C02814/4	214748.3647 units	TPEncoderZTrack: Window end • From version 12.00.00			
C02814/5	214748.3647 units	TPResolverZTrack: Window end • From version 12.00.00			
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 10000</div></div>					

C02815

Parameter | Name:
C02815 | TP: Position source

Data type: UNSIGNED_8
Index: 21760_d = 5500_h

▶ [Touch-probe detection](#)

Selection list		
0	Position encoder actual value	
1	Pos DigIn1/2	
2	Pos resolver	
3	Pos MultiEncoder	
Subcodes	Lenze setting	Info
C02815/1	0: Position encoder actual value	Reserved
C02815/2	0: Position encoder actual value	Reserved
C02815/3	0: Position encoder actual value	TPDigIn3: Position source
C02815/4	0: Position encoder actual value	TPDigIn4: Position source
C02815/5	0: Position encoder actual value	TPDigIn5: Position source
C02815/6	0: Position encoder actual value	TPDigIn6: Position source
C02815/7	0: Position encoder actual value	TPDigIn7: Position source
C02815/8	0: Position encoder actual value	TPEncoderZTrack: Position source • From version 12.00.00
C02815/9	0: Position encoder actual value	TPResolverZTrack: Position source • From version 12.00.00

☒ Read access ☒ Write access ☐ CINH ☐ PLC STOP ☐ No transfer ☐ COM ☐ MOT Scaling factor: 1

C02816

Parameter | Name: C02816 | TP: Signal counter

Data type: UNSIGNED_16
Index: 21759_d = 54FF_h

▶ [Touch-probe detection](#)

Display range (min. value unit max. value)		
0		65535
Subcodes		
C02816/1		
C02816/2		
C02816/3		
C02816/4		
C02816/5		
C02816/6		
C02816/7		
C02816/8		
C02816/9		

Info

Reserved

Reserved

TPDigIn3: Signal counter

TPDigIn4: Signal counter

TPDigIn5: Signal counter

TPDigIn6: Signal counter

TPDigIn7: Signal counter

TPEncoderZTrack: Signal counter

- From version 12.00.00

TPResolverZTrack: Signal counter

- From version 12.00.00

☒ Read access ☐ Write access ☐ CINH ☐ PLC STOP ☒ No transfer ☐ COM ☐ MOT Scaling factor: 1

C02817

Parameter Name: C02817 TP: TouchProbe position			Data type: INTEGER_32 Index: 21758 _d = 54FE _h		
<div>▶ Touch-probe detection</div>					
Display range (min. value unit max. value)					
-214748.3647	units	214748.3647			
Subcodes			Info		
C02817/1			Reserved		
C02817/2			Reserved		
C02817/3			TPDigIn3: TP position		
C02817/4			TPDigIn4: TP position		
C02817/5			TPDigIn5: TP position		
C02817/6			TPDigIn6: TP position		
C02817/7			TPDigIn7: TP position		
C02817/8			TPEncoderZTrack: TP position • From version 12.00.00		
C02817/9			TPResolverZTrack: TP position • From version 12.00.00		
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 10000</div></div>					

C02830

Parameter Name: C02830 DIx: Debounce time		Data type: UNSIGNED_8 Index: 21745 _d = 54F1 _h
Debounce times for the digital inputs		
<div>▸ Digital input terminals</div>		
Selection list		
0	0.00 ms	
1	0.25 ms	
2	0.50 ms	
3	0.75 ms	
4	1.00 ms	
5	1.25 ms	
6	1.50 ms	
7	1.75 ms	
8	2.00 ms	
10	2.50 ms	
12	3.00 ms	
14	3.50 ms	
16	4.00 ms	
18	4.50 ms	
20	5.00 ms	
22	5.50 ms	
24	6.00 ms	
28	7.00 ms	
32	8.00 ms	
36	9.00 ms	
40	10.0 ms	
44	11.0 ms	
48	12.0 ms	
52	13.0 ms	
56	14.0 ms	
64	16.0 ms	
72	18.0 ms	
80	20.0 ms	
88	22.0 ms	
96	24.0 ms	
104	26.0 ms	
112	28.0 ms	
120	30.0 ms	
128	32.0 ms	
Subcodes	Lenze setting	Info
C02830/1	1: 0.25 ms	DI1 ... DI7: Debounce time
C02830/...		
C02830/7		
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>		

C02840

Parameter Name: C02840 CountInx: Parameter			Data type: UNSIGNED_32 Index: 21735 _d = 54E7 _h		
Starting and comparison values for digital count inputs					
▶ Use DI1(6) as counting input					
Setting range (min. value unit max. value)					
0	Incr.	2147483647			
Subcodes	Lenze setting		Info		
C02840/1	0 incr.		CountIn1: Starting value		
C02840/2	65535 incr.		CountIn1: Comparison value		
C02840/3	0 incr.		CountIn6: Starting value		
C02840/4	65535 incr.		CountIn6: Comparison value		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C02841

Parameter Name: C02841 CountInx: Counter content			Data type: UNSIGNED_32 Index: 21734 _d = 54E6 _h		
Display of the current counter content of the digital count inputs					
▶ Use DI1(6) as counting input					
Display range (min. value unit max. value)					
0	Incr.	2147483647			
Subcodes			Info		
C02841/1			CountIn1: Counter content		
C02841/2			CountIn6: Counter content		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input checked="" type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C02842

Parameter Name: C02842 FreqInxx: Offset			Data type: INTEGER_16 Index: 21733 _d = 54E5 _h		
Offset for digital frequency inputs					
▶ Using DI1(6) and DI2(7) as frequency inputs					
Setting range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes	Lenze setting		Info		
C02842/1	0.00 %		FreqIn12: Offset		
C02842/2	0.00 %		FreqIn67: Offset		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C02843

Parameter Name: C02843 FreqInxx: Gain			Data type: INTEGER_16 Index: 21732 _d = 54E4 _h		
Gain for digital frequency inputs					
▶ Using DI1(6) and DI2(7) as frequency inputs					
Setting range (min. value unit max. value)					
-199.99	%	199.99			
Subcodes	Lenze setting	Info			
C02843/1	100.00 %	FreqIn12: Gain			
C02843/2	100.00 %	FreqIn67: Gain			
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C02844

Parameter Name: C02844 FreqIn12: Function			Data type: UNSIGNED_8 Index: 21731 _d = 54E3 _h		
► Output of the encoder position of the DI1/DI2 frequency input					
Selection list					
0	Loading with level				
1	Loading with edge				
2	Loading with level + reset				
Subcodes		Lenze setting	Info		
C02844/1		0: Loading with level	FreqIn12: PosIn function		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <input type="checkbox"/> Scaling factor: 1					

C02845

Parameter Name: C02845 FreqIn12: PosIn comparison value			Data type: INTEGER_32 Index: 21730 _d = 54E2 _h		
► Output of the encoder position of the DI1/DI2 frequency input					
Setting range (min. value unit max. value)			Lenze setting		
0	Incr.	2147418112	0 incr.		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 1					

C02853

Parameter Name: C02853 PSM: Lss saturation characteristic			Data type: UNSIGNED_8 Index: 21722 _d = 54DA _h		
► Current-dependent stator leakage inductance Lss(l)					
Setting range (min. value unit max. value)					
0	%	255			
Subcodes	Lenze setting		Info		
C02853/1	100 %		PSM: Lss saturation characteristic		
C02853/2	100 %		PSM: Lss saturation characteristic		
C02853/3	100 %		PSM: Lss saturation characteristic		
C02853/4	100 %		PSM: Lss saturation characteristic		
C02853/5	100 %		PSM: Lss saturation characteristic		
C02853/6	100 %		PSM: Lss saturation characteristic		
C02853/7	100 %		PSM: Lss saturation characteristic		
C02853/8	100 %		PSM: Lss saturation characteristic		
C02853/9	100 %		PSM: Lss saturation characteristic		
C02853/10	100 %		PSM: Lss saturation characteristic		
C02853/11	100 %		PSM: Lss saturation characteristic		
C02853/12	100 %		PSM: Lss saturation characteristic		
C02853/13	100 %		PSM: Lss saturation characteristic		
C02853/14	100 %		PSM: Lss saturation characteristic		
C02853/15	100 %		PSM: Lss saturation characteristic		
C02853/16	100 %		PSM: Lss saturation characteristic		
C02853/17	100 %		PSM: Lss saturation characteristic		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C02855

Parameter Name: C02855 PSM: I_{max} Lss saturation characteristic			Data type: UNSIGNED_16 Index: 21720 _d = 54D8 _h		
▶ Current-dependent stator leakage inductance Lss(l)					
Setting range (min. value unit max. value)			Lenze setting		
0.0	A	3000.0	3000.0 A		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 10					

C02859

Parameter Name: C02859 PSM: Activate Lss saturation char.		Data type: UNSIGNED_8 Index: 21716 _d = 54D4 _h	
► Current-dependent stator leakage inductance Lss(l)			
Selection list (Lenze setting printed in bold)			
0	Off		
1	On		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C02862

Parameter Name: C02862 Resolver gain			Data type: UNSIGNED_16 Index: 21713 _d = 54D1 _h		
▶ Encoder/feedback system: Resolver					
Setting range (min. value unit max. value)					
0.00	%	199.99			
Subcodes	Lenze setting		Info		
C02862/1	100.00 %		Resolver: sine gain		
C02862/2	100.00 %		Resolver: cos gain		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02863

Parameter Name: C02863 Resolver: Phase error			Data type: INTEGER_16 Index: 21712 _d = 54D0 _h		
▶ Encoder/feedback system: Resolver					
Setting range (min. value unit max. value)			Lenze setting		
-199.99	%	199.99	0.00 %		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02864

Parameter | Name:

C02864 | MCTRL: Optimisations

Data type: UNSIGNED_16

Index: 21711_d = 54CF_h

From version 14.00.00

Activation of special functions of the internal motor control

Setting range (min. hex value max. hex value)			
0x0000		0xFFFF	
Value is bit-coded:			Info
Bit 0	Motor temp. 90° for operation without KTY		1 ≡ Warm machine. In case the temperature tracking is not active, a motor temperature of 90 °C is assumed. ▶ Temperature compensation within the motor control
Bit 1	No switch-off of the brake chopper after 4s		1 ≡ Limitation of the operating time of the brake chopper (brake transistor) is deactivated. ▶ Braking operation/brake energy management
Bit 2	Brake chopper off in case of trip		0 ≡ No response of the brake chopper in the "Fault" device status. 1 ≡ In the "Fault" device status, the brake chopper is permanently switched off without any delay. ▶ Braking operation/brake energy management
Bit 3	Reserved (do not change!)		
Bit 4	Motor ident: Switching frequency 8kHz		Switching frequency for motor parameter identification: 0 ≡ 4 kHz 1 ≡ 8 kHz ▶ Preventing a decrease of the switching frequency
Bit 5	Field/field weakening control in 500us		Cycle time for field weakening control: 0 ≡ 1 ms 1 ≡ 500 μs ▶ Optimising the behaviour of the asynchronous motor in the field weakening range

Parameter Name: C02864 MCTRL: Optimisations		Data type: UNSIGNED_16 Index: 21711 _d = 54CF _h
Bit 6	Motor ident.: No calculation C577 C578 C2864	<p>From version 15.00.00: Following successful motor parameter identification, the field weakening controller parameters for ASM servo control are calculated as well. If these parameters are not to be calculated, bit 6 must be set to "1".</p> <p>0 ≡ Calculate parameter 1 ≡ Do not calculate parameter</p> <p>► Automatic motor data identification</p>
Bit 7	If C2879 Bit1=0: C087 is warm	<p>From version 15.00.00, the too high slip with the activated option "Slip calculation from motor nameplate data" can be corrected for the ASM servo control by setting bit 7 to "1".</p> <p>1 ≡ Rated motor speed (C00087) is assumed for a warm machine.</p> <p>► Slip calculation for SC</p>
Bit 8	Suppress V/f emergency operation	<p>From version 15.00.00, it is internally switched to the encoderless V/f characteristic control in case of a motor control type with feedback and an encoder open circuit in order to avoid impermissible motor movements.</p> <ul style="list-style-type: none"> • Exception: There will be no change-over in case of servo control for synchronous motors (PSM). • In order that this "V/f emergency operation" works properly, the parameters relevant for the V/f characteristic control (base frequency, Vmin boost, slip compensation, etc.) have to be set correctly. As an alternative, a motor parameter identification can be executed as well. • The change-over to "V/f emergency operation" is reported via bit 4 in C01000 and via the <i>bWirebreakUfLinearActive</i> status signal at the SB LS DeviceMonitor. • The setting in C00006 is not affected by the change-over. <p>The "V/f emergency operation" can be suppressed by setting bit 8 to "1".</p> <p>0 ≡ V/f emergency operation in case of encoder open circuit 1 ≡ No V/f emergency operation in case of encoder open circuit</p>
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	Reserved	
Bit 15	Reserved	
Subcodes	Lenze setting	Info
C02864/1	0x0000	MCTRL: Optimisations
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT		

C02865

Parameter Name: C02865 MCTRL: Special settings		Data type: UNSIGNED_16 Index: 21710 _d = 54CE _h
From version 12.00.00 Activation of special functions of the internal motor control		
Setting range (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		Info
Bit 0	No TorqueLimit if TorquemodeOn	From version 12.00.00 onwards: If sensorless vector control (SLVC) or servo control (SC) are used, in the "torque control with speed limitation" mode the torque limitation via <i>nTorqueMotLimit_a</i> and <i>nTorqueGenLimit_a</i> is also active to limit the torque setpoint. If you want to deactivate the torque limitation to retain the former function, set bit 0 to "1". 0 ≡ Torque limitation is active 1 ≡ Torque limitation is not active
Bit 1	250ms IMP before DCB	
Bit 2	1000ms IMP before DCB	
Bit 3	DCB: Current controller and C036 app. to C088	
Bit 4	Motorident.: No calculation C73 C75 C76 C77 C78	From version 12.00.00 onwards: Following successful motor parameter identification, the current controller and field controller parameters are calculated as well. If these parameters are not to be calculated, bit 4 must be set to "1". 0 ≡ Calculate parameter 1 ≡ Do not calculate parameter ► Automatic motor data identification
Bit 5	Motorident.: Calculation C70 C71 C72	From version 12.00.00 onwards: Following successful motor parameter identification, the speed controller parameters can automatically be calculated as well. If these parameters are to be calculated, bit 5 must be set to "1". 0 ≡ Do not calculate parameter 1 ≡ Calculate parameter ► Automatic motor data identification
Bit 6	Motorident.: Calculation C11 C22 C497 C966 C982	From version 12.00.00 onwards: Following successful motor parameter identification, further controller parameters can be calculated automatically. If these parameters are to be calculated, bit 6 must be set to "1". 0 ≡ Do not calculate parameter 1 ≡ Calculate parameter ► Automatic motor data identification
Bit 7	Brake chopper off in case of pulse inhibit	From version 14.00.00 0 ≡ No response of the brake chopper in case of pulse inhibit. 1 ≡ In case of pulse inhibit, the brake chopper is permanently switched off without any delay. ► Braking operation/brake energy management
Bit 8	DC-bus supply with DC charging connection	

Parameter Name: C02865 MCTRL: Special settings		Data type: UNSIGNED_16 Index: 21710 _d = 54CE _h
Bit 9	Inverter characteristics inactive	From version 12.00.00 In case of very low-inductance motors (e.g. synchronous motor with a rated frequency of 1000 Hz) the inverter error characteristic needs to be switched off as otherwise the current of the device might be switched off. 0 ≡ Inverter error characteristic is active 1 ≡ Inverter error characteristic is not active
Bit 10	SCPSM: Extrapolation - actual speed value inactive	
Bit 11	TopLine: Speed encoder signal cycle 500us	
Bit 12	In case of QSP - nTorqueSetValue_a active	From version 13.00.00
Bit 13	In case of QSP - nTorquexxxLimit_a active	From version 13.00.00
Bit 14	Sensitivity of setpoint feedf. ctrl. 16 bits	From version 14.00.00
Bit 15	SC: Dead time of speed setpoint 500us	From version 14.00.00
Subcodes	Lenze setting	Info
C02865/1	0x0000	MCTRL: Special settings
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT		

C02866

Parameter Name: C02866 MCTRL: Special settings		Data type: UNSIGNED_8 Index: 21709 _d = 54CD _h
Activation of special functions of the internal motor control		
Selection list		
0	No	
1	Yes	
Subcodes	Lenze setting	Info
C02866/1	1: Yes	Motor ident.: Current controller par. from C075 C076 ▶ Automatic motor data identification
C02866/2	0: No	Motor phase error monitoring before operation • From version 02.00.00 ▶ Motor phase error monitoring before operation
C02866/3	0: No	Brake chopper DC-bus slave • From version 12.00.00 ▶ Control of multiple internal brake choppers in the DC-bus system
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input checked="" type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C02867

Parameter Name: C02867 - Identification procedure		Data type: UNSIGNED_8 Index: 21708 _d = 54C _{Ch}
Selection of the identification procedure for motor parameter identification ► Automatic motor parameter identification		
Selection list		Info
0	automatic	Automatic selection of the optimum identification procedure: <ul style="list-style-type: none"> For synchronous motors, the extended identification procedure is always used. For asynchronous motors with a rated motor power of up to 11 kW, the basic identification procedure is used. For asynchronous motors with a rated motor power of more than 11 kW, the extended identification procedure is used.
1	standard identification	<ul style="list-style-type: none"> Only for asynchronous motors. Duration approx. 30 s
2	extended identification	<ul style="list-style-type: none"> Stands out due to increased accuracy of the determined motor parameters. Also supports synchronous motors and asynchronous motors with a power of more than 11 kW. Duration approx. 80 s
Subcodes	Lenze setting	Info
C02867/1	0: automatic	Motor parameter identification: Process
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input checked="" type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1		

C02870

Parameter Name: C02870 PLI without motion: Optimisation factor			Data type: INTEGER_16 Index: 21705 _d = 54C9 _h		
From version 02.00.00					
▶ Pole position identification without motion					
Display range (min. value unit max. value)					
0.00	%	300.00			
Subcodes			Info		
C02870/1			PLI without motion: Optimisation factor		
<input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT Scaling factor: 100					

C02871

Parameter Name: C02871 PLI without motion: Running time			Data type: INTEGER_16 Index: 21704 _d = 54C8 _h	
From version 02.00.00				
<div>► Pole position identification without motion</div>				
Display range (min. value unit max. value)				
0.00	ms	300.00		
Subcodes			Info	
C02871/1			PLI without motion: Running time	
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 100</div></div>				

C02872

Parameter Name: C02872 PLI without motion: Adaptation of time duration			Data type: INTEGER_8 Index: 21703 _d = 54C7 _h
From version 02.00.00			
<div>▶ Pole position identification without motion</div>			
Setting range (min. value unit max. value)			
-10			
Subcodes	Lenze setting	Info	
C02872/1	0	PLI without motion: Adaptation of time duration	
<div><input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1</div>			

C02873

Parameter Name: C02873 PLI without motion: Ident. el. rotor displ. angle			Data type: INTEGER_16 Index: 21702 _d = 54C6 _h	
From version 02.00.00				
<div>▶ Pole position identification without motion</div>				
Display range (min. value unit max. value)				
0	°	360		
Subcodes			Info	
C02873/1			PLI without motion: Ident. el. rotor displ. angle	
<div><input checked="" type="checkbox"/> Read access <input type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input type="checkbox"/> MOT <div>Scaling factor: 1</div></div>				

C02874

Parameter Name: C02874 PLI without motion		Data type: UNSIGNED_16 Index: 21701 _d = 54C5 _h	
From version 02.00.00			
		▶ Pole position identification without motion	
Setting range (min. hex value max. hex value)			
0x0000	0xFFFF		
Value is bit-coded:		Info	
Bit 0	for SLPSM with controller enable		
Bit 1	for SC PSM with mains on		
Bit 2	for SC PSM with controller enable		
Bit 3	for SC PSM once after fault reset	From version 14.00.00	
Bit 4	Reserved		
Bit 5	Reserved		
Bit 6	Reserved		
Bit 7	Reserved		
Bit 8	Reserved		
Bit 9	Reserved		
Bit 10	Reserved		
Bit 11	Reserved		
Bit 12	Reserved		
Bit 13	Reserved		
Bit 14	Reserved		
Bit 15	Reserved		
Subcodes	Lenze setting	Info	
C02874/1	0x0001	PLI without motion	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT			

C02875

Parameter Name: C02875 PLI without motion: Adaptation of ident angle			Data type: INTEGER_8 Index: 21700 _d = 54C4 _h
From version 02.00.00			
			▶ Pole position identification without motion
Setting range (min. value unit max. value)			
-100	°	100	
Subcodes	Lenze setting	Info	
C02875/1	0 °	PLI without motion: Adaptation of ident angle	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1			

C02876

Parameter Name: C02876 PSM: Max. motor temperature			Data type: UNSIGNED_8 Index: 21699 _d = 54C3 _h		
From version 02.00.00					
Setting range (min. value unit max. value)					
90	°C	200			
Subcodes	Lenze setting		Info		
C02876/1	150 °C		PSM: Max. motor temperature		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 1					

C02877

Parameter Name: C02877 PSM temperature coefficient			Data type: INTEGER_16 Index: 21698 _d = 54C2 _h		
From version 02.00.00					
Setting range (min. value unit max. value)					
-0.30	%/°C	0.00			
Subcodes	Lenze setting		Info		
C02877/1	-0.11 %/°C		PSM temperature coefficient		
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT Scaling factor: 100					

C02878

Parameter Name:		Data type: UNSIGNED_16 Index: 21697 _d = 54C1 _h	
C02878 KTY motor temperature compensation			
From version 02.00.00			
A temperature compensation over the detected motor temperature (display in C00063/1) serves to compensate inaccuracies in the output torque within the motor control in case of temperature changes of the asynchronous or synchronous motor.			
Note!			
In the Lenze setting, the temperature compensation within the motor control is activated. The temperature compensation, however, is only active with speed encoder selection "3: Multi encoder" or "4: Resolver" in C00495 as well as error-free KTY temperature detection (display in C00063/1 ≠ 255 °C).			
► Temperature compensation within the motor control			
Setting range (min. hex value max. hex value)			
0x0000			0xFFFF
Value is bit-coded:			
Bit 0	for SC PSM		
Bit 1	for SC ASM		
Bit 2	Reserved		
Bit 3	Reserved		
Bit 4	Reserved		
Bit 5	Reserved		
Bit 6	Reserved		
Bit 7	Reserved		
Bit 8	Reserved		
Bit 9	Reserved		
Bit 10	Reserved		
Bit 11	Reserved		
Bit 12	Reserved		
Bit 13	Reserved		
Bit 14	Reserved		
Bit 15	Reserved		
Subcodes	Lenze setting	Info	
C02878/1	0x0003	KTY motor temperature compensation	
<input checked="" type="checkbox"/> Read access <input checked="" type="checkbox"/> Write access <input type="checkbox"/> CINH <input type="checkbox"/> PLC STOP <input type="checkbox"/> No transfer <input type="checkbox"/> COM <input checked="" type="checkbox"/> MOT			

C02879

Parameter | Name:

C02879 | Slip calculation from equivalent circuit diagram

Data type: UNSIGNED_16

Index: 21696_d = 54C0_h

From version 02.00.00

In order to achieve a better speed stability and torque accuracy, the slip calculation can be either derived from the motor nameplate data (e.g. rated motor speed) or the motor equivalent circuit diagram data (stator resistance, rotor resistance etc.).

Setting range (min. hex value max. hex value)		
0x0000		0xFFFF
Value is bit-coded:		Info
Bit 0	SLVC	▸ Slip calculation for SLVC
Bit 1	SC ASM	▸ Slip calculation for SC
Bit 2	Reserved	
Bit 3	Reserved	
Bit 4	Reserved	
Bit 5	Reserved	
Bit 6	Reserved	
Bit 7	Reserved	
Bit 8	Reserved	
Bit 9	Reserved	
Bit 10	Reserved	
Bit 11	Reserved	
Bit 12	Reserved	
Bit 13	Reserved	
Bit 14	Reserved	
Bit 15	Reserved	
Subcodes	Lenze setting	Info
C02879/1	0x0002	Slip calculation from equivalent circuit diagram

☒ Read access
 ☒ Write access
 ☐ CINH
 ☐ PLC STOP
 ☐ No transfer
 ☐ COM
 ☒ MOT

C02993

Parameter Name:	Data type: UNSIGNED_32
C02993 FB xy position	Index: 21582 _d = 544E _h
This code is for device-internal use only and must not be written to by the user!	

C02994

Parameter Name:	Data type: UNSIGNED_32
C02994 FB xy position	Index: 21581 _d = 544D _h
This code is for device-internal use only and must not be written to by the user!	

C02995

Parameter Name:		Data type: UNSIGNED_32	
C02995 FB display InputOutput		Index: 21580 _d = 544C _h	
This code is for device-internal use only and must not be written to by the user!			

C02996

Parameter	Name:	Data type: UNSIGNED_32
C02996	FB display InputOutput2	Index: 21579 _d = 544B _h
This code is for device-internal use only and must not be written to by the user!		

C02998

Parameter	Name:	Data type: UNSIGNED_32
C02998	FB displayinputoutput3	Index: 21577 _d = 5449 _h
This code is for device-internal use only and must not be written to by the user!		

17.3

Selection list - analog signals

This selection list is relevant for the following configuration parameters:

Parameter	
C00410	L_SignalMonitor_a: Signal sources
C00620	System connection list: 16-bit
C00700	LA_NCtrl: Analog connection list
C00710	LA_TabPos: Analog connection list
C00760	LA_SwitchPos: Analog connection list

Selection list - analog signals	
0	Not connected
1000	LA_NCtrl: wDriveControlStatus
1001	LA_NCtrl: wFailNumber
1002	LA_NCtrl: nMotorCurrent_a
1003	LA_NCtrl: nMotorSpeedAct_a
1006	LA_NCtrl: nGPAAnalogSwitchOut_a
1007	LA_NCtrl: nGPArithmetikOut_a
1008	LA_NCtrl: nGPMulDivOut_a
1009	LA_NCtrl: nGPSignalOut1_a
1010	LA_NCtrl: nGPSignalOut2_a
1011	LA_NCtrl: nGPSignalOut3_a
1012	LA_NCtrl: nGPSignalOut4_a
1013	LA_NCtrl: nMotorTorqueAct_a
1014	LA_NCtrl: nDCVoltage_a
1015	LA_NCtrl: nMotorVoltage_a
1016	LA_NCtrl: nMotorSpeedSet_a
1017	LA_NCtrl: wFailTypeDomain
1023	LA_NCtrl: wFreeOut1
1024	LA_NCtrl: wFreeOut2
1025	LA_NCtrl: wFreeOut3
1026	LA_NCtrl: wFreeOut4
1100	LA_TabPos: wDriveControlStatus
1101	LA_TabPos: wFailNoLow
1102	LA_TabPos: wFailNoHigh
1103	LA_TabPos: nMotorCurrent_a
1104	LA_TabPos: nMotorSpeedSet_a
1105	LA_TabPos: nMotorSpeedAct_a
1106	LA_TabPos: nMotorTorqueAct_a
1107	LA_TabPos: nDCVoltage_a
1108	LA_TabPos: nMotorVoltage_a
1109	LA_TabPos: wMckState1
1110	LA_TabPos: wMckState2
1111	LA_TabPos: wMckActOperationMode
1112	LA_TabPos: wActProfileNo
1113	LA_TabPos: wActPosMode
1114	LA_TabPos: nGPAAnalogSwitchOut_a
1115	LA_TabPos: nGPArithmetikOut_a
1116	LA_TabPos: nGPMulDivOut_a
1117	LA_TabPos: nGPSignalOut1_a
1118	LA_TabPos: nGPSignalOut2_a

Selection list - analog signals	
1119	LA_TabPos: nGPSignalOut3_a
1120	LA_TabPos: nGPSignalOut4_a
1121	LA_TabPos: wGPCounter1Out
1122	LA_TabPos: wFreeOut1
1123	LA_TabPos: wFreeOut2
1124	LA_TabPos: wFreeOut3
1125	LA_TabPos: wFreeOut4
1126	LA_TabPos: nPosCtrlOutLimit_a
1127	LA_TabPos: nPosCtrlPADapt_a
1128	LA_TabPos: wPosOutUnitsLW
1129	LA_TabPos: wPosOutUnitsHW
1200	LA_SwitchPos: wDriveControlStatus
1201	LA_SwitchPos: wFailNoLow
1202	LA_SwitchPos: wFailNoHigh
1203	LA_SwitchPos: nMotorCurrent_a
1204	LA_SwitchPos: nMotorSpeedSet_a
1205	LA_SwitchPos: nMotorSpeedAct_a
1206	LA_SwitchPos: nMotorTorqueAct_a
1207	LA_SwitchPos: nDCVoltage_a
1208	LA_SwitchPos: nMotorVoltage_a
1209	LA_SwitchPos: nGPAAnalogSwitchOut_a
1210	LA_SwitchPos: nGPArithmetikOut_a
1211	LA_SwitchPos: nGPMulDivOut_a
1212	LA_SwitchPos: nGPSignalOut1_a
1213	LA_SwitchPos: nGPSignalOut2_a
1214	LA_SwitchPos: nGPSignalOut3_a
1215	LA_SwitchPos: nGPSignalOut4_a
1221	LA_SwitchPos: wFreeOut1
1222	LA_SwitchPos: wFreeOut2
1223	LA_SwitchPos: wFreeOut3
1224	LA_SwitchPos: wFreeOut4
16000	LS_AnalogInput: nIn1_a
16001	LS_AnalogInput: nIn2_a
16002	LP_CanIn1: wCtrl
16003	LP_CanIn1: wIn2
16004	LP_CanIn1: wIn3
16005	LP_CanIn1: wIn4
16006	LP_CanIn2: wIn1
16007	LP_CanIn2: wIn2
16008	LP_CanIn2: wIn3
16009	LP_CanIn2: wIn4
16010	LP_CanIn3: wIn1
16011	LP_CanIn3: wIn2
16012	LP_CanIn3: wIn3
16013	LP_CanIn3: wIn4
16014	LS_DigitalInput: wCountIn1_LW
16015	LS_DigitalInput: wCountIn1_HW
16016	LS_DigitalInput: nFreqIn12_a
16017	LS_DigitalInput: nFreqIn12_v
16018	LS_DigitalInput: wCountIn6_LW

Selection list - analog signals	
16019	LS_DigitalInput: wCountIn6_HW
16020	LS_DigitalInput: nFreqIn67_a
16021	LS_DigitalInput: nFreqIn67_v
16100	LS_DataAccess: wOut1
16101	LS_DataAccess: wOut2
16102	LS_DataAccess: wOut3
16103	LS_DataAccess: wOut4
16104	LP_McIn: wCtrl
16105	LP_McIn: wIn2
16106	LP_McIn: wIn3
16107	LP_McIn: wIn4
16108	LP_McIn: wIn5
16109	LP_McIn: wIn6
16110	LP_McIn: wIn7
16111	LP_McIn: wIn8
16112	LP_McIn: wIn9
16113	LP_McIn: wIn10
16114	LP_McIn: wIn11
16115	LP_McIn: wIn12
16116	LP_McIn: wIn13
16117	LP_McIn: wIn14
16118	LP_McIn: wIn15
16119	LP_McIn: wIn16
16120	LS_Keypad: nTorqueMotLim_a
16121	LS_Keypad: nTorqueGenLim_a
16122	LS_Keypad: nMainSetValue_a
16123	LS_CANManagement: wNodeID
16130	LS_ParReadWrite_1: wOutHWord
16131	LS_ParReadWrite_1: wOutLWord
16132	LS_ParReadWrite_2: wOutHWord
16133	LS_ParReadWrite_2: wOutLWord
16134	LS_ParReadWrite_3: wOutHWord
16135	LS_ParReadWrite_3: wOutLWord
16136	LS_ParReadWrite_4: wOutHWord
16137	LS_ParReadWrite_4: wOutLWord
16138	LS_ParReadWrite_5: wOutHWord
16139	LS_ParReadWrite_5: wOutLWord
16140	LS_ParReadWrite_6: wOutHWord
16141	LS_ParReadWrite_6: wOutLWord
16170	LS_AxisBusIn: wLine1
16171	LS_AxisBusIn: wLine2
16172	LS_AxisBusIn: wLine1
16173	LS_AxisBusIn: wCas1
16174	LS_AxisBusIn: wCas2
16175	LS_AxisBusIn: wCas3
16176	LS_AxisBusIn: wCas4
16177	LS_AxisBusAux: wAuxIn1
16178	LS_AxisBusAux: wAuxIn2
16179	LS_AxisBusAux: wAuxIn3
16180	LS_AxisBusAux: wAuxIn4
16181	LS_AxisBusAux: wSlaveNo
16300	LS_MultiEncoder: nActSpeed_v

Selection list - analog signals	
16301	LS_MultiEncoder: nActSpeed_a
16302	LS_MultiEncoder: wHighWord
16303	LS_MultiEncoder: wLowWord
16320	LS_BusEncoder: nActSpeed_v
16321	LS_BusEncoder: nActSpeed_a
16322	LS_BusEncoder: wHighWord
16323	LS_BusEncoder: wLowWord
16340	LS_Resolver: nActSpeed_v
16341	LS_Resolver: nActSpeed_a
16350	LS_RetainData: wOut1
16351	LS_RetainData: wOut2
16352	LS_RetainData: wOut3
16353	LS_RetainData: wOut4
16360	LP_CanIn4: wIn1
16361	LP_CanIn4: wIn2
16362	LP_CanIn4: wIn3
16363	LP_CanIn4: wIn4
20000	LS_ParFix: nPos100_a
20001	LS_ParFix: nNeg100_a
20002	LS_ParFix: nPos199_99_a
20003	LS_ParFix: nNeg199_99_a
20004	LS_ParFix: w65535
20005	LS_ParFix: wDriveCtrl
20010	LS_ParFree_a: nC472_1_a
20011	LS_ParFree_a: nC472_2_a
20012	LS_ParFree_a: nC472_3_a
20013	LS_ParFree_a: nC472_4_a
20014	LS_ParFree_a: nC472_5_a
20015	LS_ParFree_a: nC472_6_a
20016	LS_ParFree_a: nC472_7_a
20017	LS_ParFree_a: nC472_8_a
20018	LS_ParFree_v: nC473_1_v
20019	LS_ParFree_v: nC473_2_v
20020	LS_ParFree_v: nC473_3_v
20021	LS_ParFree_v: nC473_4_v
20022	LS_ParFree_v: nC473_5_v
20023	LS_ParFree_v: nC473_6_v
20024	LS_ParFree_v: nC473_7_v
20025	LS_ParFree_v: nC473_8_v
20026	LS_ParFree: wC471_1
20027	LS_ParFree: wC471_2
20028	LS_ParFree: wC471_3
20029	LS_ParFree: wC471_4
20030	LS_ParFree: wC471_5
20031	LS_ParFree: wC471_6
20032	LS_ParFree: wC471_7
20033	LS_ParFree: wC471_8
20034	LS_ParFree: wC471_9
20035	LS_ParFree: wC471_10
20036	LS_ParFree: wC471_11
20037	LS_ParFree: wC471_12
20038	LS_ParFree: wC471_13

Selection list - analog signals	
20039	LS_ParFree: wC471_14
20040	LS_ParFree: wC471_15
20041	LS_ParFree: wC471_16
20042	LS_ParFree: wC471_17
20043	LS_ParFree: wC471_18
20044	LS_ParFree: wC471_19
20045	LS_ParFree: wC471_20
20046	LS_ParFree: wC471_21
20047	LS_ParFree: wC471_22
20048	LS_ParFree: wC471_23
20049	LS_ParFree: wC471_24
20050	LS_ParFree: wC471_25
20051	LS_ParFree: wC471_26
20052	LS_ParFree: wC471_27
20053	LS_ParFree: wC471_28
20054	LS_ParFree: wC471_29
20055	LS_ParFree: wC471_30
20056	LS_ParFree: wC471_31
20057	LS_ParFree: wC471_32
20058	LS_ParFree_a: nC472_9_a
20059	LS_ParFree_a: nC472_10_a
20060	LS_ParFree_a: nC472_11_a
20061	LS_ParFree_a: nC472_12_a
20062	LS_ParFree_a: nC472_13_a
20063	LS_ParFree_a: nC472_14_a
20064	LS_ParFree_a: nC472_15_a
20065	LS_ParFree_a: nC472_16_a
20066	LS_ParFree_a_2: nC476_1_a
20067	LS_ParFree_a_2: nC476_2_a
20068	LS_ParFree_a_2: nC476_3_a
20069	LS_ParFree_a_2: nC476_4_a
20070	LS_ParFree_a_2: nC476_5_a
20071	LS_ParFree_a_2: nC476_6_a
20072	LS_ParFree_a_2: nC476_7_a
20073	LS_ParFree_a_2: nC476_8_a
20074	LS_ParFree_a_2: nC476_9_a
20075	LS_ParFree_a_2: nC476_10_a
20076	LS_ParFree_a_2: nC476_11_a
20077	LS_ParFree_a_2: nC476_12_a
20078	LS_ParFree_a_2: nC476_13_a
20079	LS_ParFree_a_2: nC476_14_a
20080	LS_ParFree_a_2: nC476_15_a
20081	LS_ParFree_a_2: nC476_16_a
20082	LS_ParFix_2: nPos100_a
20083	LS_ParFix_2: nNeg100_a
20084	LS_ParFix_2: nPos199_99_a
20085	LS_ParFix_2: nNeg199_99_a
20086	LS_ParFix_2: 65535
20087	LS_ParFix_2: wDriveCtrl
20088	LS_ParFree_2: wC477_1
20089	LS_ParFree_2: wC477_2
20090	LS_ParFree_2: wC477_3

Selection list - analog signals	
20091	LS_ParFree_2: wC477_4
20092	LS_ParFree_2: wC477_5
20093	LS_ParFree_2: wC477_6
20094	LS_ParFree_2: wC477_7
20095	LS_ParFree_2: wC477_8
20096	LS_ParFree_2: wC477_9
20097	LS_ParFree_2: wC477_10
20098	LS_ParFree_2: wC477_11
20099	LS_ParFree_2: wC477_12
20100	LS_ParFree_2: wC477_13
20101	LS_ParFree_2: wC477_14
20102	LS_ParFree_2: wC477_15
20103	LS_ParFree_2: wC477_16
20104	LS_ParFree_2: wC477_17
20105	LS_ParFree_2: wC477_18
20106	LS_ParFree_2: wC477_19
20107	LS_ParFree_2: wC477_20
20108	LS_ParFree_2: wC477_21
20109	LS_ParFree_2: wC477_22
20110	LS_ParFree_2: wC477_23
20111	LS_ParFree_2: wC477_24
20112	LS_ParFree_2: wC477_25
20113	LS_ParFree_2: wC477_26
20114	LS_ParFree_2: wC477_27
20115	LS_ParFree_2: wC477_28
20116	LS_ParFree_2: wC477_29
20117	LS_ParFree_2: wC477_30
20118	LS_ParFree_2: wC477_31
20119	LS_ParFree_2: wC477_32
20120	LS_ParFree_v_2: nC478_1_v
20121	LS_ParFree_v_2: nC478_2_v
20122	LS_ParFree_v_2: nC478_3_v
20123	LS_ParFree_v_2: nC478_4_v
20124	LS_ParFree_v_2: nC478_5_v
20125	LS_ParFree_v_2: nC478_6_v
20126	LS_ParFree_v_2: nC478_7_v
20127	LS_ParFree_v_2: nC478_8_v
20128	LS_DFOut: nOutAct_v
32000	LS_MotorInterface: nMotorSpeedAct_a
32001	LS_MotorInterface: nOutputSpeedCtrl_a
32002	LS_MotorInterface: nInputJerkCtrl_a
32003	LS_MotorInterface: nInputTorqueCtrl_a
32004	LS_MotorInterface: nMotorTorqueAct_a
32005	LS_MotorInterface: nActualFluxx_a
32006	LS_MotorInterface: nDCVoltage_a
32007	LS_MotorInterface: nStatorCurrentIS_a
32008	LS_MotorInterface: nEffCurrentIq_a
32009	LS_MotorInterface: nReaktCurrentId_a
32010	LS_MotorInterface: wMaxMotorSpeed
32011	LS_MotorInterface: wMaxMotorTorque
32012	LS_MotorInterface: nMotorVoltage_a
32013	LS_MotorInterface: nMotorFreqAct_a

Selection list - analog signals	
32014	LS_MotorInterface: nEffSpeedSetValue_a
32015	LS_DeviceMonitor_MCTRL: nLxTRate_a
32016	LS_DeviceMonitor_MCTRL: nL2xTRate_a
32017	LS_MotorInterface: nOutputPosCtrl_a
32018	LS_MotorInterface: nHlgSetValue_a
32019	LS_MotorInterface: nMotorSpeedAct_v
32020	LS_MotorInterface: nSpeedCtrlAct_a
32021	LS_MotorInterface: nVoltageAngleAct_a
32022	LS_DeviceMonitor_MCTRL: nActiveOuputPower_a
32023	LS_DeviceMonitor_MCTRL: nApparentOuputPower_a
32024	LS_DeviceMonitor_MCTRL: nMctrlCosinePhiAct_a
32100	LS_DriveInterface: wDeviceStateWord
32101	LS_DriveInterface: wDeviceAuxStateWord
32102	LS_DriveInterface: wDetermFailNoLow
32103	LS_DriveInterface: wDetermFailNoHigh
32104	LS_DriveInterface: wDetermFailNoShort
32200	LS_MotionControlKernel: nSpeedSet_v
32201	LS_MotionControlKernel: nSpeedCtrl_a
32202	LS_MotionControlKernel: nSpeedSetValue_a
32203	LS_MotionControlKernel: nTorqueSetValue_a
32204	LS_MotionControlKernel: wActProfileNo
32205	LS_MotionControlKernel: wFollowProfileNo
32206	LS_MotionControlKernel: wMotionState1
32207	LS_MotionControlKernel: wMotionState2
32208	LS_MotionControlKernel: wAuxState
32209	LS_MotionControlKernel: nPWMAngleOffset
32210	LS_MotionControlKernel: nTorqueLimitAdapt_a
32211	Reserved: a32211
34900	MCTRL: OszCh1
34901	MCTRL: OszCh2
34902	MCTRL: OszCh3
34903	MCTRL: OszCh4
34904	MCTRL: Status1
34905	MCTRL: Status2
34906	MCTRL: Status3
34907	LS_DeviceMonitor: wUB_24V
36000	L_Absolut_1: nOut_a
36001	L_AddSub_1: nOut_a
36002	L_OffsetGain_1: nOut_a
36003	L_OffsetGain_2: nOut_a
36004	L_OffsetGainP_1: nOut_a
36005	L_OffsetGainP_2: nOut_a
36006	L_GainOffset_1: nOut_a
36007	L_GainOffset_2: nOut_a
36008	L_GainOffsetP_1: nOut_a
36009	L_GainOffsetP_2: nOut_a
36010	L_Negation_1: nOut_a
36011	L_Arithmetik_1: nOut_a
36012	L_Arithmetik_2: nOut_a
36013	L_AnalogSwitch_1: nOut_a
36014	L_AnalogSwitch_2: nOut_a
36015	L_AnalogSwitch_3: nOut_a

Selection list - analog signals	
36016	L_Limit_1: nOut_a
36017	L_Limit_2: nOut_a
36018	L_NSet_1: nOut
36019	L_MPot_1: nOut_a
36020	L_PCTRL_1: nOut_a
36021	L_SignalMonitor_a: nOut1_a
36022	L_SignalMonitor_a: nOut2_a
36023	L_NLim_1: nOut_a
36024	L_Counter_1: wOut
36025	L_OffsetGainP_3: nOut_a
36026	L_GainOffsetP_3: nOut_a
36027	L_SignalMonitor_a: nOut3_a
36028	L_SignalMonitor_a: nOut4_a
36029	L_MulDiv_1: nOut_a
36030	L_NLim_1: wState
36031	L_NSet_1: wState
36032	L_NSet_1: nSetValue
36033	L_PT1_1: nOut_a
36034	L_Absolut_2: nOut_a
36035	L_AnalogSwitch_4: nOut_a
36036	L_AnalogSwitch_5: nOut_a
36037	L_Arithmetik_3: nOut_a
36038	L_Arithmetik_4: nOut_a
36039	L_Arithmetik_5: nOut_a
36045	L_GainOffset_3: nOut_a
36053	L_MulDiv_2: nOut_a
36054	L_Negation_2: nOut_a
36055	L_NLim_2: nOut_a
36056	L_NLim_2: wState
36057	L_OffsetGain_3: nOut_a
36058	L_PT1_2: nOut_a
36059	L_PT1_3: nOut_a
36064	L_SampleHold_1: nOut_a
36065	L_SampleHold_2: nOut_a
36068	L_Counter_2: wOut
36069	L_Counter_3: wOut
36073	L_DT1_1: nOut_a
36074	L_ConvBitsToWorld_1: wOut
36075	L_ConvBitsToWorld_2: wOut
36076	L_ConvBitsToWorld_3: wOut
36077	L_ConvDIntToWords_1: wOutLWord
36078	L_ConvDIntToWords_1: wOutHWord
36079	L_ConvDIntToWords_2: wOutLWord
36080	L_ConvDIntToWords_2: wOutHWord
36081	L_ConvDIntToWords_3: wOutLWord
36082	L_ConvDIntToWords_3: wOutHWord
36083	L_MckCtrlInterface_1: wOutMckPosCtrl_1
36084	L_MckCtrlInterface_1: wOutMckPosCtrl_2
36085	L_MckCtrlInterface_1: wFailState
36086	L_MckStateInterface_1: wOperationMode
36087	L_MckStateInterface_1: wActProfileNo
36088	L_MckStateInterface_1: wActPosMode

Selection list - analog signals	
36089	L_PosiShaftCtrlInterface_1: wOutMckPosCtrl_1
36090	L_PosiShaftCtrlInterface_1: wOutMckPosCtrl_2
36091	L_PCTRL_1: nPIDOut1_a
36092	L_PCTRL_1: nPIDOut2_a
36093	L_PCTRL_1: nInfluenceOut_a
36094	L_Curve_1: nOut_a
36095	L_Interpolator_1: nPhdOut_v
36096	L_Interpolator_1: nNOut_a
36097	L_ConvW_1: wOut
36098	L_ConvW_2: wOut
36099	L_ConvW_3: wOut
36100	L_ConvW_4: wOut
36101	L_SRFG_1: nOut_a
36102	L_SRFG_2: nOut_a
36103	L_MckStatelInterface_1: wPosUnitsLW
36104	L_MckStatelInterface_1: wPosUnitsHW
36105	L_SignalSwitch_1: wOut
36106	L_SignalSwitch_2: wOut
36107	L_SignalSwitch_3: wOut
36108	L_SignalSwitch_4: wOut
36109	L_SRFG_1: nDeltaOut_a
36110	L_SRFG_2: nDeltaOut_a
36111	L_Odometer_1: wLastMeasure
36112	L_FixSet_a_1: nOut_a
36113	L_FixSet_a_1: wSelect
36114	L_FixSet_w_1: wOut
36115	L_FixSet_w_1: wSelect
36116	L_FixSet_w_2: wOut
36117	L_FixSet_w_2: wSelect
36120	L_CalcDiameter_1: nDiameter_a
36121	L_CalcDiameter_1: nReziprDiameter_a
36122	L_CalcDiameter_1: nNReel_v
36123	L_CalcDiameter_1: nDMin_a
36124	L_ProcessCtrl_1: nOut_a
36125	L_ProcessCtrl_1: nOutRed_a
36126	L_ProcessCtrl_1: nDeviation_a
36127	L_ProcessCtrl_1: nDComponent
36128	L_PhiIntegrator_1: nOut16
36129	L_PhiIntegrator_1: nSpeedGearAdd_v
36130	L_PosCtrlLin_1: nNOut_v
36131	L_PosCtrlLin_2: nNOut_v
36132	L_PhiIntegrator_1: nSpeedGear_v
36133	L_DFSET_1: nSetGain_v
36134	L_DFSET_1: nSetGearTrim_v
36135	L_DFSET_1: nSetGearTrim_a
36136	L_DFRFG_1: nOut_v
36137	L_ConvPA_1: nOut
36138	L_ConvPA_2: nOut
36139	L_ConvPA_3: nOut
36140	L_ConvX_1: nOut
36141	L_ConvX_2: nOut
36142	L_ConvX_3: nOut

Selection list - analog signals	
36143	LS_MotionControlKernel: wGearNum
36144	LS_MotionControlKernel: wGearDenom
36145	L_DFSET_1: nSpeedSetOut_v
36146	L_Curve_2: nOut_a
36147	L_Curve_3: nOut_a
36148	L_Curve_3: nCurveValue_a
36150	L_Sequencer_1: wMCKPosCtrl1
36151	L_Sequencer_1: wMCKPosCtrl2
36152	L_Sequencer_1: wAuxCtrl
36153	L_Sequencer_1: wState
36154	L_Sequencer_1: wActStep
36155	L_Sequencer_1: nSet_a
36156	L_Sequencer_1: wProfileNumber
36157	L_Sequencer_1: wDigitalOutputs
36158	L_ConvActPos_1: nPosOut_a
36159	L_ConvActPos_1: nVAdditive_a
36160	L_ConvActPos_1: nVOut_a
36161	L_ConvActPos_1: nMAdditive_a
36162	L_MFail_1: nNOut_a
42000	LA_NCtrl_In: wCANDriveControl
42001	LA_NCtrl_In: wCCMDriveControl
42002	LA_NCtrl_In: nTorqueMotLim
42003	LA_NCtrl_In: nTorqueGenLim
42004	LA_NCtrl_In: nPIDVpAdapt_a
42005	LA_NCtrl_In: nPIDActValue_a
42006	LA_NCtrl_In: nMainSetValue
42007	LA_NCtrl_In: nAuxSetValue
42008	LA_NCtrl_In: nGPAnalogSwitchIn1_a
42009	LA_NCtrl_In: nGPAnalogSwitchIn2_a
42010	LA_NCtrl_In: nGPArithmetikIn1_a
42011	LA_NCtrl_In: nGPArithmetikIn2_a
42012	LA_NCtrl_In: nGPMulDivIn_a
42013	LA_NCtrl_In: nGPCompareIn1_a
42014	LA_NCtrl_In: nGPCompareIn2_a
42015	LA_NCtrl_In: nVoltageAdd_a
42016	LA_NCtrl_In: nPIDInfluence_a
42017	LA_NCtrl_In: nPIDSetValue_a
42018	LA_NCtrl_In: nPWMAngleOffset
42019	LA_NCtrl_In: nBoost_a
42020	LA_NCtrl_In: wSMControl
42025	LA_NCtrl_In: wFreelIn1
42026	LA_NCtrl_In: wFreelIn2
42027	LA_NCtrl_In: wFreelIn3
42028	LA_NCtrl_In: wFreelIn4
42100	LA_TabPos_In: wCanDriveControl
42101	LA_TabPos_In: wMciDriveControl
42102	LA_TabPos_In: nTorqueMotLim_a
42103	LA_TabPos_In: nTorqueGenLim_a
42104	LA_TabPos_In: nMainSetValue_a
42105	LA_TabPos_In: nAuxSetValue_a
42106	LA_TabPos_In: wMckCtrl1
42107	LA_TabPos_In: wMckCtrl2

Selection list - analog signals	
42108	LA_TabPos_In: wMckOperationMode
42109	LA_TabPos_In: wPosProfileMode
42110	LA_TabPos_In: wPosProfileNo
42111	LA_TabPos_In: nGPAnalogSwitchIn1_a
42112	LA_TabPos_In: nGPAnalogSwitchIn2_a
42113	LA_TabPos_In: nGPArithmetikIn1_a
42114	LA_TabPos_In: nGPArithmetikIn2_a
42115	LA_TabPos_In: nGPMulDivIn_a
42116	LA_TabPos_In: nGPCompareIn1_a
42117	LA_TabPos_In: nGPCompareIn2_a
42118	LA_TabPos_In: wGPCounter1LdVal
42119	LA_TabPos_In: wGPCounter1CmpVal
42120	LA_TabPos_In: nSpeedOverride_a
42121	LA_TabPos_In: nAccOverride_a
42122	LA_TabPos_In: wFreelIn1
42123	LA_TabPos_In: wFreelIn2
42124	LA_TabPos_In: wFreelIn3
42125	LA_TabPos_In: wFreelIn4
42126	LA_TabPos_In: wSMControl
42127	LA_TabPos_In: wPosProfileUnitsLW
42128	LA_TabPos_In: wPosProfileUnitsHW
42200	LA_SwitchPos_In: wCANDriveControl
42201	LA_SwitchPos_In: wMCIDriveControl
42202	LA_SwitchPos_In: nVoltageAdd_a
42203	LA_SwitchPos_In: nBoost_a
42204	LA_SwitchPos_In: nPWMAngleOffset
42205	LA_SwitchPos_In: nTorqueMotLim_a
42206	LA_SwitchPos_In: nTorqueGenLim_a
42207	LA_SwitchPos_In: nMainSetValue_a
42208	LA_SwitchPos_In: nAuxSetValue_a
42209	LA_SwitchPos_In: nGPAnalogSwitchIn1_a
42210	LA_SwitchPos_In: nGPAnalogSwitchIn2_a
42211	LA_SwitchPos_In: nGPArithmetikIn1_a
42212	LA_SwitchPos_In: nGPArithmetikIn2_a
42213	LA_SwitchPos_In: nGPMulDivIn_a
42214	LA_SwitchPos_In: nGPCompareIn1_a
42215	LA_SwitchPos_In: nGPCompareIn2_a
42216	LA_SwitchPos_In: wSMControl
42221	LA_SwitchPos_In: wFreelIn1
42222	LA_SwitchPos_In: wFreelIn2
42223	LA_SwitchPos_In: wFreelIn3
42224	LA_SwitchPos_In: wFreelIn4

17.4

Selection list - digital signals

This selection list is relevant for the following configuration parameters:

Parameter	
C00411	L_SignalMonitor_b: Signal sources
C00621	System connection list: Bool
C00701	LA_NCtrl: Digital connection list
C00711	LA_TabPos: Digital connection list
C00761	LA_SwitchPos: Digital connection list

Selection list - digital signals	
0	Not connected
1000	LA_NCtrl: bDriveReady
1001	LA_NCtrl: bDriveFail
1002	LA_NCtrl: bClnhActive
1003	LA_NCtrl: bQSPlsActive
1004	LA_NCtrl: bSpeedCcw
1005	LA_NCtrl: bSpeedActCompare
1008	LA_NCtrl: bGPDigitalDelayOut
1009	LA_NCtrl: bGPLogicOut
1010	LA_NCtrl: bGPSignalOut1
1011	LA_NCtrl: bGPSignalOut2
1012	LA_NCtrl: bGPSignalOut3
1013	LA_NCtrl: bGPSignalOut4
1014	LA_NCtrl: bOverLoadActive
1015	LA_NCtrl: bMBrakeReleaseOut
1016	LA_NCtrl: bMBrakeReleased
1017	LA_NCtrl: bGPCompareOut
1018	LA_NCtrl: bUnderLoadActive
1019	LA_NCtrl: bImaxActive
1020	LA_NCtrl: bSpeedSetReached
1021	LA_NCtrl: bSpeedActEqSet
1022	LA_NCtrl: bGPDFlipFlopOut
1023	LA_NCtrl: bGPDFlipFlopNegOut
1029	LA_NCtrl: bFreeOut1
1030	LA_NCtrl: bFreeOut2
1031	LA_NCtrl: bFreeOut3
1032	LA_NCtrl: bFreeOut4
1033	LA_NCtrl: bFreeOut5
1034	LA_NCtrl: bFreeOut6
1035	LA_NCtrl: bFreeOut7
1036	LA_NCtrl: bFreeOut8
1100	LA_TabPos: bDriveFail
1101	LA_TabPos: bDriveReady
1102	LA_TabPos: bClnhActive
1103	LA_TabPos: bQSPlsActive
1104	LA_TabPos: bSpeedCcw
1105	LA_TabPos: bSpeedActCompare
1106	LA_TabPos: bImaxActive
1107	LA_TabPos: bSpeedSetReached
1108	LA_TabPos: bMBrakeReleaseOut

Selection list - digital signals	
1109	LA_TabPos: bMBrakeReleased
1110	LA_TabPos: bHomeDone
1111	LA_TabPos: bHomePosAvailable
1112	LA_TabPos: bProfileDone
1113	LA_TabPos: bProfileBusy
1114	LA_TabPos: bAccelerating
1115	LA_TabPos: bConstantDuty
1116	LA_TabPos: bDecelerating
1117	LA_TabPos: bDwellTime
1118	LA_TabPos: bInTarget
1119	LA_TabPos: bGPDigitalDelayOut
1120	LA_TabPos: bGPLogicOut
1121	LA_TabPos: bGPCompareOut
1122	LA_TabPos: bGPSignalOut1
1123	LA_TabPos: bGPSignalOut2
1124	LA_TabPos: bGPSignalOut3
1125	LA_TabPos: bGPSignalOut4
1126	LA_TabPos: bGPDFlipFlop_Out
1127	LA_TabPos: bGPDFlipFlop_NegOut
1128	LA_TabPos: bGPCounter1Equal
1129	LA_TabPos: bFreeOut1
1130	LA_TabPos: bFreeOut2
1131	LA_TabPos: bFreeOut3
1132	LA_TabPos: bFreeOut4
1133	LA_TabPos: bFreeOut5
1134	LA_TabPos: bFreeOut6
1135	LA_TabPos: bFreeOut7
1136	LA_TabPos: bFreeOut8
1200	LA_SwitchPos: bDriveFail
1201	LA_SwitchPos: bWarningActive
1202	LA_SwitchPos: bSafeTorqueOff
1203	LA_SwitchPos: bDriveReady
1204	LA_SwitchPos: bClnhActive
1205	LA_SwitchPos: bImplsActive
1206	LA_SwitchPos: bQSPlsActive
1207	LA_SwitchPos: bSpeedCcw
1208	LA_SwitchPos: bSpeedActCompare
1209	LA_SwitchPos: bImaxActive
1210	LA_SwitchPos: bSpeedSetReached
1211	LA_SwitchPos: bSpeedActEqSet
1212	LA_SwitchPos: bBrakeReleaseOut
1213	LA_SwitchPos: bBrakeReleased
1214	LA_SwitchPos: bGPDigitalDelayOut
1215	LA_SwitchPos: bGPLogicOut
1216	LA_SwitchPos: bGPCompareOut
1217	LA_SwitchPos: bGPDFlipFlop_Out
1218	LA_SwitchPos: bGPDFlipFlop_NegOut
1219	LA_SwitchPos: bGPSignalOut1
1220	LA_SwitchPos: bGPSignalOut2
1221	LA_SwitchPos: bGPSignalOut3

Selection list - digital signals	
1222	LA_SwitchPos: bGPSignalOut4
1228	LA_SwitchPos: bFreeOut1
1229	LA_SwitchPos: bFreeOut2
1230	LA_SwitchPos: bFreeOut3
1231	LA_SwitchPos: bFreeOut4
1232	LA_SwitchPos: bFreeOut5
1233	LA_SwitchPos: bFreeOut6
1234	LA_SwitchPos: bFreeOut7
1235	LA_SwitchPos: bFreeOut8
16000	LS_DigitalInput: bln1
16001	LS_DigitalInput: bln2
16002	LS_DigitalInput: bln3
16003	LS_DigitalInput: bln4
16004	LS_DigitalInput: bln5
16005	LS_DigitalInput: bln6
16006	LS_DigitalInput: bln7
16008	LS_DigitalInput: bClnh
16009	LS_DigitalInput: bCountIn1_Compare
16010	LS_DigitalInput: bCountIn6_Compare
16011	LS_AnalogInput: bCurrentErrorIn1
16012	LS_AnalogInput: bCurrentErrorIn2
16013	LP_CanIn1: bCtrl1_B0
16014	LP_CanIn1: bCtrl1_B1
16015	LP_CanIn1: bCtrl1_B2
16016	LP_CanIn1: bCtrl1_B3
16017	LP_CanIn1: bCtrl1_B4
16018	LP_CanIn1: bCtrl1_B5
16019	LP_CanIn1: bCtrl1_B6
16020	LP_CanIn1: bCtrl1_B7
16021	LP_CanIn1: bCtrl1_B8
16022	LP_CanIn1: bCtrl1_B9
16023	LP_CanIn1: bCtrl1_B10
16024	LP_CanIn1: bCtrl1_B11
16025	LP_CanIn1: bCtrl1_B12
16026	LP_CanIn1: bCtrl1_B13
16027	LP_CanIn1: bCtrl1_B14
16028	LP_CanIn1: bCtrl1_B15
16029	LP_CanIn2: bln1_B0
16030	LP_CanIn2: bln1_B1
16031	LP_CanIn2: bln1_B2
16032	LP_CanIn2: bln1_B3
16033	LP_CanIn2: bln1_B4
16034	LP_CanIn2: bln1_B5
16035	LP_CanIn2: bln1_B6
16036	LP_CanIn2: bln1_B7
16037	LP_CanIn2: bln1_B8
16038	LP_CanIn2: bln1_B9
16039	LP_CanIn2: bln1_B10
16040	LP_CanIn2: bln1_B11
16041	LP_CanIn2: bln1_B12
16042	LP_CanIn2: bln1_B13
16043	LP_CanIn2: bln1_B14

Selection list - digital signals	
16044	LP_CanIn2: bln1_B15
16045	LP_CanIn3: bln1_B0
16046	LP_CanIn3: bln1_B1
16047	LP_CanIn3: bln1_B2
16048	LP_CanIn3: bln1_B3
16049	LP_CanIn3: bln1_B4
16050	LP_CanIn3: bln1_B5
16051	LP_CanIn3: bln1_B6
16052	LP_CanIn3: bln1_B7
16053	LP_CanIn3: bln1_B8
16054	LP_CanIn3: bln1_B9
16055	LP_CanIn3: bln1_B10
16056	LP_CanIn3: bln1_B11
16057	LP_CanIn3: bln1_B12
16058	LP_CanIn3: bln1_B13
16059	LP_CanIn3: bln1_B14
16060	LP_CanIn3: bln1_B15
16061	LP_McIn: bCtrl_B0
16062	LP_McIn: bCtrl_B1
16063	LP_McIn: bCtrl_B2
16064	LP_McIn: bCtrl_B3
16065	LP_McIn: bCtrl_B4
16066	LP_McIn: bCtrl_B5
16067	LP_McIn: bCtrl_B6
16068	LP_McIn: bCtrl_B7
16069	LP_McIn: bCtrl_B8
16070	LP_McIn: bCtrl_B9
16071	LP_McIn: bCtrl_B10
16072	LP_McIn: bCtrl_B11
16073	LP_McIn: bCtrl_B12
16074	LP_McIn: bCtrl_B13
16075	LP_McIn: bCtrl_B14
16076	LP_McIn: bCtrl_B15
16077	LP_McIn: bln2_B0
16078	LP_McIn: bln2_B1
16079	LP_McIn: bln2_B2
16080	LP_McIn: bln2_B3
16081	LP_McIn: bln2_B4
16082	LP_McIn: bln2_B5
16083	LP_McIn: bln2_B6
16084	LP_McIn: bln2_B7
16085	LP_McIn: bln2_B8
16086	LP_McIn: bln2_B9
16087	LP_McIn: bln2_B10
16088	LP_McIn: bln2_B11
16089	LP_McIn: bln2_B12
16090	LP_McIn: bln2_B13
16091	LP_McIn: bln2_B14
16092	LP_McIn: bln2_B15
16093	LS_Keypad: bSetQuickstop
16094	LS_Keypad: bSetDCBrake
16095	LS_Keypad: bSetSpeedCcw

Selection list - digital signals	
16096	LS_Keypad: bJogSpeed1
16097	LS_Keypad: bJogSpeed2
16098	LS_Keypad: bMPotEnable
16099	LS_Keypad: bMPotUp
16100	LS_Keypad: bMPotDown
16101	LS_DigitalInput: bPosIn12_State
16102	LS_DigitalInput: bOutHC_BrakeApplied
16110	LS_ParReadWrite_1: bDone
16111	LS_ParReadWrite_1: bFail
16112	LS_ParReadWrite_2: bDone
16113	LS_ParReadWrite_2: bFail
16114	LS_ParReadWrite_3: bDone
16115	LS_ParReadWrite_3: bFail
16116	LS_ParReadWrite_4: bDone
16117	LS_ParReadWrite_4: bFail
16118	LS_ParReadWrite_5: bDone
16119	LS_ParReadWrite_5: bFail
16120	LS_ParReadWrite_6: bDone
16121	LS_ParReadWrite_6: bFail
16122	LS_WriteParamList: bDone
16123	LS_WriteParamList: bFail
16161	LS_CANManagement: bFail
16162	LS_CANManagement: bOperational
16165	LS_MultiEncoder: bFail
16166	LS_Resolver: bFail
16200	LS_SyncManagement: bSyncSignalOK
16201	LS_SyncManagement: bSyncPhaseOK
16202	LS_MultiEncoder: bState
16205	LS_MultiEncoder: bState2
16206	LS_MultiEncoder: bState3
16303	LS_TouchProbe: bTPDigIn3Received
16304	LS_TouchProbe: bTPDigIn4Received
16305	LS_TouchProbe: bTPDigIn5Received
16306	LS_TouchProbe: bTPDigIn6Received
16307	LS_TouchProbe: bTPDigIn7Received
16308	LS_AxisBusIO: bFail_DigIn
16309	LS_AxisBusIO: bResetFail_In
16310	LS_RetainData: bOut1
16311	LS_RetainData: bOut2
16312	LS_RetainData: bOut3
16313	LS_RetainData: bOut4
16314	LS_TouchProbe: bTPEncoderReceived
16315	LS_TouchProbe: bTPResolverReceived
16320	LS_AxisBusAux: bDone
16321	LS_AxisBusAux: bFail
16400	LP_CanIn4: bln1_B0
16401	LP_CanIn4: bln1_B1
16402	LP_CanIn4: bln1_B2
16403	LP_CanIn4: bln1_B3
16404	LP_CanIn4: bln1_B4
16405	LP_CanIn4: bln1_B5
16406	LP_CanIn4: bln1_B6

Selection list - digital signals	
16407	LP_CanIn4: bln1_B7
16408	LP_CanIn4: bln1_B8
16409	LP_CanIn4: bln1_B9
16410	LP_CanIn4: bln1_B10
16411	LP_CanIn4: bln1_B11
16412	LP_CanIn4: bln1_B12
16413	LP_CanIn4: bln1_B13
16414	LP_CanIn4: bln1_B14
16415	LP_CanIn4: bln1_B15
20000	LS_ParFix: bTrue
20001	LS_ParFree_b: bC470_1
20002	LS_ParFree_b: bC470_2
20003	LS_ParFree_b: bC470_3
20004	LS_ParFree_b: bC470_4
20005	LS_ParFree_b: bC470_5
20006	LS_ParFree_b: bC470_6
20007	LS_ParFree_b: bC470_7
20008	LS_ParFree_b: bC470_8
20009	LS_ParFree_b: bC470_9
20010	LS_ParFree_b: bC470_10
20011	LS_ParFree_b: bC470_11
20012	LS_ParFree_b: bC470_12
20013	LS_ParFree_b: bC470_13
20014	LS_ParFree_b: bC470_14
20015	LS_ParFree_b: bC470_15
20016	LS_ParFree_b: bC470_16
20017	LS_ParFree_b: bC470_17
20018	LS_ParFree_b: bC470_18
20019	LS_ParFree_b: bC470_19
20020	LS_ParFree_b: bC470_20
20021	LS_ParFree_b: bC470_21
20022	LS_ParFree_b: bC470_22
20023	LS_ParFree_b: bC470_23
20024	LS_ParFree_b: bC470_24
20025	LS_ParFree_b: bC470_25
20026	LS_ParFree_b: bC470_26
20027	LS_ParFree_b: bC470_27
20028	LS_ParFree_b: bC470_28
20029	LS_ParFree_b: bC470_29
20030	LS_ParFree_b: bC470_30
20031	LS_ParFree_b: bC470_31
20032	LS_ParFree_b: bC470_32
20033	LS_PulseGenerator: b100Hz
20034	LS_PulseGenerator: b10Hz
20035	LS_PulseGenerator: b2Hz
20036	LS_PulseGenerator: b1Hz
20037	LS_PulseGenerator: b1HzFlash
20038	LS_PulseGenerator: b2HzFlash
20039	LS_PulseGenerator: bSingleFlash1
20040	LS_PulseGenerator: bSingleFlash2
20041	LS_PulseGenerator: bDoubleFlash
20042	LS_PulseGenerator: bSquareWave

Selection list - digital signals	
20043	LS_PulseGenerator: bFirstCycle
20044	LS_ParFix_2: bTrue
20045	LS_ParFreeUnit_1: bDataValid
20046	LS_ParFreeUnit_2: bDataValid
32000	LS_DeviceMonitor_MCTRL: bFanFault
32001	LS_DeviceMonitor_MCTRL: bHeatSinkTemp
32002	LS_MotorInterface: bLimPosCtrlOut
32003	LS_MotorInterface: bLimSpeedCtrlOut
32004	LS_MotorInterface: bLimSpeedSetVal
32005	LS_MotorInterface: bLimTorqueSetVal
32006	LS_MotorInterface: bLimCurrentSetVal
32007	LS_DeviceMonitor_MCTRL: bUVDetected
32008	LS_DeviceMonitor_MCTRL: bOVDetected
32009	LS_DeviceMonitor_MCTRL: bMotorPhaseFault
32010	LS_DeviceMonitor_MCTRL: bEncoderComFault
32011	LS_DeviceMonitor_MCTRL: b1xtOverload
32012	LS_DeviceMonitor_MCTRL: b12xtOverload
32013	LS_MotorInterface: bIdentificationActive
32014	LS_MotorInterface: bFlyingSyncActive
32015	LS_DeviceMonitor_MCTRL: bTorqueMax
32016	LS_DeviceMonitor_MCTRL: bNMax
32017	LS_DeviceMonitor_MCTRL: bFChopReduced
32018	LS_DeviceMonitor_MCTRL: bMotorPTC
32019	LS_DeviceMonitor_MCTRL: bMotorTemp
32020	LS_MotorInterface: bDcbActive
32021	LS_DeviceMonitor_MCTRL: bBrakeChopperFault
32022	LS_MotorInterface: bQsplsActive
32023	LS_MotorInterface: bHlgLoad
32024	LS_MotorInterface: bHlgStop
32025	LS_DeviceMonitor_MCTRL: bImpActive
32026	LS_DeviceMonitor_MCTRL: bClampActive
32027	LS_DeviceMonitor_MCTRL: bMainsFault
32028	LS_DeviceMonitor_MCTRL: bNmaxForFChop
32029	LS_DeviceMonitor_MCTRL: bShortCircuit
32030	LS_DeviceMonitor_MCTRL: bEarthFault
32031	LS_DeviceMonitor_MCTRL: bWirebreakUfLinearActive
32100	LS_DriveInterface: bInit
32101	LS_DriveInterface: bReady
32102	LS_DriveInterface: bReadyToSwitchOn
32103	LS_DriveInterface: bOperationEnable
32104	LS_DriveInterface: bWarning
32105	LS_DriveInterface: bTrouble
32106	LS_DriveInterface: bFail
32107	LS_DriveInterface: bCollectedFail
32108	LS_DriveInterface: bSafeTorqueOff
32109	LS_DriveInterface: bIMPIsActive
32110	LS_DriveInterface: bCINHIsActive
32111	LS_DriveInterface: bSafetyIsActive
32112	LS_DriveInterface: bCwCcw
32113	LS_DriveInterface: bNactCompare
32200	LS_MotionControlKernel: bPosCtrlOn

Selection list - digital signals	
32201	LS_MotionControlKernel: bSpeedCtrlOn
32202	LS_MotionControlKernel: bTorquemodeOn
32203	LS_MotionControlKernel: bDcBrakeOn
32204	LS_MotionControlKernel: bBrkReleaseOut
32205	LS_MotionControlKernel: bBrkReleased
32206	LS_MotionControlKernel: bDeltaPosOn
32207	LS_MotionControlKernel: bPosDerivativeOn
32208	LS_MotionControlKernel: bMotorRefOffsetOn
32209	LS_MotionControlKernel: bQspOn
32210	LS_MotionControlKernel: bPosBusy
32211	LS_MotionControlKernel: bPosDone
32212	LS_MotionControlKernel: bHomDone
32213	LS_MotionControlKernel: bHomAvailable
32214	LS_MotionControlKernel: bTorqueLimitAdaptOn
32215	Reserved: b32215
32216	Reserved: b32216
32217	Reserved: b32217
32218	Reserved: b32218
32219	LS_MotionControlKernel: bFollowErrLim1
32220	LS_MotionControlKernel: bFollowErrLim2
36000	L_And_1: bOut
36001	L_And_2: bOut
36002	L_And_3: bOut
36003	L_Or_1: bOut
36004	L_Or_2: bOut
36005	L_Or_3: bOut
36006	L_Not_1: bOut
36007	L_Not_2: bOut
36008	L_Not_3: bOut
36009	L_DFlipFlop_1: bOut
36010	L_RLQ_1: bQsp
36011	L_RLQ_1: CwCcw
36012	L_DigitalDelay_1: bOut
36013	L_Compare_1: bOut
36014	L_Compare_2: bOut
36015	L_Compare_3: bOut
36016	L_NSet_1: bRfgEq0
36017	L_DigitalLogic_1: bOut
36018	L_Counter_1: bEqual
36019	L_SignalMonitor_b: bOut1
36020	L_SignalMonitor_b: bOut2
36021	L_SignalMonitor_b: bOut3
36022	L_SignalMonitor_b: bOut4
36023	L_PCTRL_1: bActEqSet
36024	L_NLim_1: bLimitActive
36025	L_DFlipFlop_1: bNegOut
36026	L_And5_1: bOut
36027	L_And5_2: bOut
36028	L_Compare_4: bOut
36029	L_Compare_5: bOut
36030	L_ComparePhi_1: bOut
36031	L_ComparePhi_2: bOut

Selection list - digital signals	
36032	L_ComparePhi_3: bOut
36033	L_ComparePhi_4: bOut
36034	L_ComparePhi_5: bOut
36035	L_DFlipFlop_2: bOut
36036	L_DFlipFlop_2: bNegOut
36037	L_DigitalDelay_2: bOut
36038	L_DigitalDelay_3: bOut
36039	L_Or_4: bOut
36040	L_DigitalLogic_3: bOut
36041	L_DigitalLogic_2: bOut
36042	L_DigitalLogic5_1: bOut
36043	L_DigitalLogic5_2: bOut
36044	L_NLim_2: bLimitActive
36045	L_Or5_1: bOut
36046	L_Or5_2: bOut
36047	L_Not_4: bOut
36048	L_Not_5: bOut
36049	L_Not_6: bOut
36050	L_Not_7: bOut
36055	L_PhaseIntK_1: bState
36056	L_PhaseIntK_2: bState
36057	L_Counter_2: bEqual
36058	L_Counter_3: bEqual
36059	L_RSFlipFlop_1: bOut
36060	L_RSFlipFlop_1: bNegOut
36061	L_RSFlipFlop_2: bOut
36062	L_RSFlipFlop_2: bNegOut
36063	L_Transient_5: bOut
36064	L_Transient_6: bOut
36065	L_Transient_7: bOut
36066	L_Transient_8: bOut
36067	L_ConvWordToBits_1: bBit0
36068	L_ConvWordToBits_1: bBit1
36069	L_ConvWordToBits_1: bBit2
36070	L_ConvWordToBits_1: bBit3
36071	L_ConvWordToBits_1: bBit4
36072	L_ConvWordToBits_1: bBit5
36073	L_ConvWordToBits_1: bBit6
36074	L_ConvWordToBits_1: bBit7
36075	L_ConvWordToBits_1: bBit8
36076	L_ConvWordToBits_1: bBit9
36077	L_ConvWordToBits_1: bBit10
36078	L_ConvWordToBits_1: bBit11
36079	L_ConvWordToBits_1: bBit12
36080	L_ConvWordToBits_1: bBit13
36081	L_ConvWordToBits_1: bBit14
36082	L_ConvWordToBits_1: bBit15
36083	L_ConvWordToBits_2: bBit0
36084	L_ConvWordToBits_2: bBit1
36085	L_ConvWordToBits_2: bBit2
36086	L_ConvWordToBits_2: bBit3
36087	L_ConvWordToBits_2: bBit4

Selection list - digital signals	
36088	L_ConvWordToBits_2: bBit5
36089	L_ConvWordToBits_2: bBit6
36090	L_ConvWordToBits_2: bBit7
36091	L_ConvWordToBits_2: bBit8
36092	L_ConvWordToBits_2: bBit9
36093	L_ConvWordToBits_2: bBit10
36094	L_ConvWordToBits_2: bBit11
36095	L_ConvWordToBits_2: bBit12
36096	L_ConvWordToBits_2: bBit13
36097	L_ConvWordToBits_2: bBit14
36098	L_ConvWordToBits_2: bBit15
36099	L_ConvWordToBits_3: bBit0
36100	L_ConvWordToBits_3: bBit1
36101	L_ConvWordToBits_3: bBit2
36102	L_ConvWordToBits_3: bBit3
36103	L_ConvWordToBits_3: bBit4
36104	L_ConvWordToBits_3: bBit5
36105	L_ConvWordToBits_3: bBit6
36106	L_ConvWordToBits_3: bBit7
36107	L_ConvWordToBits_3: bBit8
36108	L_ConvWordToBits_3: bBit9
36109	L_ConvWordToBits_3: bBit10
36110	L_ConvWordToBits_3: bBit11
36111	L_ConvWordToBits_3: bBit12
36112	L_ConvWordToBits_3: bBit13
36113	L_ConvWordToBits_3: bBit14
36114	L_ConvWordToBits_3: bBit15
36115	L_MckCtrlInterface_1: bFail
36116	L_MckStateInterface_1: bAccelerating
36117	L_MckStateInterface_1: bDecelerating
36118	L_MckStateInterface_1: bConstantSpeedDuty
36119	L_MckStateInterface_1: bSShaping
36120	L_MckStateInterface_1: bBusy
36121	L_MckStateInterface_1: bDone
36122	L_MckStateInterface_1: bHomingPosAvailable
36123	L_MckStateInterface_1: bHomingDone
36124	L_MckStateInterface_1: bDwellTime
36125	L_MckStateInterface_1: bInTarget
36126	L_MckStateInterface_1: bPosDone
36127	L_PosShaftCtrlInterface_1: bQsp
36128	L_PosShaftCtrlInterface_1: bRsp
36129	L_PosShaftCtrlInterface_1: bTripSet
36130	L_PosShaftCtrlInterface_1: bTripReset
36131	L_JogCtrlExtension_1: bRfgOut
36132	L_JogCtrlExtension_1: bLog1Out
36133	L_JogCtrlExtension_1: bLog2Out
36134	L_Curve_1: bLimit
36135	L_Interpolator_1: bIPulse
36136	L_Interpolator_1: bSignalError
36137	L_MckCtrlInterface_1: bPosSetDataValid
36138	L_Transient_1: bOut
36139	L_Transient_2: bOut

Selection list - digital signals	
36140	L_Transient_3: bOut
36141	L_Transient_4: bOut
36142	L_CalcDiameter_1: bDMaxLimit
36143	L_CalcDiameter_1: bDMinLimit
36144	L_CalcDiameter_1: bWebBreak
36145	L_PhilIntegrator_1: bOvfl32
36146	L_PhilIntegrator_1: bOvfl16
36147	L_PhilIntegrator_1: bInItDone
36148	L_PosCtrlIn_1: bInTarget
36149	L_PosCtrlIn_2: bInTarget
36150	L_SwitchPoint_1: bOut1
36151	L_SwitchPoint_1: bOut2
36152	L_SwitchPoint_1: bOut3
36153	L_SwitchPoint_1: bOut4
36154	L_DFSET_1: bAck
36155	L_DFSET_1: bFollowingErr
36156	L_DFSET_1: bPosOverflow
36157	L_DFRFG_1: bSync
36158	L_DFRFG_1: bFail
36159	L_Curve_2: bLimit
36160	L_Curve_3: bLimit
36161	L_Sequencer_1: bProgramBusy
36162	L_Sequencer_1: bStateReady
36163	L_Sequencer_1: bStateRun
36164	L_Sequencer_1: bStatePause
36165	L_Sequencer_1: bStateBreak
36166	L_Sequencer_1: bStateReset
36167	L_Sequencer_1: bStateDone
36168	L_Sequencer_1: bErrActive
36169	L_Sequencer_1: bWachdogActive
36170	L_Sequencer_1: bErrBranch
36171	L_ConvUnitsToIncr_1: bDataValid
36172	L_ConvUnitsToIncr_2: bDataValid
36173	L_ConvUnitsToIncr_3: bDataValid
36174	L_ConvActPos_1: bPosOverrange
36175	L_ConvActPos_1: bInSetPosition
36176	L_ConvActPos_1: bNegOverrange
36177	L_MFail_1: bActive
36178	L_MFail_1: bNCtrlReset
36179	L_Curve_3: bLimit
36180	L_SwitchPoint_1: bOut5
36181	L_SwitchPoint_1: bOut6
36182	L_SwitchPoint_1: bOut7
36183	L_SwitchPoint_1: bOut8
36184	L_SwitchPointPar_1: bOut1
36185	L_SwitchPointPar_1: bOut2
36186	L_SwitchPointPar_1: bOut3
36187	L_SwitchPointPar_1: bOut4
36188	L_SwitchPointPar_1: bOut5
36189	L_SwitchPointPar_1: bOut6
36190	L_SwitchPointPar_1: bOut7
36191	L_SwitchPointPar_1: bOut8

Selection list - digital signals	
42000	LA_NCtrl_In: bClnh
42001	LA_NCtrl_In: bFailReset
42002	LA_NCtrl_In: bSetQuickstop
42003	LA_NCtrl_In: bSetDCBrake
42004	LA_NCtrl_In: bRFG_Stop
42005	LA_NCtrl_In: bRFG_0
42007	LA_NCtrl_In: bSetSpeedCcw
42008	LA_NCtrl_In: bJogSpeed1
42009	LA_NCtrl_In: bJogSpeed2
42010	LA_NCtrl_In: bJogSpeed4
42011	LA_NCtrl_In: bJogSpeed8
42012	LA_NCtrl_In: bJogRamp1
42013	LA_NCtrl_In: bJogRamp2
42014	LA_NCtrl_In: bJogRamp4
42015	LA_NCtrl_In: bJogRamp8
42017	LA_NCtrl_In: bMPOTInAct
42018	LA_NCtrl_In: bMPOTUp
42019	LA_NCtrl_In: bMPOTDown
42020	LA_NCtrl_In: bMBRKRelease
42021	LA_NCtrl_In: bGPFree1
42022	LA_NCtrl_In: bGPFree2
42023	LA_NCtrl_In: bGPAnalogSwitchSet
42024	LA_NCtrl_In: bGPDigitalDelayIn
42025	LA_NCtrl_In: bGPLogicIn1
42026	LA_NCtrl_In: bGPLogicIn2
42027	LA_NCtrl_In: bGPLogicIn3
42028	LA_NCtrl_In: bGPDFlipFlopInD
42029	LA_NCtrl_In: bGPDFlipFlopInClk
42030	LA_NCtrl_In: bGPDFlipFlopInClr
42031	LA_NCtrl_In: bMPotEnable
42032	LA_NCtrl_In: bPIDEnableInfluenceRamp
42033	LA_NCtrl_In: bPIDIOff
42034	LA_NCtrl_In: bRLQCw
42035	LA_NCtrl_In: bRLQCcw
42041	LA_NCtrl_In: bFreeln1
42042	LA_NCtrl_In: bFreeln2
42043	LA_NCtrl_In: bFreeln3
42044	LA_NCtrl_In: bFreeln4
42045	LA_NCtrl_In: bFreeln5
42046	LA_NCtrl_In: bFreeln6
42047	LA_NCtrl_In: bFreeln7
42048	LA_NCtrl_In: bFreeln8
42100	LA_TabPos_In: bClnh
42101	LA_TabPos_In: bFailReset
42102	LA_TabPos_In: bSetQuickstop
42103	LA_TabPos_In: bSetSpeedCcw
42104	LA_TabPos_In: bJogSpeed1
42105	LA_TabPos_In: bJogSpeed2
42106	LA_TabPos_In: bMPotEnable
42107	LA_TabPos_In: bMPotUp
42108	LA_TabPos_In: bMPotDown
42109	LA_TabPos_In: bMBrakeRelease

Selection list - digital signals	
42110	LA_TabPos_In: bPosCtrlOn
42111	LA_TabPos_In: bLimitSwitchPos
42112	LA_TabPos_In: bLimitSwitchNeg
42113	LA_TabPos_In: bReleaseLimitSwitch
42114	LA_TabPos_In: bManJogPos
42115	LA_TabPos_In: bManJogNeg
42116	LA_TabPos_In: bManEnable2ndSpeed
42117	LA_TabPos_In: bEnableSpeedOverride
42118	LA_TabPos_In: bEnableAccOverride
42119	LA_TabPos_In: bHomeStartStop
42120	LA_TabPos_In: bHomeSetPosition
42121	LA_TabPos_In: bHomeResetPosition
42122	LA_TabPos_In: bHomeMark
42123	LA_TabPos_In: bPosSetProfilePosition
42124	LA_TabPos_In: bPosSetActualPosition
42125	LA_TabPos_In: bPosExecute
42126	LA_TabPos_In: bPosFinishTarget
42127	LA_TabPos_In: bPosDisableFollowProfile
42128	LA_TabPos_In: bPosStop
42129	LA_TabPos_In: bGPAnalogSwitchSet
42130	LA_TabPos_In: bGPDigitalDelayIn
42131	LA_TabPos_In: bGPLogicIn1
42132	LA_TabPos_In: bGPLogicIn2
42133	LA_TabPos_In: bGPLogicIn3
42134	LA_TabPos_In: bGPDFlipFlop_InD
42135	LA_TabPos_In: bGPDFlipFlop_InClk
42136	LA_TabPos_In: bGPDFlipFlop_InClr
42137	LA_TabPos_In: bGPCounter1ClkUp
42138	LA_TabPos_In: bGPCounter1ClkDown
42139	LA_TabPos_In: bGPCounter1Load
42140	LA_TabPos_In: bMckOperationMode_1
42141	LA_TabPos_In: bMckOperationMode_2
42142	LA_TabPos_In: bMckOperationMode_4
42143	LA_TabPos_In: bMckOperationMode_8
42144	LA_TabPos_In: bPosProfileNo_1
42145	LA_TabPos_In: bPosProfileNo_2
42146	LA_TabPos_In: bPosProfileNo_4
42147	LA_TabPos_In: bPosProfileNo_8
42148	LA_TabPos_In: bFreeln1
42149	LA_TabPos_In: bFreeln2
42150	LA_TabPos_In: bFreeln3
42151	LA_TabPos_In: bFreeln4
42152	LA_TabPos_In: bFreeln5
42153	LA_TabPos_In: bFreeln6
42154	LA_TabPos_In: bFreeln7
42155	LA_TabPos_In: bFreeln8
42200	LA_SwitchPos_In: bClnh
42201	LA_SwitchPos_In: bFailReset
42202	LA_SwitchPos_In: bSetQuickstop
42203	LA_SwitchPos_In: bSetDCBrake
42204	LA_SwitchPos_In: bRFG_Stop
42205	LA_SwitchPos_In: bSetSpeedCcw

Selection list - digital signals	
42206	LA_SwitchPos_In: bRLQCw
42207	LA_SwitchPos_In: bRLQCcw
42208	LA_SwitchPos_In: bJogCtrlInputSel1
42209	LA_SwitchPos_In: bJogCtrlInputSel2
42210	LA_SwitchPos_In: bJogCtrlRfgIn
42211	LA_SwitchPos_In: bJogCtrlJog1
42212	LA_SwitchPos_In: bJogCtrlJog2
42213	LA_SwitchPos_In: bJogCtrlSlowDown1
42214	LA_SwitchPos_In: bJogCtrlStop1
42215	LA_SwitchPos_In: bJogCtrlSlowDown2
42216	LA_SwitchPos_In: bJogCtrlStop2
42217	LA_SwitchPos_In: bJogCtrlSlowDown3
42218	LA_SwitchPos_In: bJogCtrlStop3
42219	LA_SwitchPos_In: bJogSpeed4
42220	LA_SwitchPos_In: bJogSpeed8
42221	LA_SwitchPos_In: bJogRamp1
42222	LA_SwitchPos_In: bJogRamp2
42223	LA_SwitchPos_In: bJogRamp4
42224	LA_SwitchPos_In: bJogRamp8
42225	LA_SwitchPos_In: bMBrakeRelease
42226	LA_SwitchPos_In: bGPAnalogSwitchSet
42227	LA_SwitchPos_In: bGPDigitalDelayIn
42228	LA_SwitchPos_In: bGPLogicIn1
42229	LA_SwitchPos_In: bGPLogicIn2
42230	LA_SwitchPos_In: bGPLogicIn3
42231	LA_SwitchPos_In: bGPDFlipFlop_InD
42232	LA_SwitchPos_In: bGPDFlipFlop_InClk
42233	LA_SwitchPos_In: bGPDFlipFlop_InClr
42239	LA_SwitchPos_In: bFreeln1
42240	LA_SwitchPos_In: bFreeln2
42241	LA_SwitchPos_In: bFreeln3
42242	LA_SwitchPos_In: bFreeln4
42243	LA_SwitchPos_In: bFreeln5
42244	LA_SwitchPos_In: bFreeln6
42245	LA_SwitchPos_In: bFreeln7
42246	LA_SwitchPos_In: bFreeln8
42247	LS_MotorInterface: bBrakeChopperActive
42248	LS_MotorInterface: bLimSpeedTorquemodeOn

17.5 Selection list - angle signals

This selection list is relevant for the following configuration parameters:

Parameter	
C00622	System connection list: Angle
C00712	LA_TabPos: phi connection list

Selection list - angle signals	
0	Not connected
1005	LA_NCtrl: dnFreeOut1_p
1006	LA_NCtrl: dnFreeOut2_p
1100	LA_TabPos: dnTargetPos_p
1101	LA_TabPos: dnSetPos_p
1102	LA_TabPos: dnFreeOut1_p
1103	LA_TabPos: dnFreeOut2_p
1104	LA_TabPos: dnPosAct_p
1105	LA_TabPos: dnDeltaPosAct_p
1205	LA_SwitchPos: dnFreeOut1_p
1206	LA_SwitchPos: dnFreeOut2_p
16000	LP_CanIn1: dnIn34_p
16001	LP_CanIn2: dnIn34_p
16002	LP_CanIn3: dnIn34_p
16003	LP_McIn: dnIn34_p
16006	LP_CanIn1: dnIn12_p
16007	LP_CanIn2: dnIn12_p
16008	LP_CanIn3: dnIn12_p
16009	LP_McIn: dnIn56_p
16010	LP_McIn: dnIn78_p
16011	LP_CanIn4: dnIn12_p
16012	LP_CanIn4: dnIn34_p
17000	LS_MultiEncoder: dnPosition_p
17001	LS_Resolver: dnPosition_p
17010	LS_BusEncoder: dnPosition_p
17020	LS_DigitalInput: dnPosIn12_p
17101	LS_TouchProbe: dnTPDigIn1_Position_p
17102	LS_TouchProbe: dnTPDigIn2_Position_p
17103	LS_TouchProbe: dnTPDigIn3_Position_p
17104	LS_TouchProbe: dnTPDigIn4_Position_p
17105	LS_TouchProbe: dnTPDigIn5_Position_p
17106	LS_TouchProbe: dnTPDigIn6_Position_p
17107	LS_TouchProbe: dnTPDigIn7_Position_p
17108	LS_TouchProbe: dnTPEncoder_Position_p
17109	LS_TouchProbe: dnTPResolver_Position_p
17120	LS_RetainData: dnOut1
17121	LS_RetainData: dnOut2
17122	LS_RetainData: dnOut3
17123	LS_RetainData: dnOut4
17130	LS_AxisBusIn: dnLine12
17131	LS_AxisBusIn: dnCas12
17132	LS_AxisBusIn: dnCas34
17133	LS_AxisBusAux: dnAuxIn12

Selection list - angle signals	
17134	LS_AxisBusAux: dnAuxIn34
20000	LS_ParFree_p: dnC474_1_p
20001	LS_ParFree_p: dnC474_2_p
20002	LS_ParFree_p: dnC474_3_p
20003	LS_ParFree_p: dnC474_4_p
20004	LS_ParFree_p: dnC474_5_p
20005	LS_ParFree_p: dnC474_6_p
20006	LS_ParFree_p: dnC474_7_p
20007	LS_ParFree_p: dnC474_8_p
20008	LS_ParFree32: dnC479_1
20009	LS_ParFree32: dnC479_2
20010	LS_ParFree32: dnC479_3
20011	LS_ParFree32: dnC479_4
20012	LS_ParFree32: dnC479_5
20013	LS_ParFree32: dnC479_6
20014	LS_ParFree32: dnC479_7
20015	LS_ParFree32: dnC479_8
20016	LS_ParFreeUnit_1: dnC475_1
20017	LS_ParFreeUnit_1: dnC475_2
20018	LS_ParFreeUnit_1: dnC475_3
20019	LS_ParFreeUnit_1: dnC475_4
20020	LS_ParFreeUnit_1: dnC475_5
20021	LS_ParFreeUnit_1: dnC475_6
20022	LS_ParFreeUnit_1: dnC475_7
20023	LS_ParFreeUnit_1: dnC475_8
20024	LS_ParFreeUnit_1: dnC475_9
20025	LS_ParFreeUnit_1: dnC475_10
20026	LS_ParFreeUnit_1: dnC475_11
20027	LS_ParFreeUnit_1: dnC475_12
20028	LS_ParFreeUnit_1: dnC475_13
20029	LS_ParFreeUnit_1: dnC475_14
20030	LS_ParFreeUnit_1: dnC475_15
20031	LS_ParFreeUnit_1: dnC475_16
20032	LS_ParFreeUnit_2: dnC475_17
20033	LS_ParFreeUnit_2: dnC475_18
20034	LS_ParFreeUnit_2: dnC475_19
20035	LS_ParFreeUnit_2: dnC475_20
20036	LS_ParFreeUnit_2: dnC475_21
20037	LS_ParFreeUnit_2: dnC475_22
20038	LS_ParFreeUnit_2: dnC475_23
20039	LS_ParFreeUnit_2: dnC475_24
20040	LS_ParFreeUnit_2: dnC475_25
20041	LS_ParFreeUnit_2: dnC475_26
20042	LS_ParFreeUnit_2: dnC475_27
20043	LS_ParFreeUnit_2: dnC475_28
20044	LS_ParFreeUnit_2: dnC475_29
20045	LS_ParFreeUnit_2: dnC475_30
20046	LS_ParFreeUnit_2: dnC475_31
20047	LS_ParFreeUnit_2: dnC475_32
32000	LS_MotorInterface: dnMotorPosAct_p

Selection list - angle signals	
32001	LS_MotorInterface: dnMotorDeltaPosAct_p
32200	LS_MotionControlKernel: dnPosTarget_p
32201	LS_MotionControlKernel: dnPosSetValue_p
32202	LS_MotionControlKernel: dnDeltaPos_p
32203	LS_MotionControlKernel: dnMotorRefOffset_p
32204	LS_MotionControlKernel: dnPosSet_p
32205	LS_MotionControlKernel: dnPosSetRelative_p
36040	L_ArithmetikPhi_1: dnOut_p
36046	L_GainOffsetPhiP_1: dnOut_p
36047	L_GainOffsetPhiP_2: dnOut_p
36050	L_LimitPhi_1: dnOut_p
36051	L_LimitPhi_2: dnOut_p
36052	L_LimitPhi_3: dnOut_p
36060	L_OffsetGainPhiP_1: dnOut_p
36061	L_OffsetGainPhiP_2: dnOut_p
36066	L_PhaseIntK_1: dnOut_p
36067	L_PhaseIntK_2: dnOut_p
36070	L_ArithmetikPhi_2: dnOut_p
36071	L_ArithmetikPhi_3: dnOut_p
36072	L_SQrt_1: dnOut_p
36073	L_Mux_1: dnOut_p
36074	L_ConvWordsToDInt_1: dnOut_p
36075	L_ConvWordsToDInt_2: dnOut_p
36076	L_ConvWordsToDInt_3: dnOut_p
36077	L_ConvUnitsToIncr_1: dnOut_p
36078	L_ConvUnitsToIncr_2: dnOut_p
36079	L_ConvUnitsToIncr_3: dnOut_p
36080	L_Interpolator_1: dnPhiOut_p
36081	L_MckCtrlInterface_1: dnPosSetOut_p
36082	L_PhaseDiff_1: dnOut_p
36083	L_PhaseDiff_2: dnOut_p
36086	L_MckStateInterface_1: dnPosOut_p
36087	L_Odometer_1: dnPosOut_1_p
36088	L_Odometer_1: dnPosOut_2_p
36089	L_Odometer_1: dnPosOut_3_p
36090	L_Odometer_1: dnPosOut_4_p
36091	L_Odometer_1: dnPosOut_5_p
36092	L_Odometer_1: dnPosOut_6_p
36093	L_Odometer_1: dnPosOut_7_p
36094	L_Odometer_1: dnPosOut_8_p
36095	L_Odometer_1: dnDeltaPos_12_p
36096	L_Odometer_1: dnDeltaPos_23_p
36097	L_Odometer_1: dnDeltaPos_34_p
36098	L_Odometer_1: dnDeltaPos_45_p
36099	L_Odometer_1: dnDeltaPos_56_p
36100	L_Odometer_1: dnDeltaPos_67_p
36101	L_Odometer_1: dnDeltaPos_78_p
36102	L_Odometer_1: dnDeltaPos_18_p
36103	L_CalcDiameter_1: dnPos_p
36104	L_PhiIntegrator_1: dnOut32_p
36105	L_PosCtrlIn_1: dnPosOut_p
36106	L_PosCtrlIn_2: dnPosOut_p

Selection list - angle signals	
36107	L_DFSET_1: dnPosDiffOut_p
36108	L_DFSET_1: dnPosSetOut_p
36109	L_GearComp_1: dnOut_p
36110	L_ConvAP_1: dnOut_p
36111	L_ConvAP_2: dnOut_p
36112	L_ConvAP_3: dnOut_p
36113	L_ConvPP_1: dnOut_p
36114	L_ConvPP_2: dnOut_p
36115	L_ConvPP_3: dnOut_p
36116	L_SignalSwitch32_1: dnOut
36117	L_SignalSwitch32_2: dnOut
36118	L_SignalSwitch32_3: dnOut
36119	L_CalcDiameter_1: dwOutDiameter
36120	L_ArithmetikPhi_4: dnOut_p
36121	L_ArithmetikPhi_5: dnOut_p
36122	L_ArithmetikPhi_6: dnOut_p
36123	L_PhiDiv_1: dnOut_p
36124	L_PhiAdd_1: dnOut_p
36125	L_PhiAdd_1: dnOut2_p
36126	L_DFSET_1: dnDeltaPos_p
42005	LA_NCtrl_In: dnFreeIn1_p
42006	LA_NCtrl_In: dnFreeIn2_p
42100	LA_TabPos_In: dnPosProfilePosition
42101	LA_TabPos_In: dnFreeIn1_p
42102	LA_TabPos_In: dnFreeIn2_p
42205	LA_SwitchPos_In: dnFreeIn1_p
42206	LA_SwitchPos_In: dnFreeIn2_p

17.6 Table of attributes

The table of attributes contains information required for a communication with the controller via parameters.

How to read the table of attributes:

Column		Meaning	Entry	
Code		Parameter name	Cxxxxx	
Name		Parameter short text (display text)	Text	
Type		Parameter type	Selection list	Value from selection list
			Bit coded	Bit-coded value
			Linear value	Value with setting range
			String	String of digits
Index	dec	Index under which the parameter is addressed. The subindex for array variables corresponds to the Lenze subcode number.	24575 - Lenze code number	Is only required for access via a bus system.
	hex		5FFF _h - Lenze code number	
Data	DS	Data structure	E	Single variable (only one parameter element)
			A	Array variable (several parameter elements)
	DA	Number of array elements (subcodes)	Number	
	DT	Data type	INTEGER_16	2 bytes with sign
			INTEGER_32	4 bytes with sign
			UNSIGNED_8	1 byte without sign
			UNSIGNED_16	2 bytes without sign
			UNSIGNED_32	4 bytes without sign
			VISIBLE_STRING [xx]	ASCII string (with character length xx)
	Factor	Factor for data transmission via a bus system, depending on the number of decimal positions	Factor	1 = no decimal positions 10 = 1 decimal position 100 = 2 decimal positions 1000 = 3 decimal positions 10000 = 4 decimal positions
	CINH	Writing is only possible if the controller is inhibited	CINH	

Code	Name	Type	Index		Data				
			dec	hex	DS	DA	DT	Factor	CINH
C00001	Keypad UserLevel	Selection list	24574	5FFE	A	1	UNSIGNED_8	1	
C00002	Device commands	Selection list	24573	5FFD	A	34	UNSIGNED_8	1	
C00003	Status of the last device command	Selection list	24572	5FFC	E	1	UNSIGNED_8	1	
C00005	Application	Selection list	24570	5FFA	E	1	UNSIGNED_16	1	
C00006	Motor control	Selection list	24569	5FF9	E	1	UNSIGNED_8	1	
C00007	Control mode	Selection list	24568	5FF8	E	1	UNSIGNED_16	1	
C00008	Original application control source	Selection list	24567	5FF7	E	1	UNSIGNED_16	1	
C00010	AIN1: Characteristic	Linear value	24565	5FF5	A	8	INTEGER_16	100	
C00011	Appl.: Reference speed	Linear value	24564	5FF4	E	1	UNSIGNED_16	1	
C00012	Accel. time - main setpoint	Linear value	24563	5FF3	E	1	UNSIGNED_32	1000	
C00013	Decel. time - main setpoint	Linear value	24562	5FF2	E	1	UNSIGNED_32	1000	
C00015	VFC: V/f base frequency	Linear value	24560	5FF0	E	1	UNSIGNED_16	10	
C00016	VFC: Vmin boost	Linear value	24559	5FEF	E	1	UNSIGNED_16	100	
C00018	Switching frequency	Selection list	24557	5FED	E	1	UNSIGNED_8	1	
C00019	Auto-DCB: Threshold	Linear value	24556	5FEC	E	1	UNSIGNED_16	1	
C00020	AIN2: Characteristic	Linear value	24555	5FEB	A	8	INTEGER_16	100	
C00021	Slip comp.	Linear value	24554	5FEA	E	1	INTEGER_16	100	
C00022	Imax in motor mode	Linear value	24553	5FE9	E	1	UNSIGNED_16	100	
Grayed out = display parameter (read access only)									

Code	Name	Type	Index		Data					
			dec	hex	DS	DA	DT	Factor	CINH	
C00023	Imax in generator mode	Linear value	24552	5FE8	E	1	INTEGER_16	100		
C00024	LS_DriveInterface: bNActCompare	Linear value	24551	5FE7	E	1	INTEGER_16	100		
C00026	AINx: Offset	Linear value	24549	5FE5	A	2	INTEGER_16	100		
C00027	AINx: Gain	Linear value	24548	5FE4	A	2	INTEGER_32	10000		
C00028	AINx: Input voltage	Linear value	24547	5FE3	A	2	INTEGER_16	100		
C00029	AINx: Input current	Linear value	24546	5FE2	A	2	INTEGER_16	100		
C00030	LS_DFOut: Const.	Linear value	24545	5FE1	A	1	INTEGER_16	1		
C00033	AINx: Output value	Linear value	24542	5FDE	A	2	INTEGER_16	100		
C00034	AINx: Configuration	Selection list	24541	5FDD	A	2	UNSIGNED_8	1		
C00036	DC braking: Current	Linear value	24539	5FDB	E	1	INTEGER_16	100		
C00039	Fixed setpoint x (L_NSet_1 n-Fix)	Linear value	24536	5FD8	A	15	INTEGER_16	100		
C00050	MCTRL: Speed setpoint	Linear value	24525	5FCD	E	1	INTEGER_32	1		
C00051	MCTRL: Actual speed value	Linear value	24524	5FCC	E	1	INTEGER_32	1		
C00052	Motor voltage	Linear value	24523	5FCB	E	1	UNSIGNED_16	1		
C00053	DC-bus voltage	Linear value	24522	5FCA	E	1	UNSIGNED_16	1		
C00054	Motor current	Linear value	24521	5FC9	E	1	UNSIGNED_16	100		
C00055	Actual values	Linear value	24520	5FC8	A	4	INTEGER_16	1		
C00056	Torque	Linear value	24519	5FC7	A	2	INTEGER_32	100		
C00057	Maximum torque	Linear value	24518	5FC6	E	1	UNSIGNED_32	100		
C00058	Output frequency	Linear value	24517	5FC5	E	1	INTEGER_32	100		
C00059	Appl.: Reference frequency C11	Linear value	24516	5FC4	E	1	UNSIGNED_32	100		
C00060	Motor rotor position	Linear value	24515	5FC3	E	1	UNSIGNED_16	1		
C00061	Heatsink temperature	Linear value	24514	5FC2	E	1	INTEGER_16	1		
C00062	Interior temperature	Linear value	24513	5FC1	A	1	INTEGER_16	1		
C00063	Motor temperature	Linear value	24512	5FC0	A	3	INTEGER_16	1		
C00064	Device utilisation (Ixt)	Linear value	24511	5FBF	A	3	INTEGER_16	100		
C00065	Supply voltage 24V	Linear value	24510	5FBE	E	1	INTEGER_16	10		
C00066	Thermal motor load (I*xt)	Linear value	24509	5FBD	E	1	INTEGER_16	100		
C00070	Vp speed controller	Linear value	24505	5FB9	A	3	UNSIGNED_16	100		
C00071	Ti speed controller	Linear value	24504	5FB8	A	3	UNSIGNED_16	10		
C00072	SC: Tdn speed controller	Linear value	24503	5FB7	E	1	UNSIGNED_16	100		
C00073	Imax/M controller gain	Linear value	24502	5FB6	A	2	UNSIGNED_16	100		
C00074	Reset time Imax/M controller	Linear value	24501	5FB5	A	2	UNSIGNED_16	1		
C00075	Vp current controller	Linear value	24500	5FB4	E	1	UNSIGNED_16	100		
C00076	Ti current controller	Linear value	24499	5FB3	E	1	UNSIGNED_16	100		
C00077	SC: Vp field controller	Linear value	24498	5FB2	E	1	UNSIGNED_16	100		
C00078	SC: Tn field controller	Linear value	24497	5FB1	E	1	UNSIGNED_16	10		
C00079	SC: Settings	Selection list	24496	5FB0	A	4	UNSIGNED_8	1		
C00080	Override point of field weakening	Linear value	24495	5FAF	E	1	INTEGER_16	1		
C00081	Rated motor power	Linear value	24494	5FAE	E	1	UNSIGNED_16	100		
C00082	Motor rotor resistance	Linear value	24493	5FAD	E	1	UNSIGNED_32	1		
C00083	Motor rotor time constant	Linear value	24492	5FAC	E	1	UNSIGNED_16	1		
C00084	Motor stator resistance	Linear value	24491	5FAB	E	1	UNSIGNED_32	1		
C00085	Motor stator leakage inductance	Linear value	24490	5FAA	E	1	UNSIGNED_16	100		
C00087	Rated motor speed	Linear value	24488	5FA8	E	1	UNSIGNED_16	1		
C00088	Rated motor current	Linear value	24487	5FA7	E	1	UNSIGNED_16	100		
C00089	Rated motor frequency	Linear value	24486	5FA6	E	1	UNSIGNED_16	1		
C00090	Rated motor voltage	Linear value	24485	5FA5	E	1	UNSIGNED_16	1		
C00091	Motor cosine phi	Linear value	24484	5FA4	E	1	UNSIGNED_8	100		
C00092	Motor magnetising inductance	Linear value	24483	5FA3	E	1	UNSIGNED_16	10		
Grayed out = display parameter (read access only)										

Code	Name	Type	Index		Data					
			dec	hex	DS	DA	DT	Factor	CINH	
C00093	Power section ID	Linear value	24482	5FA2	E	1	UNSIGNED_16	1		
C00095	Motor magnetising current	Linear value	24480	5FA0	E	1	UNSIGNED_16	100		
C00097	Rated motor torque	Linear value	24478	5F9E	E	1	UNSIGNED_32	100		
C00098	Rated device current	Linear value	24477	5F9D	E	1	UNSIGNED_16	10		
C00099	Firmware version	String	24476	5F9C	E	1	VISIBLE_STRING [12]			
C00100	Firmware version	Linear value	24475	5F9B	A	4	UNSIGNED_8	1		
C00101	Add. acceleration time x	Linear value	24474	5F9A	A	15	UNSIGNED_32	1000		
C00103	Add. deceleration time x	Linear value	24472	5F98	A	15	UNSIGNED_32	1000		
C00104	Quick stop setting	Bit coded	24471	5F97	A	1	UNSIGNED_16	1		
C00105	Decel. time - quick stop	Linear value	24470	5F96	E	1	UNSIGNED_32	1000		
C00106	Auto-DCB: Hold time	Linear value	24469	5F95	E	1	UNSIGNED_32	1000		
C00107	DC braking: Hold time	Linear value	24468	5F94	E	1	UNSIGNED_32	1000		
C00114	DigInX: Inversion	Bit coded	24461	5F8D	E	1	UNSIGNED_16	1		
C00115	DI 1/2 & 6/7: Function	Selection list	24460	5F8C	A	2	UNSIGNED_8	1		
C00117	Status of brake output BD	Selection list	24458	5F8A	E	1	UNSIGNED_8	1		
C00118	DigOutX: Inversion	Bit coded	24457	5F89	E	1	UNSIGNED_8	1		
C00120	Setting of motor overload (I²xt)	Linear value	24455	5F87	E	1	INTEGER_16	100		
C00121	Motor temp. warning threshold	Linear value	24454	5F86	A	2	UNSIGNED_16	1		
C00122	Initial value motor overload (I²xt)	Linear value	24453	5F85	A	1	UNSIGNED_16	100		
C00123	Device utilisat. threshold (Ixt)	Linear value	24452	5F84	E	1	INTEGER_16	100		
C00129	Brake resistance value	Linear value	24446	5F7E	E	1	UNSIGNED_16	10		
C00130	Rated brake resistor power	Linear value	24445	5F7D	E	1	UNSIGNED_16	1		
C00131	Thermal capacity - brake resistor	Linear value	24444	5F7C	E	1	UNSIGNED_16	10		
C00133	Brake resistor utilisation	Linear value	24442	5F7A	E	1	UNSIGNED_16	1		
C00134	L_NSet_1: Ramp smoothing	Selection list	24441	5F79	E	1	UNSIGNED_8	1		
C00136	Communication control words	Bit coded	24439	5F77	A	2	UNSIGNED_16	1		
C00137	Device status	Selection list	24438	5F76	E	1	UNSIGNED_16	1		
C00138	Internal control signals	Bit coded	24437	5F75	A	3	UNSIGNED_16	1		
C00142	Auto-start option	Bit coded	24433	5F71	E	1	UNSIGNED_8	1		
C00144	Thermal switching frequency reduction	Selection list	24431	5F6F	E	1	UNSIGNED_8	1		
C00148	LS_DriveInterface: Error message config.	Bit coded	24427	5F6B	E	1	UNSIGNED_16	1		
C00150	Status word	Bit coded	24425	5F69	E	1	UNSIGNED_16	1		
C00155	Extended status word	Bit coded	24420	5F64	E	1	UNSIGNED_16	1		
C00158	Cause of controller inhibit	Bit coded	24417	5F61	E	1	UNSIGNED_16	1		
C00159	Cause of quick stop QSP	Bit coded	24416	5F60	E	1	UNSIGNED_16	1		
C00160	Status determining error (16-bit)	Linear value	24415	5F5F	A	1	UNSIGNED_16	1		
C00161	LS_SetError_x: Error number	Linear value	24414	5F5E	A	8	UNSIGNED_16	1		
C00162	Error number masked	Linear value	24413	5F5D	A	1	UNSIGNED_32	1		
C00163	Logbook - binary elements	Selection list	24412	5F5C	A	2	UNSIGNED_16	1		
C00164	Logbook - analog elements	Selection list	24411	5F5B	A	1	UNSIGNED_16	1		
C00165	Error information	String	24410	5F5A	A	2	VISIBLE_STRING [14]			
C00166	Error information text	String	24409	5F59	A	6	VISIBLE_STRING [31]			
C00168	Status determining error	Linear value	24407	5F57	E	1	UNSIGNED_32	1		
C00169	Logbook setting	Bit coded	24406	5F56	E	1	UNSIGNED_16	1		
C00170	Current error	Linear value	24405	5F55	E	1	UNSIGNED_32	1		
C00173	Mains voltage	Selection list	24402	5F52	E	1	UNSIGNED_8	1	CINH	
C00174	Reduc. brake chopper threshold	Linear value	24401	5F51	E	1	UNSIGNED_8	1		
C00175	Brake energy management	Selection list	24400	5F50	E	1	UNSIGNED_8	1	CINH	
C00177	Switching cycles	Linear value	24398	5F4E	A	8	UNSIGNED_32	1		
C00178	Elapsed-hour meter	Linear value	24397	5F4D	E	1	UNSIGNED_32	1		
Grayed out = display parameter (read access only)										

Code	Name	Type	Index		Data					
			dec	hex	DS	DA	DT	Factor	CINH	
C00179	Power-on time meter	Linear value	24396	5F4C	E	1	UNSIGNED_32	1		
C00180	Running time	Linear value	24395	5F4B	A	3	UNSIGNED_32	1		
C00181	Time settings	Linear value	24394	5F4A	A	1	UNSIGNED_16	1		
C00182	L_NSet_1: S-ramp time PT1	Linear value	24393	5F49	E	1	INTEGER_16	100		
C00184	AutoFailReset repetition time	Linear value	24391	5F47	E	1	UNSIGNED_16	1		
C00185	AutoFailReset residual runtime	Linear value	24390	5F46	E	1	UNSIGNED_16	1		
C00186	Max. number of AutoFailReset processes	Linear value	24389	5F45	E	1	UNSIGNED_8	1		
C00187	Current AutoFailReset processes	Linear value	24388	5F44	E	1	UNSIGNED_8	1		
C00188	AutoFailReset configuration	Selection list	24387	5F43	E	1	UNSIGNED_8	1		
C00189	Resp. to too frequent AutoFailReset	Selection list	24386	5F42	E	1	UNSIGNED_8	1		
C00190	L_NSet_1: Setpoint arithmetic	Selection list	24385	5F41	E	1	UNSIGNED_8	1		
C00191	Logbook access index User	Linear value	24384	5F40	A	1	UNSIGNED_8	1		
C00192	Logbook data User	String	24383	5F3F	A	1	OCTET_STRING [32]			
C00193	Logbook element User	Linear value	24382	5F3E	A	6	UNSIGNED_32	1		
C00199	Description data	String	24376	5F38	A	5	VISIBLE_STRING [32]			
C00200	Firmware product type	String	24375	5F37	E	1	VISIBLE_STRING [19]			
C00201	Firmware	String	24374	5F36	A	9	VISIBLE_STRING [22]			
C00203	Product type code	String	24372	5F34	A	9	VISIBLE_STRING [24]			
C00204	Serial number	String	24371	5F33	A	9	VISIBLE_STRING [24]			
C00219	Identity	Linear value	24356	5F24	A	4	UNSIGNED_32	1		
C00220	L_NSet_1: Acceleration time - add. setpoint	Linear value	24355	5F23	E	1	UNSIGNED_32	1000		
C00221	L_NSet_1: Deceleration time - add. setpoint	Linear value	24354	5F22	E	1	UNSIGNED_32	1000		
C00222	L_PCTRL_1: Vp	Linear value	24353	5F21	E	1	INTEGER_16	10		
C00223	L_PCTRL_1: Tn	Linear value	24352	5F20	E	1	UNSIGNED_16	1		
C00224	L_PCTRL_1: Kd	Linear value	24351	5F1F	E	1	UNSIGNED_16	10		
C00225	L_PCTRL_1: MaxLimit	Linear value	24350	5F1E	E	1	INTEGER_16	100		
C00226	L_PCTRL_1: MinLimit	Linear value	24349	5F1D	E	1	INTEGER_16	100		
C00227	L_PCTRL_1: Acceleration time	Linear value	24348	5F1C	E	1	UNSIGNED_32	1000		
C00228	L_PCTRL_1: Deceleration time	Linear value	24347	5F1B	E	1	UNSIGNED_32	1000		
C00231	L_PCTRL_1: Operating range	Linear value	24344	5F18	A	4	INTEGER_16	100		
C00233	L_PCTRL_1: Root function	Selection list	24342	5F16	E	1	UNSIGNED_8	1		
C00234	Oscillation damping influence	Linear value	24341	5F15	E	1	UNSIGNED_16	100		
C00235	Oscillation damping filter time	Linear value	24340	5F14	E	1	UNSIGNED_8	1		
C00236	Oscillation damping field weakening	Linear value	24339	5F13	E	1	UNSIGNED_8	1		
C00241	L_NSet_1: Hyst. NSet reached	Linear value	24334	5F0E	E	1	INTEGER_16	100		
C00242	L_PCTRL_1: Operating mode	Selection list	24333	5F0D	E	1	UNSIGNED_8	1		
C00243	L_PCTRL_1: Accel. time influence	Linear value	24332	5F0C	E	1	UNSIGNED_32	1000		
C00244	L_PCTRL_1: Deceleration time influence	Linear value	24331	5F0B	E	1	UNSIGNED_32	1000		
C00245	L_PCTRL_1: PID output value	Linear value	24330	5F0A	E	1	INTEGER_16	100		
C00246	L_PCTRL_1: nAct_a internal	Linear value	24329	5F09	E	1	INTEGER_16	100		
C00247	L_PCTRL_1: Window setpoint reached	Linear value	24328	5F08	E	1	INTEGER_16	100		
C00249	L_PT1_1: Time constant	Linear value	24326	5F06	E	1	UNSIGNED_16	1		
C00250	L_PT1 2-3: Time constant	Linear value	24325	5F05	A	2	INTEGER_16	1		
C00251	L_DT1_1: Time constant	Linear value	24324	5F04	E	1	INTEGER_16	1		
C00252	L_DT1_1: Gain	Linear value	24323	5F03	E	1	INTEGER_16	100		
C00253	L_DT1_1: Sensitivity	Selection list	24322	5F02	E	1	UNSIGNED_8	1		
C00254	Kp position controller	Linear value	24321	5F01	E	1	UNSIGNED_16	100		
C00270	SC: Freq. current setpoint filter	Linear value	24305	5EF1	E	1	UNSIGNED_16	10		
C00271	SC: Current setpoint filter width	Linear value	24304	5EF0	E	1	UNSIGNED_16	10		
Grayed out = display parameter (read access only)										

Code	Name	Type	Index		Data					
			dec	hex	DS	DA	DT	Factor	CINH	
C00272	SC: Current setpoint filter depth	Linear value	24303	5EEF	E	1	UNSIGNED_16		1	
C00273	Motor moment of inertia	Linear value	24302	5EEE	E	1	UNSIGNED_32		100	
C00274	SC: Max. change in acceleration	Linear value	24301	5EED	E	1	UNSIGNED_16		10	
C00275	Setpoint feedforward control filtering	Linear value	24300	5EEC	E	1	UNSIGNED_16		10	
C00276	SC: max. output voltage	Linear value	24299	5EEB	E	1	UNSIGNED_8		1	
C00280	SC: Filter time const. DC detection	Linear value	24295	5EE7	E	1	UNSIGNED_16		1	
C00312	System runtimes	Linear value	24263	5EC7	A	1	UNSIGNED_32		1000	
C00321	Main program runtime	Linear value	24254	5EBE	A	2	UNSIGNED_16		1	
C00322	Transmission mode CAN TxPDOs	Linear value	24253	5EBD	A	3	UNSIGNED_8		1	
C00323	Transmission mode CAN Rx PDOs	Linear value	24252	5EBC	A	3	UNSIGNED_8		1	
C00324	CAN transmit blocking time	Linear value	24251	5EBB	A	4	UNSIGNED_16		1	
C00338	L_Arithmetik_1: Function	Selection list	24237	5EAD	E	1	UNSIGNED_8		1	
C00339	L_Arithmetik_2: Function	Selection list	24236	5EAC	E	1	UNSIGNED_8		1	
C00341	CAN management - error configuration	Bit coded	24234	5EAA	E	1	UNSIGNED_16		1	
C00342	CAN decoupling PDOInOut	Bit coded	24233	5EA9	A	2	UNSIGNED_16		1	
C00343	LP_CanIn decoupling value	Linear value	24232	5EA8	A	12	UNSIGNED_16		1	
C00344	LP_CanOut decoupling value	Linear value	24231	5EA7	A	12	UNSIGNED_16		1	
C00345	CAN error status	Selection list	24230	5EA6	E	1	UNSIGNED_8		1	
C00347	CAN status HeartBeat producer	Selection list	24228	5EA4	A	15	UNSIGNED_8		1	
C00349	CAN setting - DIP switch	Bit coded	24226	5EA2	E	1	UNSIGNED_16		1	
C00350	CAN node address	Linear value	24225	5EA1	E	1	UNSIGNED_8		1	
C00351	CAN baud rate	Selection list	24224	5EA0	E	1	UNSIGNED_8		1	
C00352	CAN slave/master	Selection list	24223	5E9F	E	1	UNSIGNED_8		1	
C00353	CAN IN/OUT COBID source	Selection list	24222	5E9E	A	3	UNSIGNED_8		1	
C00354	COBID	Bit coded	24221	5E9D	A	6	UNSIGNED_32		1	
C00355	Active COBID	Linear value	24220	5E9C	A	6	UNSIGNED_16		1	
C00356	CAN time settings	Linear value	24219	5E9B	A	5	UNSIGNED_16		1	
C00357	CAN monitoring times	Linear value	24218	5E9A	A	3	UNSIGNED_16		1	
C00358	CANx_OUT data length	Linear value	24217	5E99	A	3	UNSIGNED_8		1	
C00359	CAN status	Selection list	24216	5E98	E	1	UNSIGNED_8		1	
C00360	CAN telegram counter	Linear value	24215	5E97	A	12	UNSIGNED_16		1	
C00364	CAN MessageError	Selection list	24211	5E93	E	1	UNSIGNED_8		1	
C00366	Number of CAN SDO channels	Selection list	24209	5E91	E	1	UNSIGNED_8		1	
C00367	CAN SYNC Rx identifier	Bit coded	24208	5E90	E	1	UNSIGNED_16		1	
C00368	CAN SYNC Tx identifier	Bit coded	24207	5E8F	E	1	UNSIGNED_16		1	
C00369	CAN sync transmission cycle time	Linear value	24206	5E8E	E	1	UNSIGNED_16		1	
C00370	SyncTxRxTimes	Linear value	24205	5E8D	A	2	INTEGER_16		1	
C00371	CAN ErrorCode	Linear value	24204	5E8C	A	1	UNSIGNED_16		1	
C00372	CAN_Tx_Rx_Error	Linear value	24203	5E8B	A	4	UNSIGNED_8		1	
C00381	CAN Heartbeat producer time	Linear value	24194	5E82	E	1	UNSIGNED_16		1	
C00385	CAN node addr. HeartBeat producer	Linear value	24190	5E7E	A	15	UNSIGNED_8		1	
C00386	CAN HeartBeat-ConsumerTime	Linear value	24189	5E7D	A	15	UNSIGNED_16		1	
C00387	CAN-GatewayAddr	Linear value	24188	5E7C	A	1	UNSIGNED_8		1	
C00400	LS_PulseGenerator	Linear value	24175	5E6F	A	3	UNSIGNED_16		1	
C00401	CANxInOut: Inversion	Bit coded	24174	5E6E	A	6	UNSIGNED_16		1	
C00407	LP_CanIn mapping	Linear value	24168	5E68	A	6	UNSIGNED_32		1	
C00408	LP_CanIn mapping selection	Selection list	24167	5E67	A	3	UNSIGNED_8		1	
C00409	LP_CanIn mapping	Linear value	24166	5E66	A	12	UNSIGNED_16		1	
C00410	L_SignalMonitor_a: Signal sources	Selection list	24165	5E65	A	4	UNSIGNED_16		1	
C00411	L_SignalMonitor_b: Signal sources	Selection list	24164	5E64	A	4	UNSIGNED_16		1	
Grayed out = display parameter (read access only)										

Code	Name	Type	Index		Data				
			dec	hex	DS	DA	DT	Factor	CINH
C00412	L_SignalMonitor_b: Inversion	Bit coded	24163	5E63	E	1	UNSIGNED_8	1	
C00413	L_SignalMonitor_a: Offs./gain	Linear value	24162	5E62	A	8	INTEGER_16	100	
C00417	Deactivate resolver error comp.	Selection list	24158	5E5E	E	1	UNSIGNED_8	1	
C00420	Number of encoder increments	Linear value	24155	5E5B	A	3	UNSIGNED_16	1	
C00421	LS_MultiEncoder: Supply voltage	Linear value	24154	5E5A	E	1	UNSIGNED_16	10	
C00422	LS_MultiEncoder: Encoder type	Selection list	24153	5E59	E	1	UNSIGNED_8	1	CINH
C00423	DOx: Delay times	Linear value	24152	5E58	A	10	UNSIGNED_16	1000	
C00424	Pulse form TTL encoder	Selection list	24151	5E57	E	1	UNSIGNED_8	1	
C00425	Encoder scanning time	Selection list	24150	5E56	A	2	UNSIGNED_8	1	CINH
C00426	SSI encoder: Data bits	Linear value	24149	5E55	A	9	UNSIGNED_8	1	CINH
C00427	SSI encoder: Bit rate	Selection list	24148	5E54	E	1	UNSIGNED_8	1	CINH
C00428	SSI encoder: Coding	Selection list	24147	5E53	E	1	UNSIGNED_8	1	CINH
C00430	LS_MultiEncoder: Max. initialization time	Linear value	24145	5E51	A	1	UNSIGNED_16	1	CINH
C00431	LS_MultiEncoder: bFail selection	Bit coded	24144	5E50	A	1	UNSIGNED_16	1	
C00432	LS_Resolver: bFail selection	Bit coded	24143	5E4F	A	1	UNSIGNED_16	1	
C00434	OxU/I: Gain	Linear value	24141	5E4D	A	4	INTEGER_16	100	
C00435	OxU/I: Offset	Linear value	24140	5E4C	A	4	INTEGER_16	100	
C00436	OxU: Voltage	Linear value	24139	5E4B	A	2	INTEGER_16	100	
C00437	OxI: Current	Linear value	24138	5E4A	A	2	INTEGER_32	1000	
C00439	OxU/I: Input value	Linear value	24136	5E48	A	4	INTEGER_16	100	
C00440	LS_AnalogIn1: PT1 time constant	Linear value	24135	5E47	A	2	UNSIGNED_16	1	
C00441	Decoupling AnalogOut	Bit coded	24134	5E46	E	1	UNSIGNED_16	1	
C00442	AOutx: Decoupling value	Linear value	24133	5E45	A	4	INTEGER_16	100	
C00443	Dlx: Level	Bit coded	24132	5E44	A	2	UNSIGNED_16	1	
C00444	DOx: Level	Bit coded	24131	5E43	A	2	UNSIGNED_16	1	
C00445	FreqInxx_nOut_v	Linear value	24130	5E42	A	2	INTEGER_16	1	
C00446	FreqInxx_nOut_a	Linear value	24129	5E41	A	2	INTEGER_16	100	
C00447	DigOut decoupling	Bit coded	24128	5E40	E	1	UNSIGNED_16	1	
C00448	DigOut decoupling value	Bit coded	24127	5E3F	E	1	UNSIGNED_16	1	
C00449	FreqInxx_dnOut_p	Linear value	24126	5E3E	A	1	INTEGER_32	1	
C00451	LS_MultiEncoder: Information bFail	Bit coded	24124	5E3C	A	1	UNSIGNED_16	1	
C00452	LS_Resolver: Information bFail	Bit coded	24123	5E3B	A	1	UNSIGNED_16	1	
C00453	Keypad: Default manual jog	Linear value	24122	5E3A	A	2	UNSIGNED_32	1000	
C00461	Remote: Acceleration/deceleration time	Linear value	24114	5E32	A	1	UNSIGNED_32	1000	
C00462	Remote: Control	Linear value	24113	5E31	A	2	UNSIGNED_16	1	
C00463	Remote: MCK control	Bit coded	24112	5E30	A	1	UNSIGNED_32	1	
C00464	Remote: Monitoring timeout	Linear value	24111	5E2F	A	1	UNSIGNED_16	1	
C00465	Keypad: Time-out welcome screen	Selection list	24110	5E2E	E	1	INTEGER_32	1	
C00466	Keypad: Default parameter	Linear value	24109	5E2D	E	1	INTEGER_32	1	
C00467	Keypad: Default welcome screen	Selection list	24108	5E2C	E	1	INTEGER_32	1	
C00469	Keypad: Fct. STOP key	Selection list	24106	5E2A	E	1	INTEGER_32	1	CINH
C00470	LS_ParFree_b	Selection list	24105	5E29	A	32	UNSIGNED_8	1	
C00471	LS_ParFree	Bit coded	24104	5E28	A	32	UNSIGNED_16	1	
C00472	LS_ParFree_a	Linear value	24103	5E27	A	16	INTEGER_16	100	
C00473	LS_ParFree_v	Linear value	24102	5E26	A	8	INTEGER_16	1	
C00474	LS_ParFree_p	Linear value	24101	5E25	A	8	INTEGER_32	1	
C00475	LS_ParFreeUnit_1_2	Linear value	24100	5E24	A	32	INTEGER_32	10000	
C00476	LS_ParFree_a_2	Linear value	24099	5E23	A	16	INTEGER_16	100	
C00477	LS_ParFree_2	Bit coded	24098	5E22	A	32	UNSIGNED_16	1	
C00478	LS_ParFree_v_2	Linear value	24097	5E21	A	8	INTEGER_16	1	
Grayed out = display parameter (read access only)									

Code	Name	Type	Index		Data				
			dec	hex	DS	DA	DT	Factor	CINH
C00479	LS_ParFree32	Linear value	24096	5E20	A	8	INTEGER_32	1	
C00480	LS_DisFree_b	Bit coded	24095	5E1F	E	1	UNSIGNED_16	1	
C00481	LS_DisFree	Bit coded	24094	5E1E	A	8	UNSIGNED_16	1	
C00482	LS_DisFree_a	Linear value	24093	5E1D	A	8	INTEGER_16	100	
C00483	LS_DisFree_p	Linear value	24092	5E1C	A	8	INTEGER_32	1	
C00484	Application units: Offset	Linear value	24091	5E1B	A	4	INTEGER_16	100	
C00485	Application units: Display factor	Linear value	24090	5E1A	A	4	INTEGER_32	10000	
C00486	Application units: Text	String	24089	5E19	A	4	VISIBLE_STRING [7]		
C00487	Application units	Linear value	24088	5E18	A	4	INTEGER_32	100	
C00488	L_JogCtrlEdgeDetect_1	Selection list	24087	5E17	A	6	UNSIGNED_8	1	
C00490	Position encoder selection	Selection list	24085	5E15	E	1	UNSIGNED_8	1	
C00491	Hiperface messages	Linear value	24084	5E14	A	4	UNSIGNED_8	1	
C00492	Hiperface: Detected TypCode	Linear value	24083	5E13	E	1	UNSIGNED_8	1	
C00493	Hiperface: TypCode	Linear value	24082	5E12	E	1	UNSIGNED_8	1	
C00494	Hiperface: Resolutions	Linear value	24081	5E11	A	2	UNSIGNED_32	1	
C00495	Speed sensor selection	Selection list	24080	5E10	E	1	UNSIGNED_8	1	
C00496	Encoder evaluation method DigIn12	Selection list	24079	5E0F	E	1	UNSIGNED_8	1	CINH
C00497	Filter time constant	Linear value	24078	5E0E	A	4	UNSIGNED_16	10	
C00498	Open-circuit monitoring	Selection list	24077	5E0D	A	1	UNSIGNED_8	1	
C00499	Hiperface: Settings	Bit coded	24076	5E0C	A	1	UNSIGNED_16	1	
C00505	Password data	String	24070	5E06	A	3	VISIBLE_STRING [16]		
C00507	Current password protection	Bit coded	24068	5E04	A	1	UNSIGNED_16	1	
C00517	User menu	Linear value	24058	5DFA	A	32	INTEGER_32	1000	
C00540	LS_DFOut: Function	Selection list	24035	5DE3	E	1	UNSIGNED_8	1	
C00545	LS_DFOut: Angular offset	Linear value	24030	5DDE	A	1	INTEGER_32	1	
C00560	Fan switching status	Selection list	24015	5DCF	A	2	UNSIGNED_8	1	
C00561	Failure indication	Selection list	24014	5DCE	A	5	UNSIGNED_8	1	
C00565	Resp. to mains phase failure	Selection list	24010	5DCA	E	1	UNSIGNED_8	1	
C00566	Resp. to fan failure	Selection list	24009	5DC9	E	1	UNSIGNED_8	1	
C00567	Resp. to speed controller limited	Selection list	24008	5DC8	E	1	UNSIGNED_8	1	
C00569	Resp. to peak current	Selection list	24006	5DC6	A	1	UNSIGNED_8	1	
C00570	Resp. to controller limitations	Selection list	24005	5DC5	A	4	UNSIGNED_8	1	
C00571	Resp. to wrong controller setting	Selection list	24004	5DC4	A	2	UNSIGNED_8	1	
C00572	Brake resistor overload threshold	Linear value	24003	5DC3	E	1	UNSIGNED_8	1	
C00574	Resp. to brake resist. overtemp.	Selection list	24001	5DC1	E	1	UNSIGNED_8	1	
C00576	SC: Optimisation of field feedforward control	Linear value	23999	5DBF	E	1	UNSIGNED_16	1	
C00577	SC: Vp field weakening controller	Linear value	23998	5DBE	E	1	UNSIGNED_16	10000	
C00578	SC: Tn field weakening controller	Linear value	23997	5DBD	E	1	UNSIGNED_16	10	
C00579	Resp. to max. speed/output freq. reached	Selection list	23996	5DBC	E	1	UNSIGNED_8	1	
C00580	Resp. to operating system error	Selection list	23995	5DBB	A	1	UNSIGNED_8	1	
C00581	Resp. to LS_SetError_x	Selection list	23994	5DBA	A	8	UNSIGNED_8	1	
C00582	Resp. to heatsink temp.> shutdown temp. -5°C	Selection list	23993	5DB9	E	1	UNSIGNED_8	1	
C00583	Resp. to motor temperature KTY	Selection list	23992	5DB8	A	6	UNSIGNED_8	1	
C00585	Resp. to motor overtemp. PTC	Selection list	23990	5DB6	E	1	UNSIGNED_8	1	
C00586	Resp. open circuit HTL encoder	Selection list	23989	5DB5	E	1	UNSIGNED_8	1	
C00588	Resp. to max. speed at switching freq.	Selection list	23987	5DB3	E	1	UNSIGNED_8	1	
C00590	Resp. to switch. frequency red.	Selection list	23985	5DB1	E	1	UNSIGNED_8	1	
C00591	Reakt. Achsbusfehler	Selection list	23984	5DB0	A	2	UNSIGNED_8	1	
C00592	Resp. to CAN bus connection	Selection list	23983	5DAF	A	5	UNSIGNED_8	1	
Grayed out = display parameter (read access only)									

Code	Name	Type	Index		Data				
			dec	hex	DS	DA	DT	Factor	CINH
C00593	Resp. to CANx_IN monitoring	Selection list	23982	5DAE	A	3	UNSIGNED_8	1	
C00594	Resp. to control word error	Selection list	23981	5DAD	A	2	UNSIGNED_8	1	
C00595	MCK: Resp. to MCK error	Selection list	23980	5DAC	A	15	UNSIGNED_8	1	
C00597	Resp. to motor phase failure	Selection list	23978	5DAA	E	1	UNSIGNED_8	1	
C00598	Resp. to open circuit AlNx	Selection list	23977	5DA9	A	2	UNSIGNED_8	1	
C00599	Motor phase failure threshold	Linear value	23976	5DA8	E	1	INTEGER_16	100	
C00600	Resp. to DC bus voltage	Selection list	23975	5DA7	A	1	UNSIGNED_8	1	
C00601	Delayed resp. to fault: DC bus overvoltage	Linear value	23974	5DA6	A	1	UNSIGNED_16	1000	
C00602	Resp. to earth fault	Selection list	23973	5DA5	E	1	UNSIGNED_8	1	
C00603	Resp. to feedback	Selection list	23972	5DA4	A	7	UNSIGNED_8	1	
C00604	Resp. to device overload (Ixt)	Selection list	23971	5DA3	E	1	UNSIGNED_8	1	
C00606	Resp. to motor overload (I*xt)	Selection list	23969	5DA1	E	1	UNSIGNED_8	1	
C00607	Resp. to max. freq. feedb. DIG12/67	Selection list	23968	5DA0	E	1	UNSIGNED_8	1	
C00608	Resp. to maximum torque	Selection list	23967	5D9F	E	1	UNSIGNED_8	1	
C00609	Resp. to maximum current	Selection list	23966	5D9E	E	1	UNSIGNED_8	1	
C00620	System connection list: 16-bit	Selection list	23955	5D93	A	107	UNSIGNED_16	1	
C00621	System connection list: Bool	Selection list	23954	5D92	A	183	UNSIGNED_16	1	
C00622	System connection list: Angle	Selection list	23953	5D91	A	24	UNSIGNED_16	1	
C00630	L_Limit 1-2: Min/Max	Linear value	23945	5D89	A	4	INTEGER_16	100	
C00631	L_LimitPhi 1-3: Min/Max	Linear value	23944	5D88	A	6	INTEGER_32	1	
C00632	L_NSet_1: Max. skip freq.	Linear value	23943	5D87	A	3	INTEGER_16	100	
C00633	L_NSet_1: Min. skip freq.	Linear value	23942	5D86	A	3	INTEGER_16	100	
C00634	L_NSet_1: wState	Bit coded	23941	5D85	E	1	UNSIGNED_16	1	
C00635	L_NSet_1: nMaxLimit	Linear value	23940	5D84	E	1	INTEGER_16	100	
C00636	L_NSet_1: nMinLimit	Linear value	23939	5D83	E	1	INTEGER_16	100	
C00637	L_NSet_1: Output blocking zones	Linear value	23938	5D82	E	1	INTEGER_16	100	
C00638	L_NSet_1: Output ramp rounding	Linear value	23937	5D81	E	1	INTEGER_16	100	
C00639	L_NSet_1: Output add.value	Linear value	23936	5D80	E	1	INTEGER_16	100	
C00640	L_NSet_1: nNOut_a	Linear value	23935	5D7F	E	1	INTEGER_16	100	
C00643	Resp. to PLI monitoring	Selection list	23932	5D7C	A	1	UNSIGNED_8	1	
C00644	PLI traversing direction	Selection list	23931	5D7B	A	1	UNSIGNED_8	1	
C00645	PLI max. permissible deflection	Linear value	23930	5D7A	A	2	INTEGER_16	10	
C00646	PLI current amplitude	Linear value	23929	5D79	A	2	UNSIGNED_16	1	
C00647	PLI ramp time	Linear value	23928	5D78	A	2	UNSIGNED_16	1	
C00650	L_Arithmetik 3-5: Function	Selection list	23925	5D75	A	3	UNSIGNED_8	1	
C00653	Sensibility - Setpoint feedforward control	Selection list	23922	5D72	A	1	UNSIGNED_8	1	
C00654	Source of diff. setpoint feedforward control	Selection list	23921	5D71	A	1	UNSIGNED_8	1	
C00660	L_FixSet_a_1: Analog values	Linear value	23915	5D6B	A	16	INTEGER_16	100	
C00661	L_FixSet_w_1: Fixed values	Linear value	23914	5D6A	A	16	UNSIGNED_16	1	
C00662	L_FixSet_w_2: Fixed values	Linear value	23913	5D69	A	16	UNSIGNED_16	1	
C00670	L_OffsetGainP_1: Gain	Linear value	23905	5D61	E	1	INTEGER_32	10000	
C00671	L_OffsetGainP_2: Gain	Linear value	23904	5D60	E	1	INTEGER_32	10000	
C00672	L_OffsetGainP_3: Gain	Linear value	23903	5D5F	E	1	INTEGER_32	10000	
C00673	L_OffsetGainPhiP 1-2: Offset	Linear value	23902	5D5E	A	2	INTEGER_32	1	
C00674	L_OffsetGainPhiP 1-2: Gain	Linear value	23901	5D5D	A	2	INTEGER_32	1	
C00677	L_GainOffsetP 1-3: Parameter	Linear value	23898	5D5A	A	6	INTEGER_16	100	
C00678	L_GainOffsetPhiP 1-2: Parameter	Linear value	23897	5D59	A	4	INTEGER_32	1	
C00679	L_MulDiv_2: Parameter	Linear value	23896	5D58	A	2	INTEGER_16	1	
C00680	L_Compare_1: Fct.	Selection list	23895	5D57	E	1	UNSIGNED_8	1	
Grayed out = display parameter (read access only)									

Code	Name	Type	Index		Data					
			dec	hex	DS	DA	DT	Factor	CINH	
C00681	L_Compare_1: Hysteresis	Linear value	23894	5D56	E	1	INTEGER_16	100		
C00682	L_Compare_1: Window	Linear value	23893	5D55	E	1	INTEGER_16	100		
C00685	L_Compare_2: Fct.	Selection list	23890	5D52	E	1	UNSIGNED_8	1		
C00686	L_Compare_2: Hysteresis	Linear value	23889	5D51	E	1	INTEGER_16	100		
C00687	L_Compare_2: Window	Linear value	23888	5D50	E	1	INTEGER_16	100		
C00690	L_Compare_3: Fct.	Selection list	23885	5D4D	E	1	UNSIGNED_8	1		
C00691	L_Compare_3: Hysteresis	Linear value	23884	5D4C	E	1	INTEGER_16	100		
C00692	L_Compare_3: Window	Linear value	23883	5D4B	E	1	INTEGER_16	100		
C00693	L_Compare 4-5: Fct.	Selection list	23882	5D4A	A	2	UNSIGNED_8	1		
C00694	L_Compare 4-5: Hysteresis	Linear value	23881	5D49	A	2	INTEGER_16	100		
C00695	L_Compare 4-5: Window	Linear value	23880	5D48	A	2	INTEGER_16	100		
C00696	L_OffsetGainP_1: Offset	Linear value	23879	5D47	E	1	INTEGER_16	100		
C00697	L_OffsetGainP_2: Offset	Linear value	23878	5D46	E	1	INTEGER_16	100		
C00698	L_OffsetGainP_3: Offset	Linear value	23877	5D45	E	1	INTEGER_16	100		
C00699	L_MulDiv_1: Parameter	Linear value	23876	5D44	A	2	INTEGER_16	1		
C00700	LA_NCtrl: Analog connection list	Selection list	23875	5D43	A	29	UNSIGNED_16	1		
C00701	LA_NCtrl: Digital connection list	Selection list	23874	5D42	A	48	UNSIGNED_16	1		
C00710	LA_TabPos: Analog connection list	Selection list	23865	5D39	A	31	UNSIGNED_16	1		
C00711	LA_TabPos: Digital connection list	Selection list	23864	5D38	A	56	UNSIGNED_16	1		
C00712	LA_TabPos: phi connection list	Selection list	23863	5D37	A	3	UNSIGNED_16	1		
C00720	L_DigitalDelay_1: Delay	Linear value	23855	5D2F	A	2	UNSIGNED_32	1000		
C00721	L_DigitalDelay: Delay	Linear value	23854	5D2E	A	4	UNSIGNED_32	1000		
C00725	Current switching frequency	Selection list	23850	5D2A	E	1	UNSIGNED_8	1		
C00727	LS_Keypad digital values	Linear value	23848	5D28	A	8	UNSIGNED_8	1		
C00728	Analog values - keypad	Linear value	23847	5D27	A	3	INTEGER_16	100		
C00729	Remote: Setpoint selection	Linear value	23846	5D26	A	2	INTEGER_16	100		
C00760	LA_SwitchPos: Analog connection list	Selection list	23815	5D07	A	25	UNSIGNED_16	1		
C00761	LA_SwitchPos: Digital connection list	Selection list	23814	5D06	A	47	UNSIGNED_16	1		
C00800	L_MPot_1: Upper limit	Linear value	23775	5CDF	E	1	INTEGER_16	100		
C00801	L_MPot_1: Lower limit	Linear value	23774	5CDE	E	1	INTEGER_16	100		
C00802	L_MPot_1: Acceleration time	Linear value	23773	5CDD	E	1	UNSIGNED_16	10		
C00803	L_MPot_1: Deceleration time	Linear value	23772	5CDC	E	1	UNSIGNED_16	10		
C00804	L_MPot_1: Inactive fct.	Selection list	23771	5CDB	E	1	UNSIGNED_8	1		
C00805	L_MPot_1: Init fct.	Selection list	23770	5CDA	E	1	UNSIGNED_8	1		
C00806	L_MPot_1: Use	Selection list	23769	5CD9	E	1	UNSIGNED_8	1		
C00807	L_NLim_1: Max.SkipFrq.	Linear value	23768	5CD8	A	3	INTEGER_16	100		
C00808	L_NLim_1: Min.SkipFrq.	Linear value	23767	5CD7	A	3	INTEGER_16	100		
C00809	L_NLim_2: Max.SkipFrq.	Linear value	23766	5CD6	A	3	INTEGER_16	100		
C00810	L_NLim_2: Min.SkipFrq.	Linear value	23765	5CD5	A	3	INTEGER_16	100		
C00811	L_NLim_1: Current output value	Linear value	23764	5CD4	A	2	INTEGER_16	100		
C00812	L_NLim: Current status	Bit coded	23763	5CD3	A	2	UNSIGNED_16	1		
C00820	L_DigitalLogic_1: Function	Selection list	23755	5CCB	E	1	UNSIGNED_8	1		
C00821	L_DigitalLogic_1: Truth table	Selection list	23754	5CCA	A	8	UNSIGNED_8	1		
C00822	L_DigitalLogic_2: Function	Selection list	23753	5CC9	E	1	UNSIGNED_8	1		
C00823	L_DigitalLogic_2: Truth table	Selection list	23752	5CC8	A	8	UNSIGNED_8	1		
C00824	L_DigitalLogic5_1: Function	Selection list	23751	5CC7	E	1	UNSIGNED_8	1		
C00825	L_DigitalLogic5_1: Truth table	Selection list	23750	5CC6	A	32	UNSIGNED_8	1		
C00826	L_DigitalLogic5_2: Function	Selection list	23749	5CC5	E	1	UNSIGNED_8	1		
C00827	L_DigitalLogic5_2: Truth table	Selection list	23748	5CC4	A	32	UNSIGNED_8	1		
C00828	L_DigitalLogic_3: Function	Selection list	23747	5CC3	E	1	UNSIGNED_8	1		
Grayed out = display parameter (read access only)										

Code	Name	Type	Index		Data					
			dec	hex	DS	DA	DT	Factor	CINH	
C00829	L_DigitalLogic_3: truth table	Selection list	23746	5CC2	A	8	UNSIGNED_8	1		
C00830	16-bit inputs [%]	Linear value	23745	5CC1	A	97	INTEGER_16	100		
C00831	16-bit inputs	Bit coded	23744	5CC0	A	97	UNSIGNED_16	1		
C00832	16-bit inputs [rpm]	Linear value	23743	5CBF	A	97	INTEGER_16	1		
C00833	Binary inputs	Selection list	23742	5CBE	A	131	UNSIGNED_8	1		
C00834	32-bit inputs [incr]	Linear value	23741	5CBD	A	8	INTEGER_32	1		
C00835	16-bit inputs [%] (Set2)	Linear value	23740	5CBC	A	162	INTEGER_16	100		
C00836	16-bit inputs (Set2)	Bit coded	23739	5CBB	A	162	UNSIGNED_16	1		
C00837	16-bit inputs [rpm] (Set2)	Linear value	23738	5CBA	A	162	INTEGER_16	1		
C00838	Binary inputs (Set2)	Selection list	23737	5CB9	A	213	UNSIGNED_8	1		
C00839	32-bit inputs [incr] (Set2)	Linear value	23736	5CB8	A	96	INTEGER_32	1		
C00840	16-bit inputs I/O level [%]	Linear value	23735	5CB7	A	107	INTEGER_16	100		
C00841	16-bit inputs I/O level	Bit coded	23734	5CB6	A	107	UNSIGNED_16	1		
C00843	Binary inputs I/O level	Selection list	23732	5CB4	A	183	UNSIGNED_8	1		
C00844	32-bit inputs I/O level [incr]	Linear value	23731	5CB3	A	24	INTEGER_32	1		
C00866	CAN input words	Bit coded	23709	5C9D	A	12	UNSIGNED_16	1		
C00868	CAN output words	Bit coded	23707	5C9B	A	12	UNSIGNED_16	1		
C00876	MCI input words	Bit coded	23699	5C93	A	16	UNSIGNED_16	1		
C00877	MCI output words	Bit coded	23698	5C92	A	16	UNSIGNED_16	1		
C00890	MCI_InOut: Inversion	Bit coded	23685	5C85	A	4	UNSIGNED_16	1		
C00905	Motor phase direction of rotation	Selection list	23670	5C76	E	1	UNSIGNED_8	1	CINH	
C00909	Speed limitation	Linear value	23666	5C72	A	2	INTEGER_16	100		
C00910	Frequency limitation	Linear value	23665	5C71	A	2	UNSIGNED_16	1		
C00915	Motor cable length	Linear value	23660	5C6C	E	1	UNSIGNED_16	10		
C00916	Motor cable cross-section	Linear value	23659	5C6B	E	1	UNSIGNED_16	100		
C00917	Motor cable resistance	Linear value	23658	5C6A	E	1	UNSIGNED_16	1		
C00918	SC: Start motor magnetising current	Linear value	23657	5C69	E	1	UNSIGNED_8	1		
C00919	Load moment of inertia	Linear value	23656	5C68	A	1	UNSIGNED_32	100		
C00925	LS_Resolver: Number of pole pairs	Linear value	23650	5C62	E	1	UNSIGNED_8	1		
C00926	Pole position	Linear value	23649	5C61	A	2	INTEGER_16	10		
C00927	Motor rotor position	Linear value	23648	5C60	E	1	UNSIGNED_16	1		
C00937	Field-oriented motor currents	Linear value	23638	5C56	A	2	INTEGER_16	100		
C00938	PSM: Maximum motor current field weakening	Linear value	23637	5C55	E	1	UNSIGNED_16	100		
C00939	Ultimate motor current	Linear value	23636	5C54	E	1	UNSIGNED_16	10		
C00940	L_ConvW numerator	Linear value	23635	5C53	A	4	INTEGER_16	1		
C00941	L_ConvW denominator	Linear value	23634	5C52	A	4	INTEGER_16	1		
C00942	L_ConvW conversion method	Selection list	23633	5C51	A	4	UNSIGNED_8	1		
C00950	L_Interpolator_1: Activation FB functions	Selection list	23625	5C49	A	3	UNSIGNED_8	1		
C00951	L_Interpolator_1: No. of interpolation steps	Linear value	23624	5C48	E	1	UNSIGNED_16	1		
C00952	L_Interpolator_1: Limit value - error cycles	Linear value	23623	5C47	E	1	UNSIGNED_16	1		
C00953	L_Interpolator_1: Speed-up	Linear value	23622	5C46	E	1	UNSIGNED_8	1		
C00959	L_Curve: Current output value	Linear value	23616	5C40	A	3	INTEGER_16	100		
C00960	L_Curve_1: Selected curve type	Selection list	23615	5C3F	A	1	UNSIGNED_8	1		
C00961	L_Curve_1: Input limitation	Linear value	23614	5C3E	A	2	INTEGER_16	100		
C00963	L_Curve_1: Table X-values	Linear value	23612	5C3C	A	32	INTEGER_16	1		
C00964	L_Curve_1: Table Y-values	Linear value	23611	5C3B	A	32	INTEGER_16	1		
C00965	Max. motor speed	Linear value	23610	5C3A	E	1	UNSIGNED_16	1		
C00966	VFC: Time const. slip comp.	Linear value	23609	5C39	E	1	UNSIGNED_16	1		
C00967	VFC: Frequency interpol. point n	Linear value	23608	5C38	A	11	INTEGER_16	10		
Grayed out = display parameter (read access only)										

Code	Name	Type	Index		Data					
			dec	hex	DS	DA	DT	Factor	CINH	
C00968	VFC: Voltage interpol. point n	Linear value	23607	5C37	A	11	UNSIGNED_16	100		
C00969	Motorparameter	Linear value	23606	5C36	A	1	UNSIGNED_8	1		
C00971	VFC: V/f +encoder limitation	Linear value	23604	5C34	A	2	UNSIGNED_16	100		
C00972	VFC: Vp V/f +encoder	Linear value	23603	5C33	E	1	UNSIGNED_16	1000		
C00973	VFC: Ti V/f +encoder	Linear value	23602	5C32	E	1	UNSIGNED_16	10		
C00975	VFC-ECO: Vp CosPhi controller	Linear value	23600	5C30	E	1	UNSIGNED_16	1000		
C00976	VFC-ECO: Ti CosPhi controller	Linear value	23599	5C2F	E	1	UNSIGNED_16	10		
C00977	VFC-ECO: Minimum voltage V/f	Linear value	23598	5C2E	E	1	INTEGER_16	100		
C00978	VFC-ECO: Voltage reduction	Linear value	23597	5C2D	E	1	INTEGER_16	1		
C00979	Cosine phi	Linear value	23596	5C2C	A	2	INTEGER_16	100		
C00980	Output power	Linear value	23595	5C2B	A	2	INTEGER_32	1000		
C00981	Energy display	Linear value	23594	5C2A	A	2	INTEGER_32	100		
C00982	VFC-ECO: Voltage reduction ramp	Linear value	23593	5C29	E	1	UNSIGNED_8	10		
C00983	Delay	Linear value	23592	5C28	A	1	UNSIGNED_16	1		
C00985	SLVC: Field current controller gain	Linear value	23590	5C26	E	1	INTEGER_16	100		
C00986	SLVC: Cross current controller gain	Linear value	23589	5C25	E	1	INTEGER_16	100		
C00987	Inverter motor brake: nAdd	Linear value	23588	5C24	E	1	INTEGER_16	1		
C00988	Inverter motor brake: PT1 filter time	Linear value	23587	5C23	E	1	INTEGER_16	10		
C00990	Flying restart fct.: Activate	Selection list	23585	5C21	E	1	UNSIGNED_8	1	CINH	
C00991	Flying restart fct.: Process	Selection list	23584	5C20	E	1	UNSIGNED_16	1		
C00992	Flying restart fct.: Start frequency	Linear value	23583	5C1F	E	1	INTEGER_16	1		
C00993	Flying restart fct: Int. time	Linear value	23582	5C1E	E	1	UNSIGNED_16	10		
C00994	Flying restart fct.: Current	Linear value	23581	5C1D	E	1	INTEGER_16	100		
C00995	SLPSM: Controlled current setpoint	Linear value	23580	5C1C	A	2	UNSIGNED_16	100		
C00996	SLPSM: Switching speed	Linear value	23579	5C1B	A	2	INTEGER_16	100		
C00997	SLPSM: Filter cutoff frequency	Linear value	23578	5C1A	E	1	INTEGER_16	100		
C00998	SLPSM: Filter time rotor position	Linear value	23577	5C19	A	2	INTEGER_16	10		
C00999	SLPSM: PLL gain	Linear value	23576	5C18	E	1	INTEGER_16	1		
C01000	MCTRL: Status	Bit coded	23575	5C17	E	1	UNSIGNED_16	1		
C01001	Manual entry of motor type	Selection list	23574	5C16	A	1	UNSIGNED_8	1		
C01010	L_ArithmetikPhi 1-3: Function	Selection list	23565	5C0D	A	3	UNSIGNED_8	1		
C01011	L_ArithmetikPhi 4-6: Function	Selection list	23564	5C0C	A	3	UNSIGNED_8	1		
C01012	L_PhiDiv: byDivision	Linear value	23563	5C0B	A	1	INTEGER_8	1		
C01020	L_Odometer_1: Memory length	Selection list	23555	5C03	E	1	UNSIGNED_8	1		
C01021	L_Odometer_1: Memory type	Selection list	23554	5C02	E	1	UNSIGNED_8	1		
C01022	L_Odometer_1: Input selection	Selection list	23553	5C01	E	1	UNSIGNED_8	1		
C01023	L_Odometer_1: Edge selection	Selection list	23552	5C00	E	1	UNSIGNED_8	1		
C01025	L_Curve_2: Selected curve type	Selection list	23550	5BFE	A	1	UNSIGNED_8	1		
C01026	L_Curve_2: Input limitation	Linear value	23549	5BFD	A	2	INTEGER_16	100		
C01028	L_Curve_2: Table X-values	Linear value	23547	5BFB	A	32	INTEGER_16	1		
C01029	L_Curve_2: Table Y-values	Linear value	23546	5BFA	A	32	INTEGER_16	1		
C01030	L_Curve_3: Selected curve type	Selection list	23545	5BF9	A	1	UNSIGNED_8	1		
C01031	L_Curve_3: Input limitation	Linear value	23544	5BF8	A	2	INTEGER_16	100		
C01033	L_Curve_3: Table X-values	Linear value	23542	5BF6	A	32	INTEGER_16	1		
C01034	L_Curve_3: Table Y-values	Linear value	23541	5BF5	A	32	INTEGER_16	1		
C01035	L_Curve_3: SelectCurve	Selection list	23540	5BF4	A	1	UNSIGNED_16	1		
C01040	L_SRFG_1..2 linear ramp time	Linear value	23535	5BEF	A	2	UNSIGNED_32	1000		
C01041	L_SRFG_1..2 S-ramp time	Linear value	23534	5BEE	A	2	UNSIGNED_32	1000		
C01042	L_SRFG_1..2 limitations of output values	Linear value	23533	5BED	A	4	INTEGER_16	100		
C01045	L_ConvAP 1-3: numerator/denominator	Linear value	23530	5BEA	A	6	INTEGER_16	1		
Grayed out = display parameter (read access only)										

Code	Name	Type	Index		Data					
			dec	hex	DS	DA	DT	Factor	CINH	
C01046	L_ConvPA 1-3: byDivision	Linear value	23529	5BE9	A	3	INTEGER_8	1		
C01047	L_GearComp_1: Offset	Linear value	23528	5BE8	A	1	INTEGER_16	1		
C01048	L_GearComp_1: Num_Denom	Linear value	23527	5BE7	A	2	INTEGER_16	1		
C01049	L_CalcDiameter_1: Status	Linear value	23526	5BE6	A	1	INTEGER_16	1		
C01050	L_CalcDiameter_1: Diameter recalculation	Linear value	23525	5BE5	A	2	UNSIGNED_32	1000		
C01051	L_CalcDiameter_1: Filter time constant	Linear value	23524	5BE4	A	1	UNSIGNED_16	1000		
C01052	L_CalcDiameter_1: Web break monitoring	Linear value	23523	5BE3	A	1	INTEGER_16	100		
C01053	L_ProcessCtrl_1: Controller times	Linear value	23522	5BE2	A	5	UNSIGNED_16	1000		
C01054	L_ProcessCtrl_1: System deviation	Linear value	23521	5BE1	A	2	INTEGER_16	100		
C01055	L_ProcessCtrl_1: Correcting variable limitation	Selection list	23520	5BE0	A	1	UNSIGNED_8	1		
C01056	L_ProcessCtrl_1: Controller gain	Linear value	23519	5BDF	A	1	UNSIGNED_16	100		
C01057	L_CalcDiameter_1: Current diameter	Linear value	23518	5BDE	A	1	UNSIGNED_32	1000		
C01058	L_PosCtrlLin_1-2: bDisable	Selection list	23517	5BDD	A	2	UNSIGNED_8	1		
C01059	L_PosCtrlLin_1-2: Positioning behaviour	Selection list	23516	5BDC	A	2	UNSIGNED_8	1		
C01060	L_PosCtrlLin_1-2: Ramps	Linear value	23515	5BDB	A	6	INTEGER_32	1000		
C01061	L_PosCtrlLin_1-2: Traversing speed	Linear value	23514	5BDA	A	4	INTEGER_16	1		
C01062	L_SwitchPoint_1: Dead time	Linear value	23513	5BD9	A	8	UNSIGNED_16	1		
C01063	L_SwitchPoint_1: Hysteresis	Linear value	23512	5BD8	A	8	UNSIGNED_16	1		
C01064	L_SwitchPoint_1: CenterMode	Selection list	23511	5BD7	A	8	UNSIGNED_8	1		
C01065	L_SwitchPoint_1: Running time	Linear value	23510	5BD6	A	8	UNSIGNED_16	1		
C01066	L_SwitchPoint_1: Status	Selection list	23509	5BD5	A	8	INTEGER_16	1		
C01067	Inversion of gearbox stages	Selection list	23508	5BD4	A	3	UNSIGNED_8	1		
C01068	L_SwitchPoint_1: Invert	Bit coded	23507	5BD3	A	1	UNSIGNED_16	1		
C01069	L_DFSET_1: Ramp settings	Linear value	23506	5BD2	A	2	UNSIGNED_16	1		
C01070	L_DFSET_1: Angular trimming	Linear value	23505	5BD1	A	1	INTEGER_32	1		
C01071	L_DFSET_1: Following error limit	Linear value	23504	5BD0	A	1	UNSIGNED_32	1		
C01072	L_DFSET_1: Multiplier - angular trimming	Linear value	23503	5BCF	A	1	INTEGER_16	1		
C01073	L_DFSET_1: Adjustment	Bit coded	23502	5BCE	A	1	UNSIGNED_8	1		
C01074	L_DFSET_1: Zero pulse divider	Linear value	23501	5BCD	A	2	UNSIGNED_16	1		
C01075	L_DFSET_1: Synchronisation mode	Selection list	23500	5BCC	A	1	UNSIGNED_8	1		
C01076	L_DFRFG_1: Times	Linear value	23499	5BCB	A	2	UNSIGNED_32	1000		
C01077	L_DFRFG_1: Max. speed-up	Linear value	23498	5BCA	A	1	INTEGER_16	1		
C01078	L_DFRFG_1: Following error	Linear value	23497	5BC9	A	1	UNSIGNED_32	1		
C01079	L_DFRFG_1: Synchronisation window	Linear value	23496	5BC8	A	1	UNSIGNED_16	1		
C01080	L_DFRFG_1: Offset	Linear value	23495	5BC7	A	1	INTEGER_32	1		
C01081	L_DFRFG_1: Sync. direction / TP function	Selection list	23494	5BC6	A	1	UNSIGNED_8	1		
C01082	LS_WriteParamList: Execute Mode	Selection list	23493	5BC5	E	1	UNSIGNED_8	1		
C01083	LS_WriteParamList: Error status	Linear value	23492	5BC4	E	1	UNSIGNED_16	1		
C01084	LS_WriteParamList: Error line	Linear value	23491	5BC3	E	1	UNSIGNED_8	1		
C01085	LS_WriteParamList: Index	Linear value	23490	5BC2	A	32	INTEGER_32	1000		
C01086	LS_WriteParamList: WriteValue_1	Linear value	23489	5BC1	A	32	INTEGER_32	1		
C01087	LS_WriteParamList: WriteValue_2	Linear value	23488	5BC0	A	32	INTEGER_32	1		
C01088	LS_WriteParamList: WriteValue_3	Linear value	23487	5BBF	A	32	INTEGER_32	1		
C01089	LS_WriteParamList: WriteValue_4	Linear value	23486	5BBE	A	32	INTEGER_32	1		
C01090	LS_ParReadWrite 1-6: Index	Linear value	23485	5BBD	A	6	INTEGER_32	1000		
C01091	LS_ParReadWrite 1-6: Cycle time	Selection list	23484	5BBC	A	6	UNSIGNED_16	1		
C01092	LS_ParReadWrite 1-6: FailState	Linear value	23483	5BBB	A	6	UNSIGNED_16	1		
C01093	LS_ParReadWrite 1-6: Arithmetic mode	Selection list	23482	5BBA	A	6	UNSIGNED_8	1		
C01094	LS_ParReadWrite 1-6: Numerator	Linear value	23481	5BB9	A	6	INTEGER_16	1		
Grayed out = display parameter (read access only)										

Code	Name	Type	Index		Data					CINH
			dec	hex	DS	DA	DT	Factor		
C01095	LS_ParReadWrite 1-6: Denominator	Linear value	23480	5BB8	A	6	INTEGER_16	1		
C01100	Function L_Counter 1-3	Selection list	23475	5BB3	A	3	UNSIGNED_8	1		
C01101	Comparison L_Counter 1-3	Selection list	23474	5BB2	A	3	UNSIGNED_8	1		
C01108	L_SwitchPoint_1: Deadtime factor	Selection list	23467	5BAB	A	8	UNSIGNED_8	1		
C01109	L_SwitchPointPar_1: Deadtime factor	Selection list	23466	5BAA	A	8	UNSIGNED_8	1		
C01110	LS_MultiEncoder: Solid measure	Selection list	23465	5BA9	E	1	UNSIGNED_8	1		
C01111	LS_MultiEncoder: Encoder constant	Linear value	23464	5BA8	A	3	INTEGER_32	1		
C01112	LS_MultiEncoder: Position values	Linear value	23463	5BA7	A	4	INTEGER_32	10000		
C01119	LS_MultiEncoder: Current position	Linear value	23456	5BA0	A	2	INTEGER_32	10000		
C01120	Sync signal source	Selection list	23455	5B9F	E	1	UNSIGNED_8	1		
C01121	Sync cycle time setpoint	Linear value	23454	5B9E	E	1	UNSIGNED_16	1		
C01122	Sync phase position	Linear value	23453	5B9D	E	1	UNSIGNED_16	1		
C01123	Sync window	Linear value	23452	5B9C	E	1	UNSIGNED_16	1		
C01124	Sync correction width	Selection list	23451	5B9B	E	1	UNSIGNED_8	1		
C01130	LS_RetainData: Selection	Bit coded	23445	5B95	A	4	UNSIGNED_16	1		
C01131	LS_RetainData: 16Bit data	Linear value	23444	5B94	A	4	UNSIGNED_16	1		
C01132	LS_RetainData: 32Bit data	Linear value	23443	5B93	A	4	INTEGER_32	1		
C01133	LS_RetainData: Bool data	Selection list	23442	5B92	A	4	UNSIGNED_8	1		
C01138	L_Transient 1-4: Function	Selection list	23437	5B8D	A	4	UNSIGNED_8	1		
C01139	L_Transient 1-4: Pulse duration	Linear value	23436	5B8C	A	4	UNSIGNED_16	1000		
C01140	L_Transient 5-8: Function	Selection list	23435	5B8B	A	4	UNSIGNED_8	1		
C01141	L_Transient 5-8 pulse duration	Linear value	23434	5B8A	A	4	UNSIGNED_16	1000		
C01150	L_PhaseIntK: Function	Selection list	23425	5B81	A	2	UNSIGNED_8	1		
C01151	L_PhaseIntK: Compare	Linear value	23424	5B80	A	2	INTEGER_32	1		
C01152	L_SwitchPointPar_1: Dead time	Linear value	23423	5B7F	A	8	UNSIGNED_16	1		
C01153	L_SwitchPointPar_1: Hysteresis	Linear value	23422	5B7E	A	8	UNSIGNED_16	1		
C01154	L_SwitchPointPar_1: CenterMode	Selection list	23421	5B7D	A	8	UNSIGNED_8	1		
C01155	L_SwitchPointPar_1: Running time	Linear value	23420	5B7C	A	8	UNSIGNED_16	1		
C01156	L_SwitchPointPar_1: Status	Selection list	23419	5B7B	A	8	INTEGER_16	1		
C01157	L_SwitchPointPar_1:Position	Linear value	23418	5B7A	A	16	INTEGER_32	10000		
C01158	L_SwitchPointPar_1: Invert	Bit coded	23417	5B79	A	1	UNSIGNED_16	1		
C01190	Motor thermal sensor	Selection list	23385	5B59	A	2	UNSIGNED_8	1		
C01191	PTC characteristic: Temperature 1/2	Linear value	23384	5B58	A	2	UNSIGNED_8	1		
C01192	PTC characteristic: Resistance 1/2	Linear value	23383	5B57	A	2	INTEGER_32	1		
C01193	Motor temp. feedback system	Selection list	23382	5B56	E	1	UNSIGNED_8	1		
C01201	MCK: Cycle	Linear value	23374	5B4E	A	1	INTEGER_32	10000		
C01202	MCK: iM motor/process	Linear value	23373	5B4D	A	2	UNSIGNED_16	1		
C01203	MCK: iG motor/position encoder	Linear value	23372	5B4C	A	2	UNSIGNED_16	1		
C01204	MCK: Feed constant	Linear value	23371	5B4B	E	1	INTEGER_32	10000		
C01205	MCK: Position resolution	Linear value	23370	5B4A	E	1	INTEGER_32	10000		
C01206	MCK: Mounting direction	Selection list	23369	5B49	A	2	UNSIGNED_8	1	CINH	
C01210	MCK: Current positions	Linear value	23365	5B45	A	9	INTEGER_32	10000		
C01211	MCK: Speed	Linear value	23364	5B44	A	3	INTEGER_32	10000		
C01213	MCK: Max. traversing distance	Linear value	23362	5B42	A	1	INTEGER_32	1		
C01215	MCK: Following error	Linear value	23360	5B40	A	3	INTEGER_32	10000		
C01216	MCK: Positioning setting	Bit coded	23359	5B3F	E	1	UNSIGNED_8	1		
C01218	MCK: Position follower setting	Bit coded	23357	5B3D	E	1	UNSIGNED_8	1		
C01219	MCK: Speed follower setting	Bit coded	23356	5B3C	E	1	UNSIGNED_8	1		
C01220	MCK: Ref. setting	Bit coded	23355	5B3B	A	1	UNSIGNED_16	1		
C01221	MCK: Homing mode	Selection list	23354	5B3A	E	1	UNSIGNED_8	1		
Grayed out = display parameter (read access only)										

Code	Name	Type	Index		Data				
			dec	hex	DS	DA	DT	Factor	CINH
C01222	MCK: Ref. M limit mode 14/15	Linear value	23353	5B39	E	1	INTEGER_16	100	
C01223	MCK: Ref. waiting time mode 14/15	Linear value	23352	5B38	E	1	UNSIGNED_16	1	
C01224	MCK: Ref. speeds	Linear value	23351	5B37	A	2	INTEGER_32	10000	
C01225	MCK: Ref. accelerations	Linear value	23350	5B36	A	2	INTEGER_32	10000	
C01226	MCK: Ref. S-ramp time	Linear value	23349	5B35	A	1	UNSIGNED_16	1000	
C01227	MCK: Ref. positions	Linear value	23348	5B34	A	2	INTEGER_32	10000	
C01228	MCK: Ref. sequence profile	Linear value	23347	5B33	E	1	UNSIGNED_8	1	
C01229	MCK: Position limiting values	Linear value	23346	5B32	A	2	INTEGER_32	10000	
C01230	Manual jog: Setting	Bit coded	23345	5B31	E	1	UNSIGNED_8	1	
C01231	MCK: Manual jog speeds	Linear value	23344	5B30	A	2	INTEGER_32	10000	
C01232	MCK: Manual jog accelerations	Linear value	23343	5B2F	A	2	INTEGER_32	10000	
C01233	MCK: Manual jog S-ramp time	Linear value	23342	5B2E	A	1	UNSIGNED_16	1000	
C01234	MCK: Manual jog breakpoints	Linear value	23341	5B2D	A	4	INTEGER_32	10000	
C01235	MCK: Manual jog waiting times	Linear value	23340	5B2C	A	1	UNSIGNED_16	1000	
C01236	MCK: Speed follower	Linear value	23339	5B2B	A	1	INTEGER_32	10000	
C01237	MCK: Acceleration follower	Linear value	23338	5B2A	A	2	INTEGER_32	10000	
C01238	MCK: S-ramp time follower	Linear value	23337	5B29	A	1	UNSIGNED_16	1000	
C01239	Setpoint holding	Linear value	23336	5B28	E	1	UNSIGNED_32	1	
C01240	MCK: Control word	Bit coded	23335	5B27	E	1	UNSIGNED_32	1	
C01241	MCK: Status word	Bit coded	23334	5B26	E	1	UNSIGNED_32	1	
C01242	MCK: Current pos profile number	Linear value	23333	5B25	E	1	UNSIGNED_8	1	
C01243	MCK: Current operating mode	Selection list	23332	5B24	E	1	UNSIGNED_8	1	
C01244	MCK: Target detection - times	Linear value	23331	5B23	A	3	UNSIGNED_16	1	
C01245	MCK: Target detection - positions	Linear value	23330	5B22	A	3	INTEGER_32	10000	
C01246	MCK: Select signal source	Selection list	23329	5B21	A	2	UNSIGNED_8	1	
C01251	MCK: Acceleration stop	Linear value	23324	5B1C	A	1	INTEGER_32	10000	
C01252	MCK: S-ramp times stop	Linear value	23323	5B1B	A	1	UNSIGNED_16	1000	
C01294	Mode: Position calculation	Selection list	23281	5AF1	A	3	UNSIGNED_8	1	
C01295	L_MCKStateInterface_1: Pos. selection	Selection list	23280	5AF0	E	1	UNSIGNED_8	1	
C01296	Mode: Position calculation	Selection list	23279	5AEF	A	2	UNSIGNED_8	1	
C01297	L_MckCtrlInterface_1: Alternative function	Bit coded	23278	5AEE	E	1	UNSIGNED_8	1	
C01298	MCK: Operating mode change with profile no.	Selection list	23277	5AED	A	4	UNSIGNED_8	1	
C01299	MCKI: Status MCKInterface	Bit coded	23276	5AEC	E	1	UNSIGNED_8	1	
C01300	Profile data: Positioning mode	Selection list	23275	5AEB	A	15	UNSIGNED_8	1	
C01301	Profile data: Position	Linear value	23274	5AEA	A	15	INTEGER_32	10000	
C01302	Profile data: Speed	Linear value	23273	5AE9	A	15	INTEGER_32	10000	
C01303	Profile data: Acceleration	Linear value	23272	5AE8	A	15	INTEGER_32	10000	
C01304	Profile data: Deceleration	Linear value	23271	5AE7	A	15	INTEGER_32	10000	
C01305	Profile data: Final speed	Linear value	23270	5AE6	A	15	INTEGER_32	10000	
C01306	Profile data: S-ramp time	Linear value	23269	5AE5	A	15	UNSIGNED_16	1000	
C01307	Profile data: Sequence profile	Linear value	23268	5AE4	A	15	UNSIGNED_8	1	
C01308	Profile data: TP profile	Linear value	23267	5AE3	A	15	UNSIGNED_8	1	
C01309	Profile data: TP signal source	Selection list	23266	5AE2	A	15	UNSIGNED_8	1	
C01350	ACDrive: Drive mode	Selection list	23225	5AB9	A	1	UNSIGNED_8	1	
C01351	ACDrive: Control word	Bit coded	23224	5AB8	A	1	UNSIGNED_16	1	
C01352	ACDrive: Status word	Bit coded	23223	5AB7	A	1	UNSIGNED_16	1	
C01353	ACDrive: Setpoint scaling	Linear value	23222	5AB6	A	2	INTEGER_8	1	
C01400	L_Sequencer_1: Sequence step	Linear value	23175	5A87	A	100	UNSIGNED_16	1	
C01401	L_Sequencer_1: Current step	Linear value	23174	5A86	A	1	UNSIGNED_16	1	
Grayed out = display parameter (read access only)									

Code	Name	Type	Index		Data					
			dec	hex	DS	DA	DT	Factor	CINH	
C01402	L_Sequencer_1: Sequence control: Status	Linear value	23173	5A85	A	1	UNSIGNED_16	1		
C01403	L_Sequencer_1: Sequence control: Control word	Linear value	23172	5A84	A	1	UNSIGNED_16	1		
C01404	L_Sequencer_1: Step for bCancel = TRUE	Linear value	23171	5A83	A	1	UNSIGNED_16	1		
C01405	L_Sequencer_1: PSInput	Selection list	23170	5A82	A	50	UNSIGNED_16	1		
C01406	L_Sequencer_1: PSLevel	Linear value	23169	5A81	A	50	UNSIGNED_8	1		
C01407	L_Sequencer_1: PSProfil	Linear value	23168	5A80	A	50	UNSIGNED_16	1		
C01408	L_Sequencer_1: PSStep	Linear value	23167	5A7F	A	50	UNSIGNED_16	1		
C01409	L_Sequencer_1: PS_WD_Time	Linear value	23166	5A7E	A	50	UNSIGNED_32	1000		
C01410	L_Sequencer_1: PS_WD_Step	Linear value	23165	5A7D	A	50	UNSIGNED_16	1		
C01411	L_Sequencer_1: SwitchOut1	Selection list	23164	5A7C	A	16	UNSIGNED_16	1		
C01412	L_Sequencer_1: SwitchLevel1	Linear value	23163	5A7B	A	16	UNSIGNED_8	1		
C01413	L_Sequencer_1: SwitchOut2	Selection list	23162	5A7A	A	16	UNSIGNED_16	1		
C01414	L_Sequencer_1: SwitchLevel2	Linear value	23161	5A79	A	16	UNSIGNED_8	1		
C01415	L_Sequencer_1: BranchIn	Selection list	23160	5A78	A	16	UNSIGNED_16	1		
C01416	L_Sequencer_1: BranchLevel	Linear value	23159	5A77	A	16	UNSIGNED_8	1		
C01417	L_Sequencer_1: BranchStep	Linear value	23158	5A76	A	16	UNSIGNED_16	1		
C01418	L_Sequencer_1: BranchStep1	Linear value	23157	5A75	A	2	UNSIGNED_16	1		
C01419	L_Sequencer_1: BranchStep2	Linear value	23156	5A74	A	2	UNSIGNED_16	1		
C01420	L_Sequencer_1: BranchStep3	Linear value	23155	5A73	A	2	UNSIGNED_16	1		
C01421	L_Sequencer_1: BranchStep4	Linear value	23154	5A72	A	2	UNSIGNED_16	1		
C01422	L_Sequencer_1: BranchStep5	Linear value	23153	5A71	A	2	UNSIGNED_16	1		
C01423	L_Sequencer_1: BranchStep6	Linear value	23152	5A70	A	2	UNSIGNED_16	1		
C01424	L_Sequencer_1: BranchStep7	Linear value	23151	5A6F	A	2	UNSIGNED_16	1		
C01425	L_Sequencer_1: BranchStep8	Linear value	23150	5A6E	A	2	UNSIGNED_16	1		
C01426	L_Sequencer_1: BranchStep9	Linear value	23149	5A6D	A	2	UNSIGNED_16	1		
C01427	L_Sequencer_1: BranchStep10	Linear value	23148	5A6C	A	2	UNSIGNED_16	1		
C01428	L_Sequencer_1: BranchStep11	Linear value	23147	5A6B	A	2	UNSIGNED_16	1		
C01429	L_Sequencer_1: BranchStep12	Linear value	23146	5A6A	A	2	UNSIGNED_16	1		
C01430	L_Sequencer_1: BranchStep13	Linear value	23145	5A69	A	2	UNSIGNED_16	1		
C01431	L_Sequencer_1: BranchStep14	Linear value	23144	5A68	A	2	UNSIGNED_16	1		
C01432	L_Sequencer_1: BranchStep15	Linear value	23143	5A67	A	2	UNSIGNED_16	1		
C01433	L_Sequencer_1: BranchStep16	Linear value	23142	5A66	A	2	UNSIGNED_16	1		
C01434	L_Sequencer_1: BranchStep17	Linear value	23141	5A65	A	2	UNSIGNED_16	1		
C01435	L_Sequencer_1: BranchStep18	Linear value	23140	5A64	A	2	UNSIGNED_16	1		
C01436	L_Sequencer_1: BranchStep19	Linear value	23139	5A63	A	2	UNSIGNED_16	1		
C01437	L_Sequencer_1: BranchStep20	Linear value	23138	5A62	A	2	UNSIGNED_16	1		
C01438	L_Sequencer_1: Wartezeit	Linear value	23137	5A61	A	8	UNSIGNED_32	1000		
C01439	L_Sequencer_1: Wait Eingang f. Weiter	Selection list	23136	5A60	A	8	UNSIGNED_16	1		
C01440	L_Sequencer_1: WaitLevel	Linear value	23135	5A5F	A	8	UNSIGNED_8	1		
C01441	L_Sequencer_1: SetZählernummer	Linear value	23134	5A5E	A	5	UNSIGNED_16	1		
C01442	L_Sequencer_1: SetZählerStartwert	Linear value	23133	5A5D	A	5	INTEGER_32	1		
C01443	L_Sequencer_1: Aktueller Zählerstand	Linear value	23132	5A5C	A	5	INTEGER_32	1		
C01444	L_Sequencer_1: ZählerNummer	Linear value	23131	5A5B	A	8	UNSIGNED_16	1		
C01445	L_Sequencer_1: SchrittwertZähler	Linear value	23130	5A5A	A	8	INTEGER_32	1		
C01446	L_Sequencer_1: ZählerVergleichswert	Linear value	23129	5A59	A	8	INTEGER_32	1		
C01447	L_Sequencer_1: ZählerSprungziel	Linear value	23128	5A58	A	8	UNSIGNED_16	1		
C01448	L_Sequencer_1: ZählerVergleichsfunktion	Selection list	23127	5A57	A	8	UNSIGNED_16	1		
C01449	L_Sequencer_1: Standby Eingang f. Ende	Selection list	23126	5A56	A	5	UNSIGNED_16	1		
C01450	L_Sequencer_1: Standby PolaritätEingang	Linear value	23125	5A55	A	5	UNSIGNED_8	1		
Grayed out = display parameter (read access only)										

Code	Name	Type	Index		Data					
			dec	hex	DS	DA	DT	Factor	CINH	
C01451	L_Sequencer_1: Standby Modusfolger	Selection list	23124	5A54	A	5	UNSIGNED_16	1		
C01452	L_Sequencer_1: StandbySollwert	Linear value	23123	5A53	A	5	INTEGER_16	100		
C01453	L_Sequencer_1: Bool signal	Linear value	23122	5A52	A	16	UNSIGNED_8	1		
C01454	L_Sequencer_1: INT signal	Linear value	23121	5A51	A	1	INTEGER_16	100		
C01455	L_Sequencer_1: Word signal	Linear value	23120	5A50	A	13	UNSIGNED_16	1		
C01460	L_ConvActPos: TConst	Linear value	23115	5A4B	A	1	UNSIGNED_16	1		
C01461	L_ConvActPos: MaxPos/MinPos	Linear value	23114	5A4A	A	2	INTEGER_16	100		
C01462	L_ConvActPos: Length	Linear value	23113	5A49	A	1	UNSIGNED_32	1		
C01463	L_ConvActPos: UpperRef/LowerRef	Linear value	23112	5A48	A	2	INTEGER_16	100		
C01464	L_ConvActPos: WindowSetPos	Linear value	23111	5A47	A	1	INTEGER_16	100		
C01465	L_ConvActPos: DelayTime	Linear value	23110	5A46	A	1	UNSIGNED_16	1000		
C01466	L_ConvActPos: TConstVAdd	Linear value	23109	5A45	A	1	UNSIGNED_16	1		
C01467	L_ConvActPos: DeadBand	Linear value	23108	5A44	A	1	INTEGER_16	100		
C01468	L_ConvActPos: Damping	Linear value	23107	5A43	A	1	UNSIGNED_16	100		
C01469	L_MFail: Vp	Linear value	23106	5A42	A	1	UNSIGNED_16	1000		
C01470	L_MFail: Tn	Linear value	23105	5A41	A	3	UNSIGNED_16	1		
C01501	Resp. to communication error with MCI	Selection list	23074	5A22	A	2	UNSIGNED_8	1		
C01670	L_ComparePhi 1-5: Function	Selection list	22905	5979	A	5	UNSIGNED_8	1		
C01671	L_ComparePhi 1-5: Hysteresis	Linear value	22904	5978	A	5	INTEGER_32	1		
C01672	L_ComparePhi 1-5: Window	Linear value	22903	5977	A	5	INTEGER_32	1		
C01770	Filter time - earth-fault detect. is running	Linear value	22805	5915	E	1	UNSIGNED_8	1		
C01902	Diagnostics X6: Max. baud rate	Selection list	22673	5891	E	1	UNSIGNED_16	1		
C01903	Diagnostics X6: Change baud rate	Selection list	22672	5890	E	1	UNSIGNED_8	1		
C01905	Diagnostics X6: Current baud rate	Linear value	22670	588E	E	1	UNSIGNED_32	1		
C02200	LS_WriteParamList: Function	Selection list	22375	5767	A	2	UNSIGNED_8	1		
C02210	LS_WriteParamList: Motor control	Selection list	22365	575D	A	4	UNSIGNED_8	1		
C02212	LS_WriteParamList: VFC: V/f base frequency	Linear value	22363	575B	A	4	UNSIGNED_16	10		
C02213	LS_WriteParamList: VFC: Vmin boost	Linear value	22362	575A	A	4	UNSIGNED_16	100		
C02214	LS_WriteParamList: Switching frequency	Selection list	22361	5759	A	4	UNSIGNED_8	1		
C02215	LS_WriteParamList: Auto-DCB: Threshold	Linear value	22360	5758	A	4	UNSIGNED_16	1		
C02216	LS_WriteParamList: Slip compensation	Linear value	22359	5757	A	4	INTEGER_16	100		
C02217	LS_WriteParamList: Imax in motor mode	Linear value	22358	5756	A	4	UNSIGNED_16	100		
C02218	LS_WriteParamList: Imax in generator mode	Linear value	22357	5755	A	4	INTEGER_16	100		
C02219	LS_WriteParamList: DC braking: Current	Linear value	22356	5754	A	4	INTEGER_16	100		
C02220	LS_WriteParamList: Vp speed controller	Linear value	22355	5753	A	12	UNSIGNED_16	100		
C02221	LS_WriteParamList: Ti speed controller	Linear value	22354	5752	A	12	UNSIGNED_16	10		
C02222	LS_WriteParamList: SC: Tdn speed controller	Linear value	22353	5751	A	4	UNSIGNED_16	100		
C02223	LS_WriteParamList: Imax/M controller gain	Linear value	22352	5750	A	8	UNSIGNED_16	100		
C02224	LS_WriteParamList: Imax/M controller reset time	Linear value	22351	574F	A	8	UNSIGNED_16	1		
C02225	LS_WriteParamList: Vp current controller	Linear value	22350	574E	A	4	UNSIGNED_16	100		
C02226	LS_WriteParamList: Ti current controller	Linear value	22349	574D	A	4	UNSIGNED_16	100		
C02227	LS_WriteParamList: SC: Vp field controller	Linear value	22348	574C	A	4	UNSIGNED_16	100		
C02228	LS_WriteParamList: SC: Tn field controller	Linear value	22347	574B	A	4	UNSIGNED_16	10		
C02229	LS_WriteParamList: SC: settings	Selection list	22346	574A	A	16	UNSIGNED_8	1		
C02230	LS_WriteParamList: Override point of field weakening	Linear value	22345	5749	A	4	INTEGER_16	1		
C02231	LS_WriteParamList: Rated motor power	Linear value	22344	5748	A	4	UNSIGNED_16	100		
Grayed out = display parameter (read access only)										

Code	Name	Type	Index		Data				
			dec	hex	DS	DA	DT	Factor	CINH
C02232	LS_WriteParamList: Motor rotor resistance	Linear value	22343	5747	A	4	UNSIGNED_32	1	
C02233	LS_WriteParamList: Motor stator resistance	Linear value	22342	5746	A	4	UNSIGNED_32	1	
C02234	LS_WriteParamList: Motor stator leakage inductance	Linear value	22341	5745	A	4	UNSIGNED_16	100	
C02236	LS_WriteParamList: Rated motor speed	Linear value	22339	5743	A	4	UNSIGNED_16	1	
C02237	LS_WriteParamList: Rated motor current	Linear value	22338	5742	A	4	UNSIGNED_16	100	
C02238	LS_WriteParamList: Rated motor frequency	Linear value	22337	5741	A	4	UNSIGNED_16	1	
C02239	LS_WriteParamList: Rated motor voltage	Linear value	22336	5740	A	4	UNSIGNED_16	1	
C02240	LS_WriteParamList: Motor cosine phi	Linear value	22335	573F	A	4	UNSIGNED_8	100	
C02241	LS_WriteParamList: Motor magnetizing inductance	Linear value	22334	573E	A	4	UNSIGNED_16	10	
C02242	LS_WriteParamList: Motor magnetising current	Linear value	22333	573D	A	4	UNSIGNED_16	100	
C02244	LS_WriteParamList: Auto-DCB: hold time	Linear value	22331	573B	A	4	UNSIGNED_32	1000	
C02245	LS_WriteParamList: DC braking: Hold time	Linear value	22330	573A	A	4	UNSIGNED_32	1000	
C02246	LS_WriteParamList: Setting of motor overload (I _{xt})	Linear value	22329	5739	A	4	INTEGER_16	100	
C02249	LS_WriteParamList: Oscillation damping influence	Linear value	22326	5736	A	4	UNSIGNED_16	100	
C02250	LS_WriteParamList: Filter time - oscill. damping	Linear value	22325	5735	A	4	UNSIGNED_8	1	
C02251	LS_WriteParamList: Oscillation damping field weakening	Linear value	22324	5734	A	4	UNSIGNED_8	1	
C02252	LS_WriteParamList: Kp position controller	Linear value	22323	5733	A	4	UNSIGNED_16	100	
C02256	LS_WriteParamList: Moment of inertia	Linear value	22319	572F	A	4	UNSIGNED_32	100	
C02260	LS_WriteParamList: Speed sensor selection	Selection list	22315	572B	A	4	UNSIGNED_8	1	
C02261	LS_WriteParamList: SC: Field feedforward control	Linear value	22314	572A	A	4	UNSIGNED_16	1	
C02262	LS_WriteParamList: SC: Vp field weakening controller	Linear value	22313	5729	A	4	UNSIGNED_16	10000	
C02263	LS_WriteParamList: SC: Tn field weakening controller	Linear value	22312	5728	A	4	UNSIGNED_16	10	
C02264	LS_WriteParamList: Sensibility - Setpoint feedforward control	Selection list	22311	5727	A	4	UNSIGNED_8	1	
C02272	LS_WriteParamList: Motor phase direction of rotation	Selection list	22303	571F	A	4	UNSIGNED_8	1	CINH
C02273	LS_WriteParamList: Speed limitation	Linear value	22302	571E	A	8	INTEGER_16	100	
C02274	LS_WriteParamList: Frequency limitation	Linear value	22301	571D	A	8	UNSIGNED_16	1	
C02275	LS_WriteParamList: Motor cable length	Linear value	22300	571C	A	4	UNSIGNED_16	10	
C02276	LS_WriteParamList: Motor cable cross-section	Linear value	22299	571B	A	4	UNSIGNED_16	100	
C02278	LS_WriteParamList: PSM: Maximum motor current field weakening	Linear value	22297	5719	A	4	UNSIGNED_16	100	
C02279	LS_WriteParamList: Ultimate motor current	Linear value	22296	5718	A	4	UNSIGNED_16	10	
C02280	LS_WriteParamList: Max. motor speed	Linear value	22295	5717	A	4	UNSIGNED_16	1	
C02281	LS_WriteParamList: VFC: Time const. slip comp.	Linear value	22294	5716	A	4	UNSIGNED_16	1	
C02284	LS_WriteParamList: VFC: limitation V/f +encoder	Linear value	22291	5713	A	8	UNSIGNED_16	100	
C02285	LS_WriteParamList: VFC: Vp V/f +encoder	Linear value	22290	5712	A	4	UNSIGNED_16	1000	
C02286	LS_WriteParamList: VFC: Ti V/f +encoder	Linear value	22289	5711	A	4	UNSIGNED_16	10	
C02287	LS_WriteParamList: VFC-ECO: Vp CosPhi controller	Linear value	22288	5710	A	4	UNSIGNED_16	1000	
C02288	LS_WriteParamList: VFC-ECO: Ti CosPhi controller	Linear value	22287	570F	A	4	UNSIGNED_16	10	
Grayed out = display parameter (read access only)									

Code	Name	Type	Index		Data				
			dec	hex	DS	DA	DT	Factor	CINH
C02289	LS_WriteParamList: VFC-ECO: Minimum voltage U/f	Linear value	22286	570E	A	4	INTEGER_16	100	
C02290	LS_WriteParamList: VFC-ECO: Voltage reduction ramp	Linear value	22285	570D	A	4	UNSIGNED_8	10	
C02291	LS_WriteParamList: SLVC: Field current controller gain	Linear value	22284	570C	A	4	INTEGER_16	100	
C02292	LS_WriteParamList: SLVC: Cross current controller gain	Linear value	22283	570B	A	4	INTEGER_16	100	
C02293	LS_WriteParamList: Inverter motor brake: nAdd	Linear value	22282	570A	A	4	INTEGER_16	1	
C02294	LS_WriteParamList: Inverter motor brake: PT1 filter time	Linear value	22281	5709	A	4	INTEGER_16	10	
C02295	LS_WriteParamList: Flying restart fct.: activation	Selection list	22280	5708	A	4	UNSIGNED_8	1	CINH
C02296	LS_WriteParamList: Flying restart fct.: process	Selection list	22279	5707	A	4	UNSIGNED_16	1	
C02297	LS_WriteParamList: Flying restart: start frequency	Linear value	22278	5706	A	4	INTEGER_16	1	
C02298	LS_WriteParamList: Flying restart fct: int. time	Linear value	22277	5705	A	4	UNSIGNED_16	10	
C02299	LS_WriteParamList: Flying restart fct.: current	Linear value	22276	5704	A	4	INTEGER_16	100	
C02300	LS_WriteParamList: SLPSM: Controlled current setpoint	Linear value	22275	5703	A	8	UNSIGNED_16	100	
C02301	LS_WriteParamList: SLPSM: Switching speed	Linear value	22274	5702	A	8	INTEGER_16	100	
C02302	LS_WriteParamList: SLPSM: Filter time - rotor position	Linear value	22273	5701	A	4	INTEGER_16	100	
C02303	LS_WriteParamList: SLPSM: Filter time rotor position	Linear value	22272	5700	A	8	INTEGER_16	10	
C02304	LS_WriteParamList: SLPSM: PLL gain	Linear value	22271	56FF	A	4	INTEGER_16	1	
C02305	LS_WriteParamList: PSM: Ppp saturation characteristic	Linear value	22270	56FE	A	68	UNSIGNED_8	1	
C02306	LS_WriteParamList: PSM: Imax Ppp saturation characteristic	Linear value	22269	56FD	A	4	UNSIGNED_16	10	
C02307	LS_WriteParamList: PSM: Activate Ppp saturation char.	Selection list	22268	56FC	A	4	UNSIGNED_8	1	
C02311	LS_WriteParamList: PLI without motion: Adaptation of time duration	Linear value	22264	56F8	A	4	INTEGER_8	1	
C02312	LS_WriteParamList: PLI without motion	Bit coded	22263	56F7	A	4	UNSIGNED_16	1	
C02313	LS_WriteParamList: PLI without motion: Adaptation of ident angle	Linear value	22262	56F6	A	4	INTEGER_8	1	
C02315	LS_WriteParamList: Manual entry of motor type	Selection list	22260	56F4	A	4	UNSIGNED_8	1	
C02430	Axis bus address and no. of nodes	Linear value	22145	5681	A	2	UNSIGNED_8	1	
C02431	Axis bus time settings	Linear value	22144	5680	A	3	UNSIGNED_16	1	
C02435	Axis bus status	Selection list	22140	567C	E	1	UNSIGNED_8	1	
C02436	Axis bus error status	Selection list	22139	567B	E	1	UNSIGNED_8	1	
C02437	Axis bus MessageError	Selection list	22138	567A	E	1	UNSIGNED_8	1	
C02438	CAB_Tx_Rx_diagnosis	Linear value	22137	5679	A	4	UNSIGNED_16	1	
C02440	AxisBusIO slave/master	Selection list	22135	5677	A	1	UNSIGNED_8	1	
C02442	CAB decoupling inputs	Bit coded	22133	5675	A	1	UNSIGNED_16	1	
C02443	CAB decoupling value	Linear value	22132	5674	A	11	UNSIGNED_16	1	
C02444	CAB configuration	Bit coded	22131	5673	A	1	UNSIGNED_16	1	
C02580	Holding brake: Operating mode	Selection list	21995	55EB	E	1	UNSIGNED_8	1	
C02581	Holding brake: Speed thresholds	Linear value	21994	55EA	A	5	INTEGER_16	100	
C02582	Holding brake: Setting	Bit coded	21993	55E9	E	1	UNSIGNED_8	1	
C02589	Holding brake: Time system	Linear value	21986	55E2	A	4	UNSIGNED_16	1	
Grayed out = display parameter (read access only)									

Code	Name	Type	Index		Data				
			dec	hex	DS	DA	DT	Factor	CINH
C02593	Holding brake: Activation time	Linear value	21982	55DE	A	4	UNSIGNED_32	1000	
C02607	Holding brake: Status	Bit coded	21968	55D0	E	1	UNSIGNED_16	1	
C02610	MCK: Accel./decel. times	Linear value	21965	55CD	A	3	UNSIGNED_32	1000	
C02611	MCK: Limitations	Linear value	21964	55CC	A	5	INTEGER_16	100	
C02652	Settings of measuring system	Bit coded	21923	55A3	E	1	UNSIGNED_16	1	
C02810	TP: Edge selection	Selection list	21765	5505	A	9	UNSIGNED_8	1	
C02811	TP: Sensor delay	Linear value	21764	5504	A	9	UNSIGNED_16	1	
C02812	TP: Position offset	Linear value	21763	5503	A	9	INTEGER_32	10000	
C02813	TP: Pos window start	Linear value	21762	5502	A	5	INTEGER_32	10000	
C02814	TP: Pos window end	Linear value	21761	5501	A	5	INTEGER_32	10000	
C02815	TP: Position source	Selection list	21760	5500	A	9	UNSIGNED_8	1	
C02816	TP: Signal counter	Linear value	21759	54FF	A	9	UNSIGNED_16	1	
C02817	TP: TouchProbe position	Linear value	21758	54FE	A	9	INTEGER_32	10000	
C02830	Dlx: Debounce time	Selection list	21745	54F1	A	7	UNSIGNED_8	1	
C02840	CountInx: Parameter	Linear value	21735	54E7	A	4	UNSIGNED_32	1	
C02841	CountInx: Counter content	Linear value	21734	54E6	A	2	UNSIGNED_32	1	
C02842	FreqInxx: Offset	Linear value	21733	54E5	A	2	INTEGER_16	100	
C02843	FreqInxx: Gain	Linear value	21732	54E4	A	2	INTEGER_16	100	
C02844	FreqIn12: Function	Selection list	21731	54E3	A	1	UNSIGNED_8	1	
C02845	FreqIn12: PosIn comparison value	Linear value	21730	54E2	E	1	INTEGER_32	1	
C02853	PSM: Lss saturation characteristic	Linear value	21722	54DA	A	17	UNSIGNED_8	1	
C02855	PSM: Imax Lss saturation characteristic	Linear value	21720	54D8	E	1	UNSIGNED_16	10	
C02859	PSM: Activate Ppp saturation char.	Selection list	21716	54D4	E	1	UNSIGNED_8	1	
C02862	Resolver gain	Linear value	21713	54D1	A	2	UNSIGNED_16	100	
C02863	Resolver: Phase error	Linear value	21712	54D0	E	1	INTEGER_16	100	
C02864	MCTRL: Special settings 2	Bit coded	21711	54CF	A	1	UNSIGNED_16	1	
C02865	MCTRL: Special settings	Bit coded	21710	54CE	A	1	UNSIGNED_16	1	
C02866	MCTRL: Special settings	Selection list	21709	54CD	A	3	UNSIGNED_8	1	CINH
C02867	Identification process	Selection list	21708	54CC	A	1	UNSIGNED_8	1	CINH
C02870	PLI without motion: Optimisation factor	Linear value	21705	54C9	A	1	INTEGER_16	100	
C02871	PLI without motion: Running time	Linear value	21704	54C8	A	1	INTEGER_16	100	
C02872	PLI without motion: Adaptation of time duration	Linear value	21703	54C7	A	1	INTEGER_8	1	
C02873	PLI without motion: Ident. el. rotor displ. angle	Linear value	21702	54C6	A	1	INTEGER_16	1	
C02874	PLI without motion	Bit coded	21701	54C5	A	1	UNSIGNED_16	1	
C02875	PLI without motion: Adaptation of ident angle	Linear value	21700	54C4	A	1	INTEGER_8	1	
C02876	PSM: Max. motor temperature	Linear value	21699	54C3	A	1	UNSIGNED_8	1	
C02877	PSM temperature coefficient	Linear value	21698	54C2	A	1	INTEGER_16	100	
C02878	KTY motor temperature compensation	Bit coded	21697	54C1	A	1	UNSIGNED_16	1	
C02879	Slip calculation from equivalent circuit diagram	Bit coded	21696	54C0	A	1	UNSIGNED_16	1	
Grayed out = display parameter (read access only)									

18 Working with the FB Editor

The function block editor (in the following called "FB Editor") is available in the »Engineer« from the "StateLine" device version.

The FB Editor can be used to carry out an online monitoring of the technology application running in the device (e.g. for diagnostic purposes) and reconfigure the I/O interconnection of the technology application.

Functional range

The options for processing function block interconnections depend on the device version:

Function	Inverter Drives 8400		
	StateLine C	HighLine C	TopLine C
I/O interconnection can be reconfigured	●	●	●
Application interconnection can be reconfigured	●	●	●
Free interconnection	(●)	●	●
(●) Free interconnection for "StateLine C" is only available from version 12.00.00 and »Engineer« V2.17.			



Note!

The illustrations of the FB Editor user interface and the dialog boxes in this documentation are based on the »Engineer« V2.10.

18.1 Basics

Using the function block interconnection, any signal interconnection can be implemented. Various FBs are available for digital signal processing, signal conversion and logic modules.

For special tasks it has proved of value to use the integrated technology applications as a basis for modifications or extensions of the available FB interconnections. Depending on the device version (see [Functional range](#)), the experienced user has the opportunity to implement own drive solutions independent of the predefined technology applications by using the "free interconnection".

For this purpose, the FB Editor provides the following functions:

- Copying & pasting of interconnection elements (also device-independent)
- Export & import of the interconnection
- Comparison of two interconnections (also online <-> offline comparison)
- Overview window and zoom functions
- Comments on the signal flow
- Online monitoring

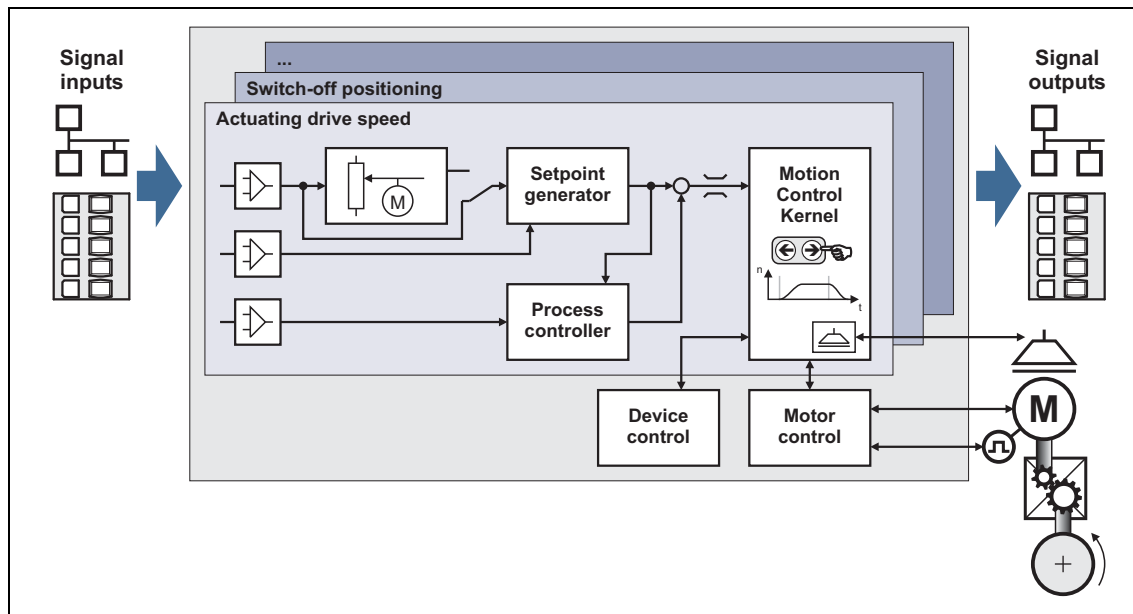
The option to mask out non-used inputs and outputs of modules is also sensible to minimise the complexity of the FB interconnection and to adapt the clarity of the interconnection to the customers need.

All graphical information of the FB interconnection view (positions of the FBs, line or flag presentation of the connection, visibility of the inputs/outputs) are saved with the parameter set in the memory module of the controller and can be uploaded any time into the FB Editor of the »Engineer« even if the Engineer project is not available.

18.1.1 Basic components of a drive solution

A drive solution consists of the following basic components:

- Signal inputs (for control and setpoint signals)
- Signal flow of the technology application
- Signal outputs (for status and actual value signals)



[18-1] Basic components of a drive solution

Regarding the 8400 device series, these three components are available for the FB interconnection and classified as follows:

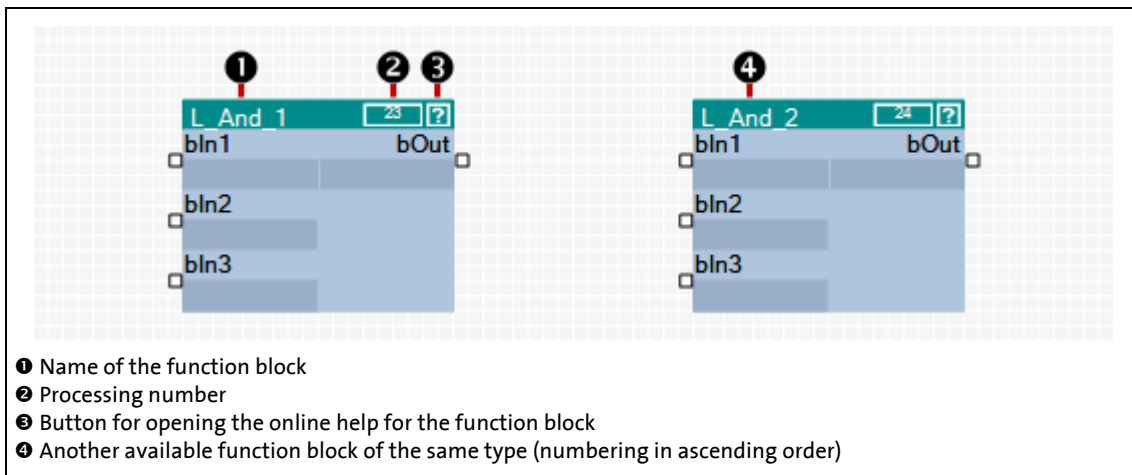
Module type	Name	Task	Example
Function block	L_name	General function block for free interconnection (only HighLine)	L_Compare_1 L_PCTRL_1
System block	LS_name	Signal interface to inverter-internal functions	LS_DigitalInput LS_DriveInterface
Port block	LP_name	<ul style="list-style-type: none"> • Process data communication via a fieldbus using a communication module • Process data communication via CAN on board 	LP_CanIn1 LP_CanOut1 LP_MciIn LP_MciOut
Application block	LA_name	Block for a technology application	LA_NCtrl LA_SwitchPos

Further information on the individual modules can be obtained from the following subchapters!

18.1.1.1 What is a function block?

A function block (FB) can be compared with an integrated circuit that contains a specific control logic and delivers one or several values when being executed.

- The function blocks are classified alphabetically in a "function library".
- Each function block has a unique identifier and a processing number which defines the position at which the function block is calculated during runtime.



[18-2] Information on a function block in the FB Editor




Tip!

A detailed description of all available function blocks can be found in the main chapter "[Function library](#)". (1381)

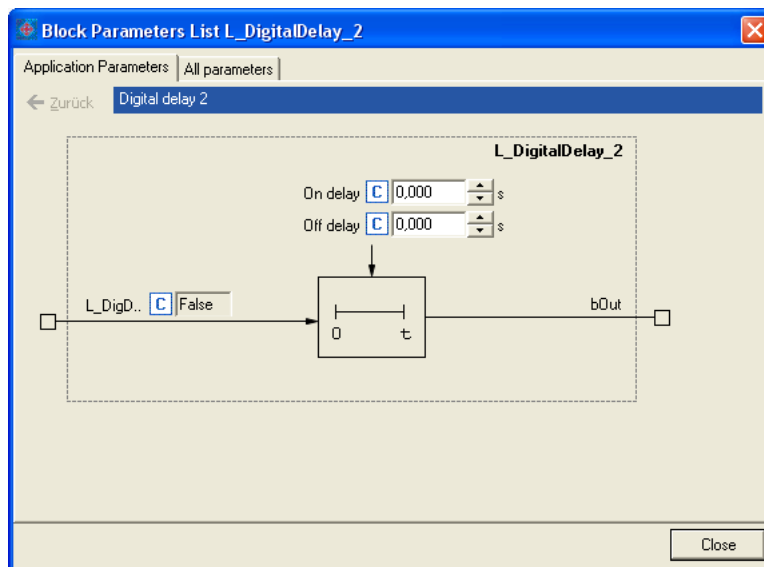
18.1.1.2 Parameterisable function blocks

Some function blocks have parameters which serve to change particular settings during operation, if required, or which display actual values & status information.

- The  icon in the head of the module, a double-click on the module, or the **Parameter...** command in the *Context menu* of the module serve to open the parameterisation dialog or the parameter list for the module.

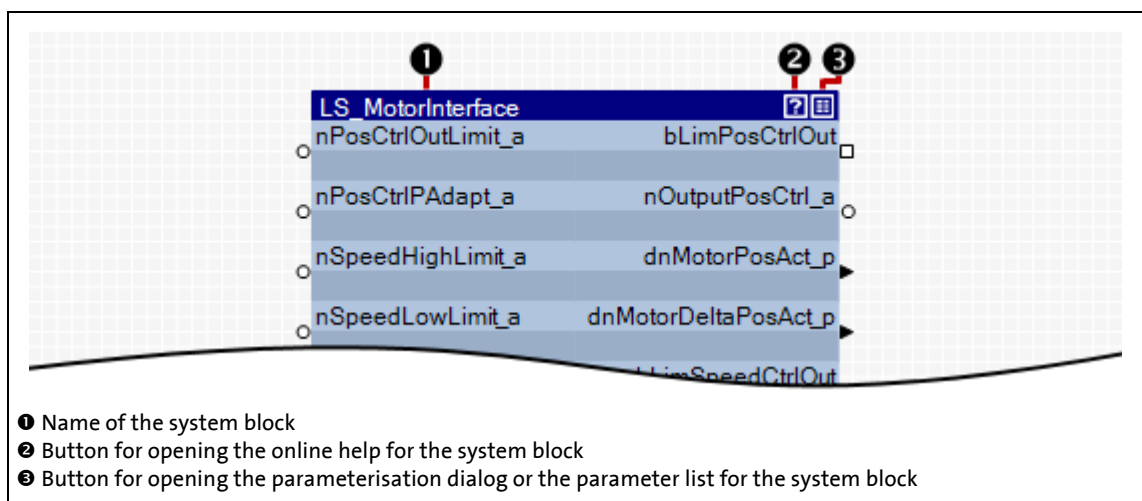
Example

Parameterisation dialog for the FB **L_DigitalDelay_2**:



18.1.1.3 What is a system block?

System blocks are a special variant of a function block. They partly activate real hardware, e. g. the digital and analog inputs/outputs and the motor control.



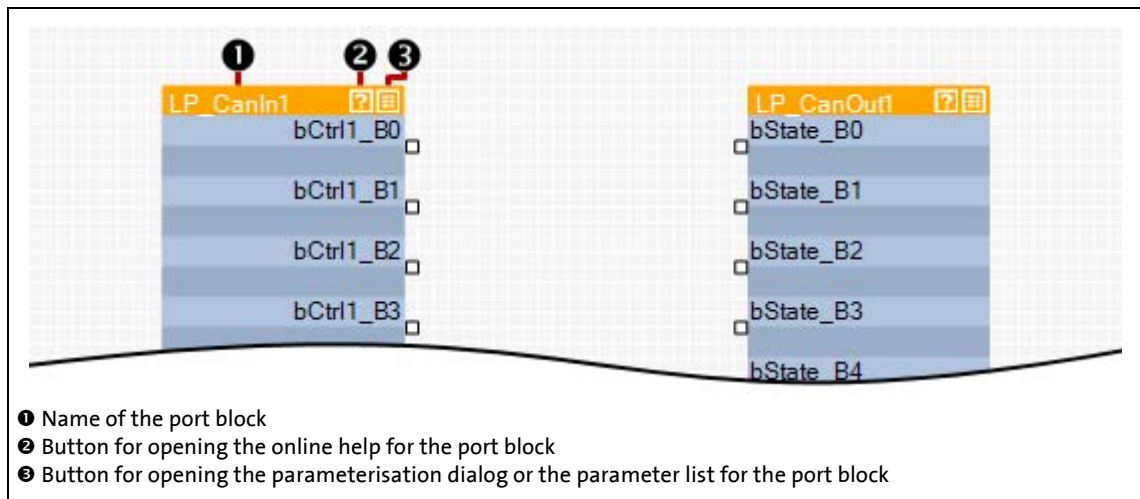
[18-3] Example: System block "LS_MotorInterface" for mapping the motor control

18.1.1.4 What is a port block?

A port block is a signal interface to a fieldbus. Input/output ports represent the input and output process data of the fieldbus.

- Port blocks LP_CanIn/LP_CanOut: Signal interface to the CAN bus
- Port blocks LP_MciIn/LP_MciOut: Signal interface to a plugged fieldbus module

If, for instance, the controller is to be controlled via CAN bus or a fieldbus module, the input/output ports are connected to the application block (device-internal signal processing) in the I/O level of the FB Editor.



[18-4] Example: Input port "LP_CanIn1" and output port "LP_CanOut1"

18.1.1.5 What is an application block?

The application/technology function set in [C00005](#) is shown as application block in the I/O level of the FB Editor.

The application block comprises the signal flow processing generated via function block interconnection for the selected application in each case (e.g. "actuating drive speed" or "switch-off positioning"). The function block interconnection is shown in detail on the application level.



Tip!

Every application block features so-called "free inputs and outputs" which you can use to transfer signals from the I/O level to the application level and vice versa.

- In the Lenze setting, these connectors are hidden in the function block editor.
- These connections can be shown via the **Connector visibilities** command in the *Context menu* of the application block.

18.1.2 Conventions used for input/output identifiers

This chapter describes the conventions used for the identifiers of the inputs/outputs of the blocks. The conventions ensure a uniform and consistent terminology and make reading and comprehending the interconnection and application easier.



Tip!

The conventions used by Lenze are based on the "Hungarian Notation". This ensures that the most significant characteristics of the corresponding input/output (e.g. the data type) can be instantly recognised from its identifier.

An identifier consists of

- a data type entry
- an identifier (the "proper" name of the input/output)
- an (optional) signal type specification

Data type entry

The data type entry provides information about the data type of the corresponding input/output:

Data type entry	Meaning	Resolution	Value range
b	BOOL	1 bit	0 ≡ FALSE / 1 ≡ TRUE
dn	DINT	32 bits	-2147483647 ... 2147483647
n	INT	16 bits	-32767 ... 32767
w	WORD	16 bits	0 ... 65535

Identifier







The identifier is the proper name of the input/output and should indicate the application or function.

- Identifiers always start with a capital letter.
- If an identifier consists of several "words", then each "word" must start with a capital letter.
- All other letters are written in lower case.

Signal type entry




In general, it is possible to assign a certain signal type to the inputs and outputs of the Lenze function blocks. There are e.g. digital, scaled, position, acceleration and speed signals.

- A corresponding ending (preceded by an underscore) is added to the identifier of the corresponding input/output to indicate the signal type.

Signal type entry & port symbol in the FB Editor	Meaning	Resolution	Value range
<u>_a</u> 	Analog/scaled	16 bits	± 199.99 %
<u>_v</u> 	Angular velocity	16 bits	± 30000.0 rpm
<u>_p</u> 	Position	32 bits	-2 ³¹ ... 2 ³¹ -1 increments
	Digital (BOOL)	8 bits	0 ≡ FALSE; 1 ≡ TRUE
	Other (WORD)	16 bits	0 ... 65535
	Other (DINT)	32 bits	-2147483647 ... 2147483647

18.1.3 Scaling of physical units

With regard to the parameter setting & configuration of the controller it is very helpful to know the signal types and their scaling listed in the following table, which are used to process physical values (e.g. an angular velocity or position) in the function block interconnection.

Signal type entry & port symbol in the FB Editor	Meaning	Scaling	
		External value	≡ internal value
<u>_a</u> 	Analog/scaled	100 %	≡ 2 ¹⁴ ≡ 16384
<u>_v</u> 	Angular velocity	15000 rpm	≡ 2 ¹⁴ ≡ 16384
<u>_p</u> 	Position	1 encoder revolution	≡ 2 ¹⁶ increments

18.2

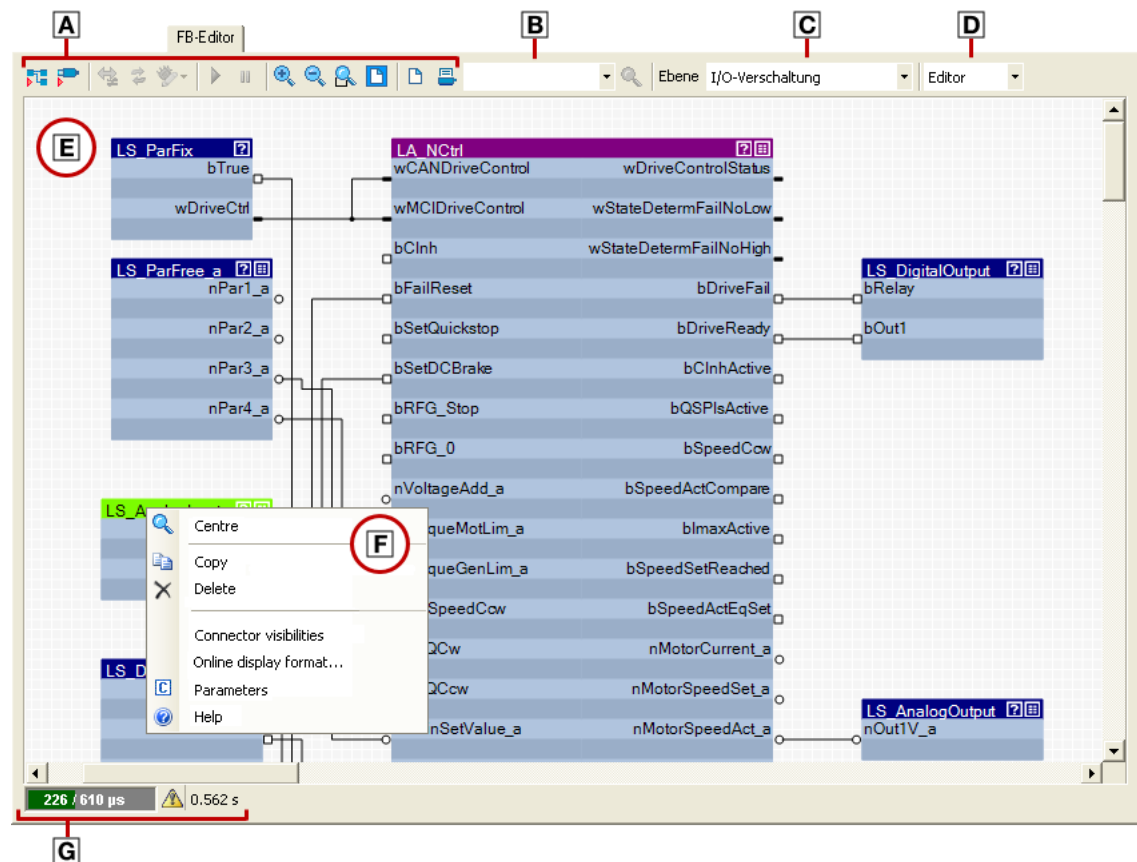
User interface

**How to access the FB Editor:**

1. Go to *Project View* and select the 8400 controller.
2. Go to *Workspace* and select the **FB Editor** tab.

The FB Editor displays the wiring of the technology function selected in [C00005](#). The interconnection of the I/Os of the controller depend on the control mode selected in [C00007](#).

The user interface of the FB Editor includes the following control and function elements:



A [Toolbar](#)

B [Search function](#)

C [Level selection](#)

D [Editor view/overview](#)

E Drawing area

F [Context menu](#)

G [Status bar](#)

Not shown:
[Overview window](#)
















**Tip!**

Go to the »Engineer« toolbar and click the  icon to hide the *Project View* and the *Message Window*. This increases the *Workspace* available for the FB Editor. A renewed click on the symbol shows the *Project View* and the *Message Window* again.

18.2.1 Toolbar

The FB Editor is provided with an individual toolbar in the upper position which in the following text is called *FB Editor toolbar*.

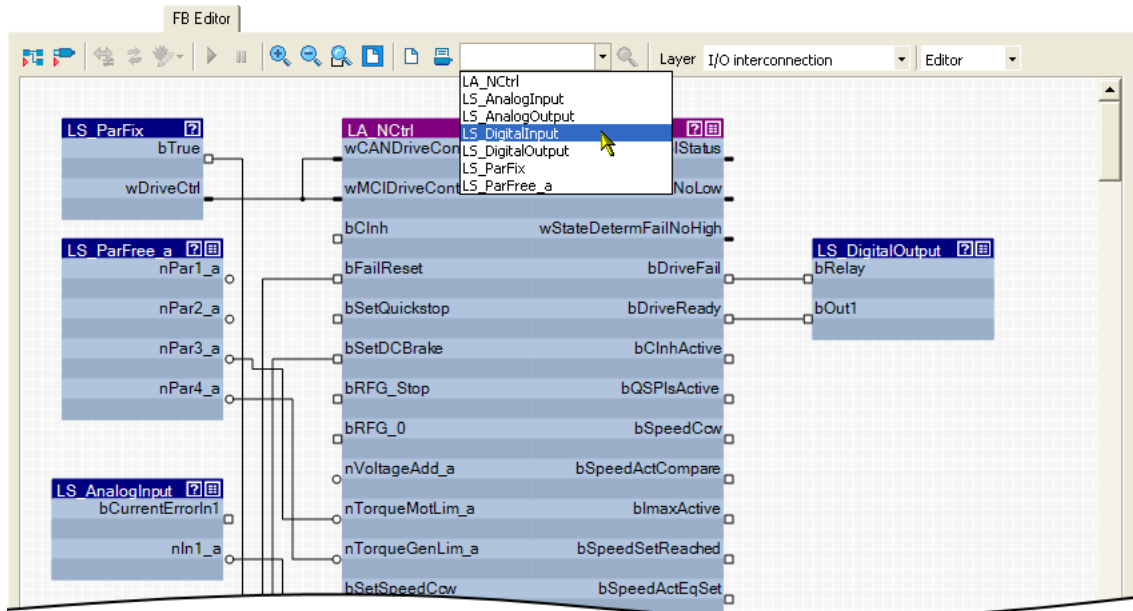
- Click an icon to execute the corresponding function.

Icon	Function
	Insert function block or system block ▶ Inserting a function block (1351) ▶ Inserting a system block (1353)
	Inserting a port block (1355)
	Adjusting online and offline interconnection (1374)
	Acknowledge error in the interconnection / reload interconnection
	Correct interconnection
	Start online monitoring
	Interrupt online monitoring
	Close online monitoring
	Enlarge view of interconnection
	Reduce view of interconnection
	Enlarge cutout of interconnection
	Show total interconnection in the drawing area
	Show print view
	Printing the interconnection (1375)
	Search function (1338)

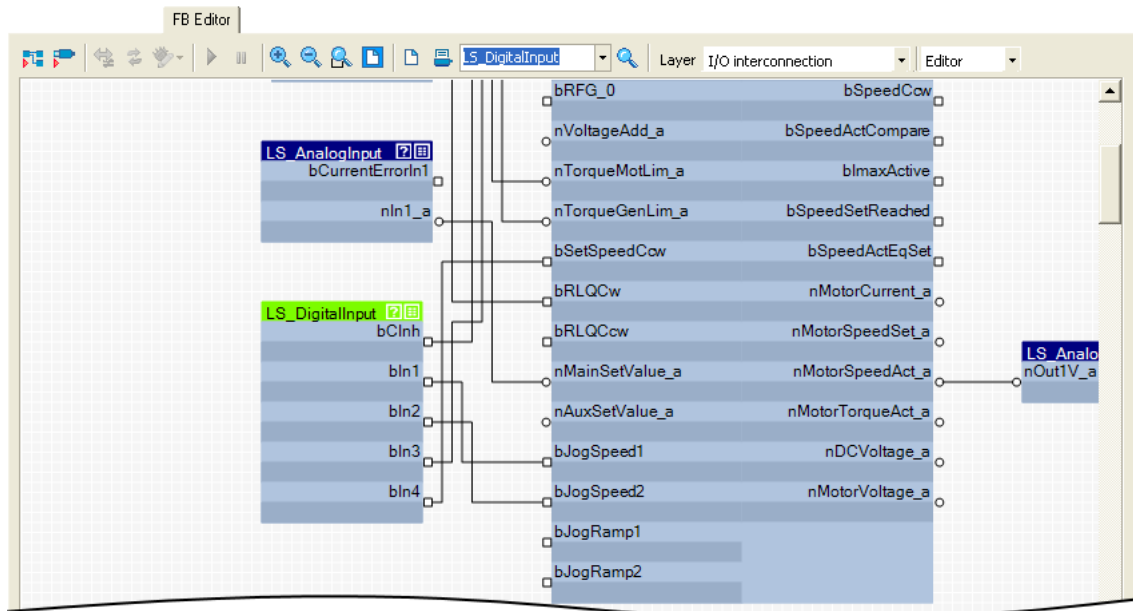
18.2.2 Search function

Use the search function to get quickly to a certain module of the interconnection.

- The list field of the search function contains all function blocks, system blocks, and port blocks of the interconnection:





- When you select a module in the list field, this module is zoomed in and selected at the same time (the following example shows the **LS_DigitalInput** system block):



**Tip!**

You can also enter any search text in the input field.

- If you click the  icon, the cutout is moved to the object which contains this search text.
- Another click on the  icon leads to a new search. Thus, you can navigate successively to all objects which contain the entered search text.
- The search text does not consider case sensitivity.

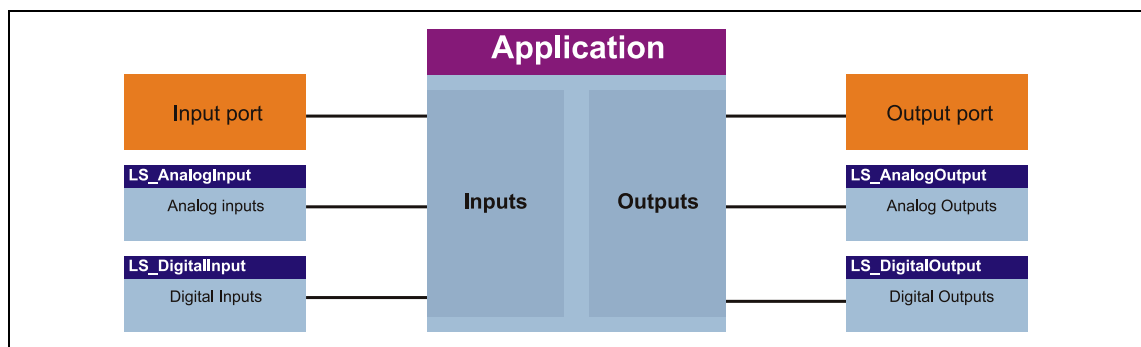
18.2.3 Level selection

Go to the **Level selection** list field and select the interconnection level to be displayed.

"I/O interconnection" level

This level displays only the I/O interconnection of the currently selected technology application for a better overview.

- Details of the application are masked out in this level.
- The interconnection of the I/Os of the controller with the inputs and outputs of the application in detail depends on the control mode selected in [C00007](#).
- The parameterisation dialogs on the **Application parameter** tab correspond to the application block displayed in this level.

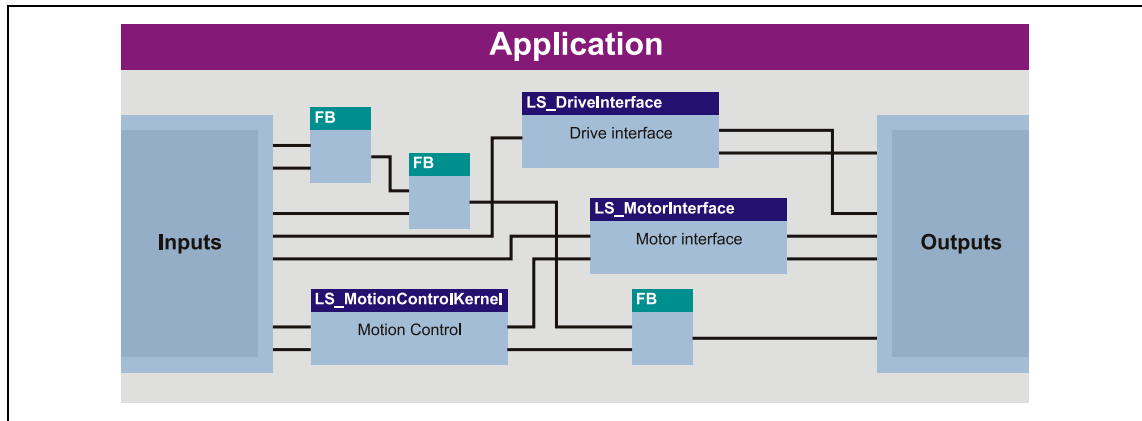


[18-5] Schematic diagram of "I/O interconnection"

"Application interconnection" level

This level displays the interconnection of the application selected in [C00005](#) in detail. All function blocks used in the application and the system blocks which provide the interfaces to the drive and motor interface and to the MotionControlKernel (MCK) are displayed with their connections.

- The interconnection of the I/Os of the controller with the inputs and outputs of the application is masked out in this level.



[18-6] Schematic diagram of "Application interconnection"



Tip!

Every application block features so-called "free inputs and outputs" which you can use to transfer signals from the I/O level to the application level and vice versa.

- In the Lenze setting, these connectors are hidden in the function block editor.
- These connections can be shown via the **Connector visibilities** command in the *Context menu* of the application block.

"Free interconnection" level

This level serves to implement an individual drive solution for the device versions "Stateline C" (from version 12.00.00 and »Engineer« V2.17), "HighLine C" and "TopLine C".



Note!

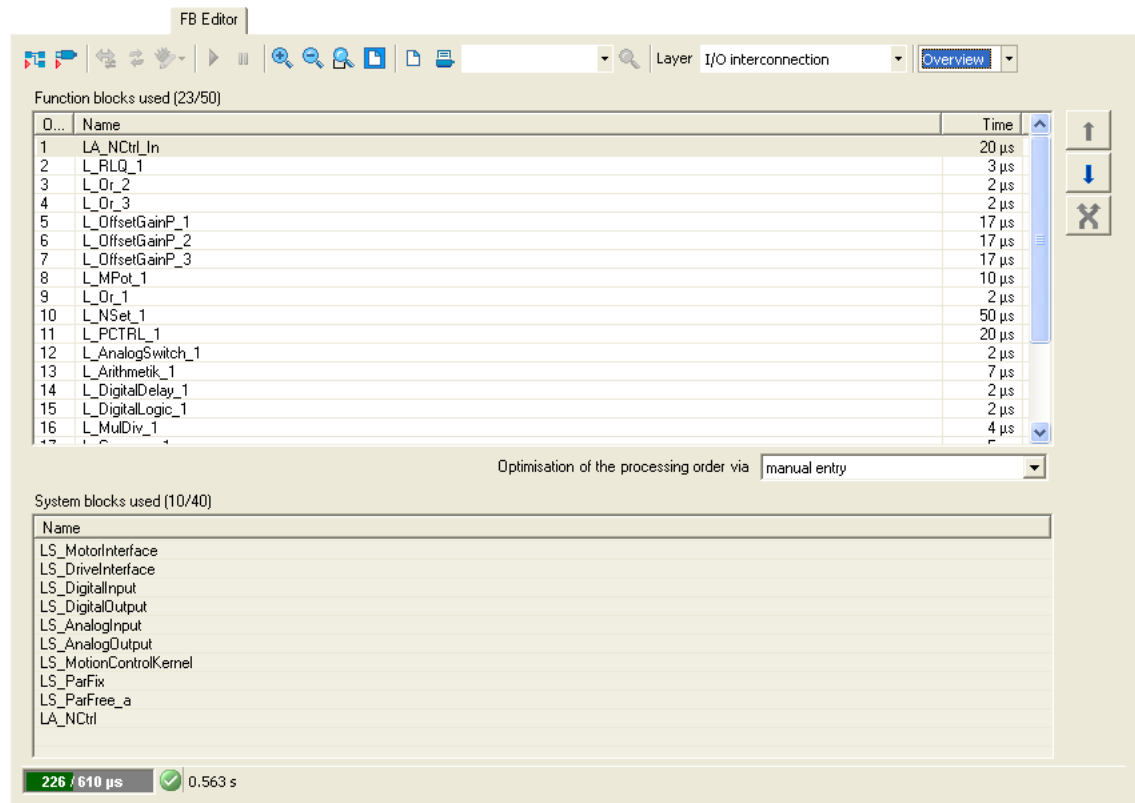
When you select the "Free interconnection" level for the first time, you are prompted to confirm whether the interconnection from the I/O level and the application level are to be combined and copied into this level.

When you confirm this confirmation prompt with **Yes**, the I/O level and the application level are not available anymore. This action can only be undone by resetting the application to a predefined Lenze application! ▶ [Resetting changed interconnection](#) (1373)

18.2.4 Editor view/overview

Use the list field at the top right to change from the Editor to the overview and vice versa.

The overview shows all function blocks used of the interconnection in the upper list field in the order of their processing. The lower list field shows all used system blocks.

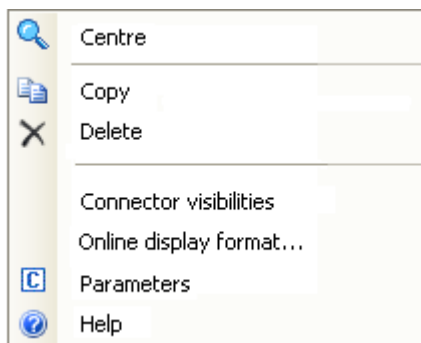


- The processing order of the function blocks can be optimised manually or according to an automatically generated selection. ▶ [Changing the processing order](#) (1368)

18.2.5 Context menu

You can open a *context menu* via the right mouse button for each object (function block, system block, line, comment, etc.) and for the drawing area:

- The contents of the *context menu* depend on the type of object you click on.
- Example: *Context menu* for a function block:



18.2.6 Status bar

The status bar of the FB Editor shows, among other things, information about the system load and the error status of the interconnection:



Icon	Meaning
A System load	
	Here: out of the available computing time of 610 µs, 226 µs are required by the application.
B Error status of the interconnection	
	The interconnection has no errors and no warnings
	The interconnection has errors and/or warnings
C Communication status	
	Offline
	Online
	Communication error
D Adjustment status	
	Offline and online interconnection match
	Offline and online interconnection are different
E Update rate for monitoring values	

18.2.7 Overview window

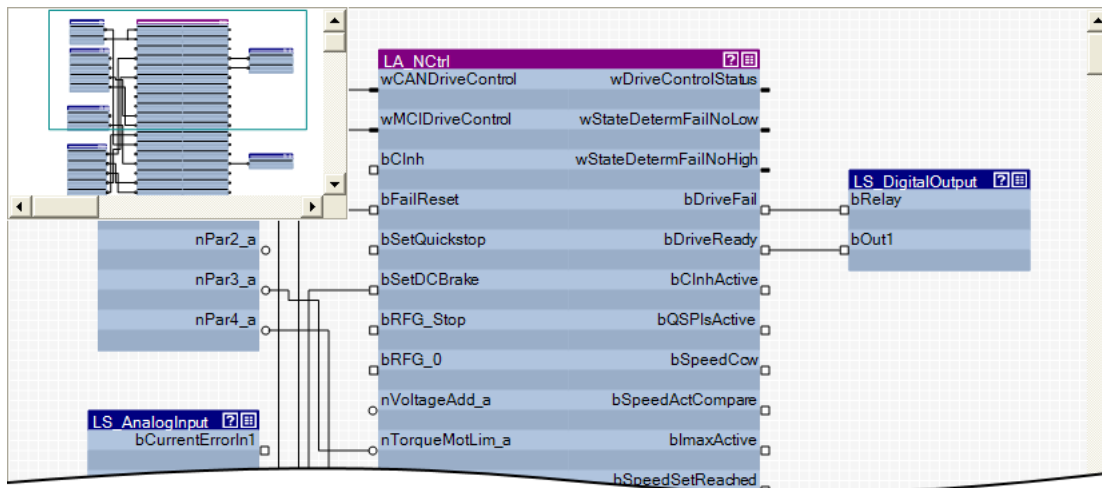
The overview window shows the drawing area in a reduced view. The overview window serves to e.g. move quickly through a more complex interconnection.



How to show the monitor window:

Go to the *Context Menu* of the drawing area and select the **Overview Window**.

- If you execute this command again, the overview window is hidden again.



- The green frame in the overview window indicates the interconnection cutout that is currently displayed in the drawing area.
- Use the mouse pointer to shift and resize the cutout to be displayed.



How to shift the cutout presented in the drawing area:

1. Position the mouse pointer to the green frame in the overview window.
 - The mouse pointer symbol becomes a positioning cross.
2. Click left mouse button and shift the green frame to its new position by keeping the mouse button pressed, so that the desired cutout of the interconnection is displayed in the drawing area.



How to redefine the cutout to be presented:


In the overview window draw a frame around the area of the interconnection which is to be presented in the drawing window by keeping the left mouse button pressed:



- The aspect ratio of the frame is automatically adapted to the aspect ratio of the drawing area.
- According to the size of the frame that is drawn, also the presentation size of the objects in the drawing area changes.



Tip!

Go to the *FB Editor toolbar* and click the  icon to adapt the view size so that all objects included in the interconnection are visible in the drawing area.

Automatic scroll ("AutoScroll function")

If you reach a window limitation in the drawing area when shifting an object or in the overview window when shifting the green frame, and if you then shortly hold the mouse pointer in this position, an automatic scrolling into the corresponding direction is carried out:

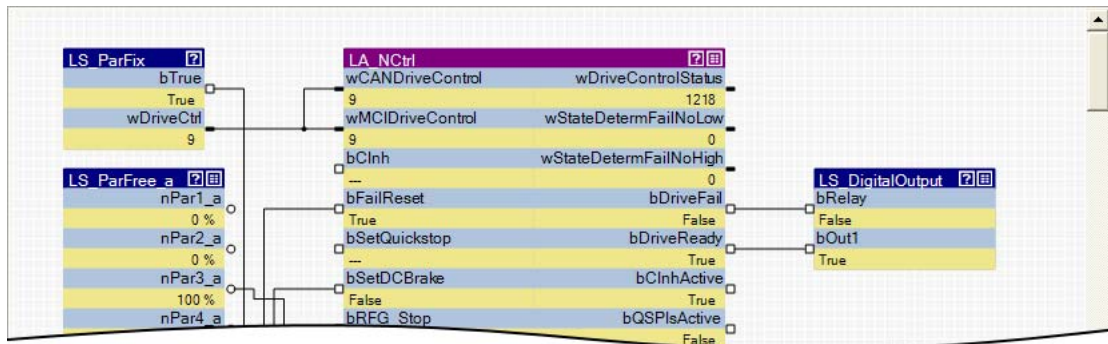
18.3 Using the FB Editor as "Viewer"

The main purpose of the FB Editor is the individual configuration of the selected technology application. However, you can also use the FB Editor to

- make a diagnosis of the application (when an online connection has been established),
- get a better understanding for the operating mode of the application,
- use the interconnection as an alternative parameterisation access.

Diagnostics of the application


When an online connection to the controller has been established, the current values are displayed at the inputs and outputs of the objects.




- Process-scaled signals can be scaled in a "user-defined" way for easy diagnostics in the FB Editor.
 ▶ [Change online display format](#) (📖 1348)

Getting a better understanding for the operating mode of the application

Make yourself familiar with the signal flow of the interconnection to get a better understanding of the operating mode of the application or individual functional areas.

- The  symbol in the head of the block or the **Help** command in the *context menu* for the block serve to open the online help for the block.

Using the interconnection as an alternative parameterisation access

- The  icon in the head of the module, a double-click on the module, or the **Parameter...** command in the *Context menu* of the module serve to open the parameterisation dialog or the parameter list for the module.

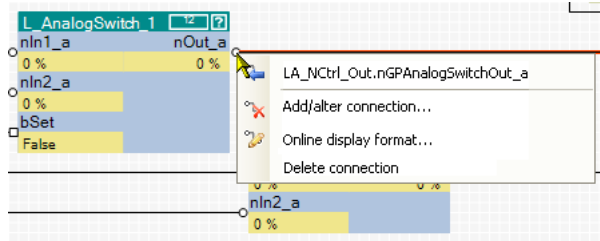
18.3.1 Following connections of inputs and outputs

In addition to the [Search function](#) you can use the *context menu* of inputs and outputs to follow connections and quickly reach certain signals.

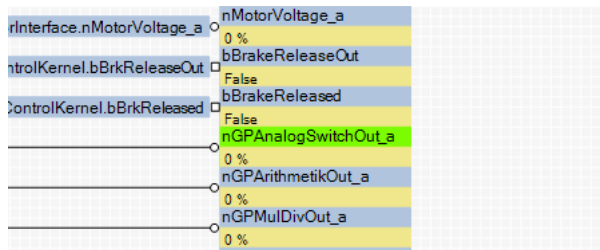


How to navigate from one output to another connected input:

1. Open the *context menu* (right mouse button) of the port symbol at the output.
 - The *context menu* for the port symbol contains all inputs which are connected to the output:



2. Select input in the *context menu* to which you want to navigate.
 - As a result, the selected input is displayed in the centre of the drawing area (in this example: nGPAnalogSwitchOut_a):

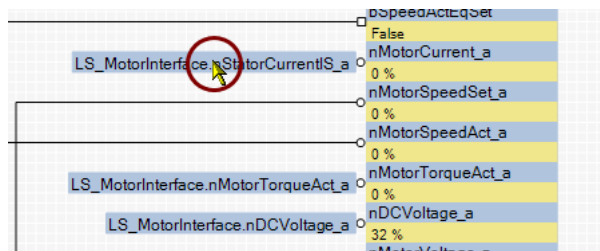




How to navigate from one input to another connected output:

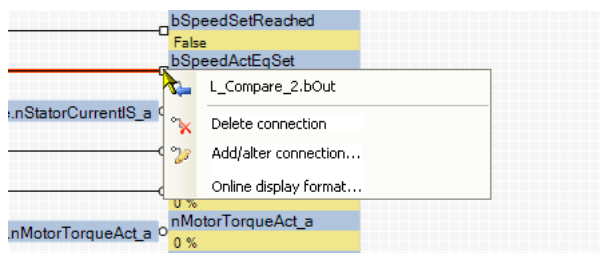
If the input is connected to a flag:

- Double-click the flag:



If the input is connected to a line:

1. Open the *context menu* (right mouse button) of the port symbol at the output:



2. Select output in the *context menu*.
 - Since an output can only be connected to an input, the *context menu* contains only an output.

The output is displayed in the centre of the drawing area.

18.3.2 Keyboard commands for navigation

Keyboard command	Function
<Picture ▲ >	Scroll up
<Picture ▼ >	Scroll down
<Shift> + <picture ▲ >	Scroll to the left
<Shift> + <picture ▼ >	Scroll to the right
<POS1>	Scroll to the left edge of the interconnection
<END>	Scroll to the right edge of the interconnection
<Ctrl> + <Pos1>	Scroll to the left upper corner of the interconnection
<Ctrl> + <End>	Scroll to the right lower corner of the interconnection

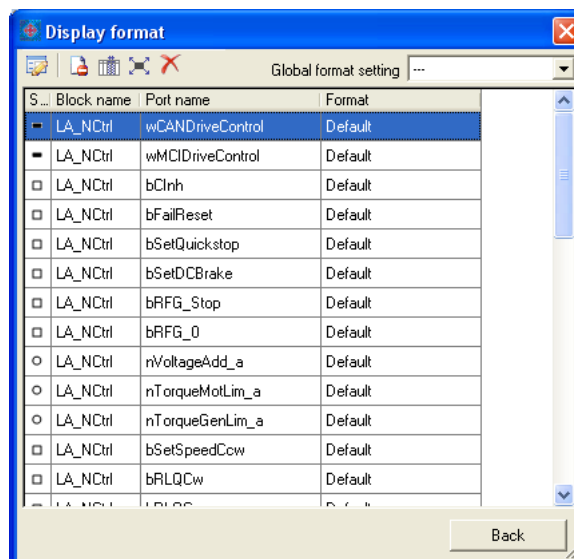
18.3.3 Change online display format





For online monitoring in the FB Editor the display format of the input and output data of a block can be adapted individually. Process-scaled signals can be scaled in a "user-defined" way for easy diagnostics in the FB Editor. Thus, the display of these signals gets a process reference.




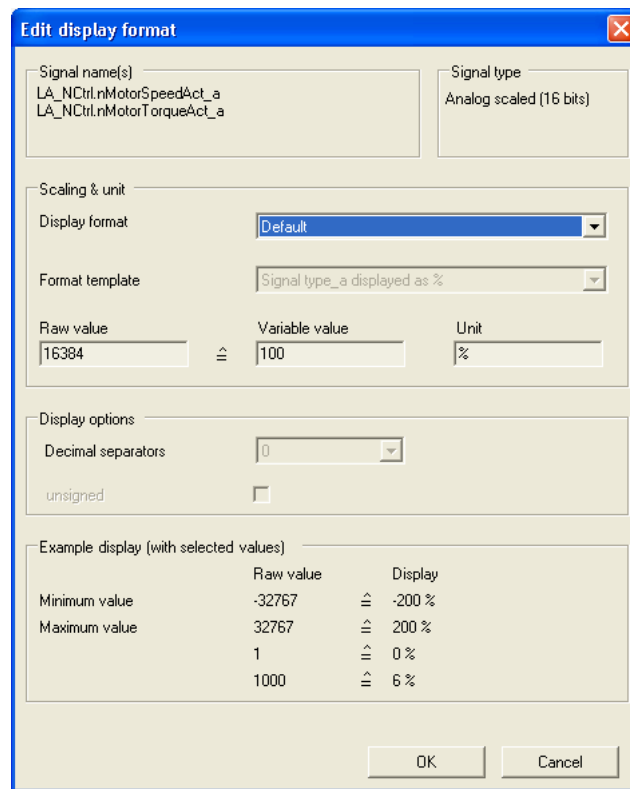
How to change the data display format of block inputs/outputs:

- Go to the *context menu* of the block and select the **Online display format** command.
 - Tip:** You can call the *context menu* of a block by clicking with the right mouse button on the header of the block.
 - The *Display format* dialog box is displayed:



- Select the inputs/outputs from the list the display format of which is to be changed.
 - Note:** In the **Global format setting** list field the "---" entry must be selected so that the display format can be changed.
 - If you click further inputs/outputs while pressing **<Ctrl>** they are added to an already existing selection (multi-selection).
 - The **<Shift>** key serves to select a related area of inputs/outputs.
 - More functions:
 -  Display masked out connections
 -  Display additional information
 -  Select all inputs/outputs
 -  Reset all format information

3. Click the  symbol to edit the display format of the selected inputs/outputs.
 - The *Edit display format* dialog box is displayed:



Example display (with selected values)		
	Raw value	Display
Minimum value	-32767	-200 %
Maximum value	32767	200 %
	1	0 %
	1000	6 %

4. Go to the **Display format** list field and select the "User-defined" entry.
5. Go to the **Format template** list field and select "No template".
6. Select the required scaling, unit, number of decimal positions, and sign handling.
7. Click **OK** to accept the settings and close the *Edit display format* dialog box.
 - The *Display format* dialog box now displays the text "User-defined" for the changed inputs/outputs in the **Format** column.

After all required formats have been changed:

8. Click **Back** to close the *Display format* dialog box.
 - For online monitoring, the changed format is used.

18.4 Reconfiguring the predefined interconnection

How to proceed:

1. Insert additionally required objects into the interconnection.
2. Hide unneeded inputs/outputs of function blocks and system blocks to obtain a clearly arranged interconnection.
3. Arrange the objects in the drawing area in a reasonable manner.
4. Establish the connections required for the desired function.
5. If required, change (optimise) the processing order of the function blocks.



Tip!

Detailed information on the individual steps can be obtained from the following subchapters!





Note!

With the "StateLine" version, the interconnection shown in the application level cannot be edited.

18.4.1 Inserting/Deleting objects

Objects can be inserted in the interconnection via the *FB Editor toolbar* and the *context menu* of the drawing area. The following subchapters provide detailed information on how to insert/delete the different objects.

Icon	Function
	Inserting a function block (1351)
	Inserting a system block (1353)
	Inserting a port block (1355)
	Inserting a comment (1357)



Tip!

Use the *context menu* of the drawing area to insert a function block, system block, port block or comment directly to the current position of the mouse pointer in the drawing area.

If you insert an object via the corresponding icon in the *FB Editor toolbar*, the object is always placed at the top left corner in the drawing area.

Interconnection elements cannot only be copied within the same interconnection but also across all devices within the same project, as long as the devices stem from the same product family. ▶ [Copying interconnection elements \(across all devices\) \(1370\)](#)

18.4.1.1 Inserting a function block



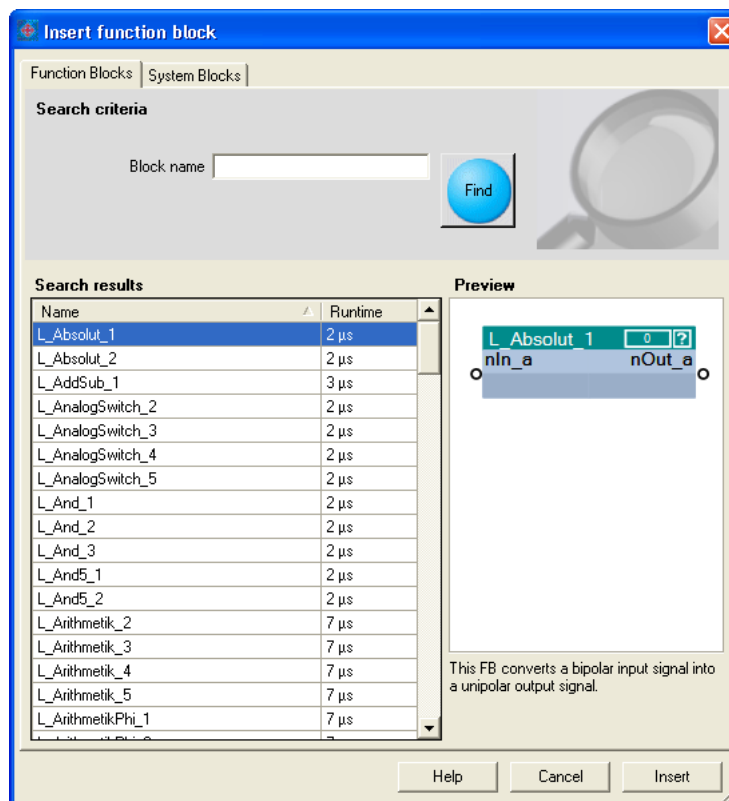
Note!

In the FB Editor, function blocks are only available in the "Application interconnection" level!



How to insert a function block into the interconnection:

1. In the *FB Editor toolbar*, click the icon.
 - The *Insert Function Block* dialog box appears:
2. Unless it is already displayed, select the **Function Blocks** tab.
 - All function blocks available are displayed in the **Search results** list field.






- A preview of the selected function block is displayed.
 - A detailed description of all available function blocks can be found in the main chapter "[Function library](#)". ([1381](#))
3. If required, define **Search criteria** to narrow down the available function blocks:
 - **Block name:**
String which must be contained in the name of the function block.
 4. After changing the search criteria, press the **Find** button to update the selection.
 - Then, only the function blocks complying with the features set in the search criteria are shown in the **Search Results** list field.
 - If no search criteria are set, all function blocks available are shown.
 5. Select the function block to be inserted in the **Search results** list field.

6. Press **Insert** button.

- The dialog box is closed and the selected function block is inserted into the interconnection.

Context menu for the function block

If you right-click on the header of a function block, a *context menu* opens via which you can execute the following functions in addition to the general processing functions (Copy, Insert, Delete):

Command	Function
 Center	Move the visible cutout of the drawing area so that the block is centred.
Connector visibilities...	Define visible inputs and outputs of the block. ▶ Changing connector visibilities (📖 1360)
Online display format...	Adapt the display format of the input and output data of the block individually for online monitoring. ▶ Change online display format (📖 1348)
 Parameter...	Open the parameter list/parameterisation dialog for the block. • Only if function block is parameterisable.
 Help	Show online help for the block.

Related topics


- ▶ [Deleting objects that are no longer required](#) (📖 1359)
- ▶ [Changing connector visibilities](#) (📖 1360)
- ▶ [Arranging objects in the drawing area](#) (📖 1361)
- ▶ [Creating/deleting connections](#) (📖 1362)
- ▶ [Changing the processing order](#) (📖 1368)

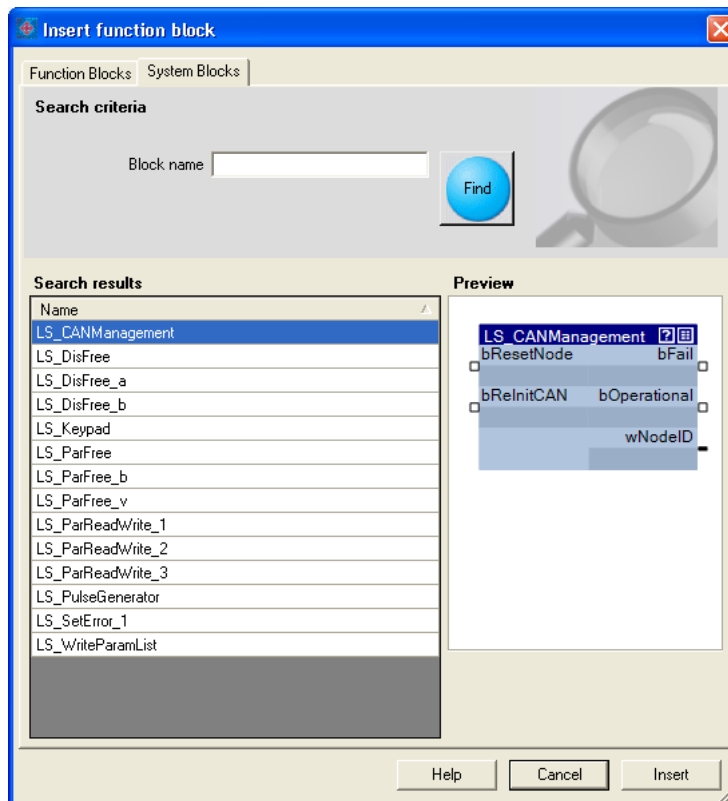
18.4.1.2 Inserting a system block

A system block is inserted similarly to the way a function block is inserted.



How to insert a system block into the interconnection:

1. In the *FB Editor toolbar*, click the  icon.
 - The *Insert Function Block* dialog box appears:
2. Unless it is already displayed, select the **System Blocks** tab.
 - All system blocks available are displayed in the **Search results** list field.






- A preview of the selected function block is displayed.
3. If required, define **Search criteria** to accordingly narrow down the system blocks available:
 - **Block name:**
String which must be contained in the name of the system block.
 4. After changing the search criteria, press the **Find** button to update the selection.
 - Then, only the system blocks complying with the features set in the search criteria are shown in the **Search Results** list field.
 - If no search criteria are set, all system blocks available are shown.

5. Select the system block to be inserted in the **Search results** list field.
6. Press **Insert** button.
 - The dialog box is closed and the selected system block is inserted into the interconnection.

Context menu for the system block

If you right-click on the header of a system block, a *context menu* opens via which you can execute the following functions in addition to the general processing functions (Copy, Insert, Delete):

Command		Function
	Center	Move the visible cutout of the drawing area so that the block is centred.
	Connector visibilities...	Define visible inputs and outputs of the block. ▶ Changing connector visibilities (📖 1360)
	Online display format...	Adapt the display format of the input and output data of the block individually for online monitoring. ▶ Change online display format (📖 1348)
	Parameter...	Open the parameter list/parameterisation dialog for the block.
	Help	Show online help for the block.

Related topics

- ▶ [Deleting objects that are no longer required](#) (📖 1359)
- ▶ [Changing connector visibilities](#) (📖 1360)
- ▶ [Arranging objects in the drawing area](#) (📖 1361)
- ▶ [Creating/deleting connections](#) (📖 1362)

18.4.1.3 Inserting a port block

All input/output ports defined for the application on the **Ports** tab can be inserted into the interconnection in the form of port blocks in order to get access to the associated element variables.




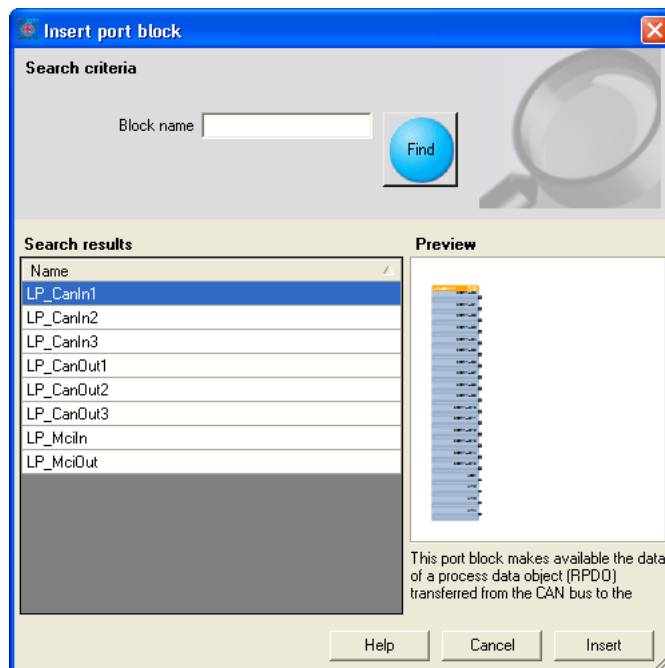
Tip!

You can change between the **Ports** and **FB Editor** tabs at any time to define new ports and afterwards insert them into the interconnection.



How to insert a port block into the interconnection:




1. In the *FB Editor toolbar*, click the  icon.
 - The *Insert port block* dialog box appears.
 - All port blocks available are displayed in the **Search results** list field.



- A preview of the selected port block is displayed.
2. If required, define **search criteria** to accordingly narrow down the port blocks available:
 - **Block name:**
String which must be contained in the name of the port block.
 3. After changing the search criteria, press the **Find** button to update the selection.
 - Then, only the port blocks complying with the features set in the search criteria are shown in the **Search Results** list field.
 - If no search criteria are set, all port blocks available are shown.
 4. Select the port block to be inserted in the **Search results** list field.
 5. Press **Insert** button.
 - The dialog box is closed and the selected port block is inserted into the interconnection.

Context menu for the port block

If you right-click on the header of a port block, a *context menu* opens via which you can execute the following functions in addition to the general processing functions (Copy, Insert, Delete):

Command	Function
 Center	Move the visible cutout of the drawing area so that the block is centred.
Connector visibilities...	Define visible inputs and outputs of the block. ▶ Changing connector visibilities (📖 1360)
Online display format...	Adapt the display format of the input and output data of the block individually for online monitoring. ▶ Change online display format (📖 1348)
 Parameter...	Open the parameter list/parameterisation dialog for the block.
 Help	Show online help for the block.

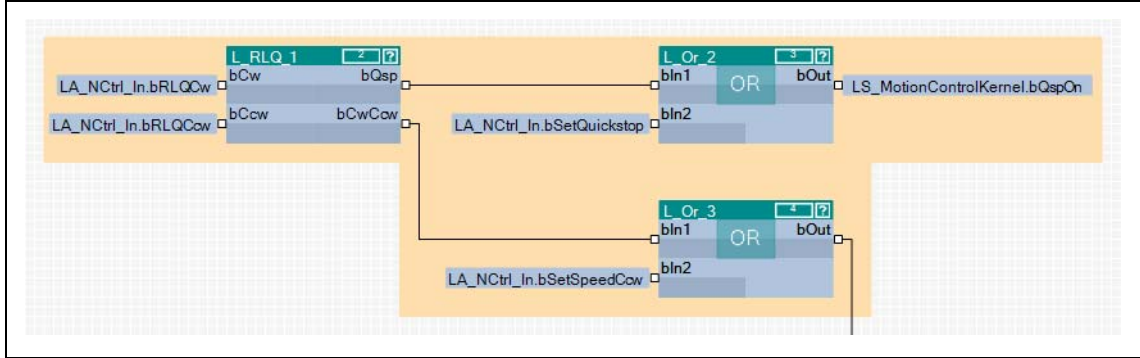
Related topics

- ▶ [Deleting objects that are no longer required](#) (📖 1359)
- ▶ [Changing connector visibilities](#) (📖 1360)
- ▶ [Arranging objects in the drawing area](#) (📖 1361)
- ▶ [Creating/deleting connections](#) (📖 1362)

18.4.1.4 Inserting a comment

Comments can be inserted at any position in the drawing area.

As of the »Engineer« V2.10, the interior colour and text alignment of a comment can be changed via a properties dialog. Now the sizes of comments can also be changed using the mouse pointer. When using different interior colours you can use comments to graphically arrange areas that belong together in terms of function or separate them from other areas:



[18-7] Example: Graphical arrangement of FBs by means of two comments that overlap.



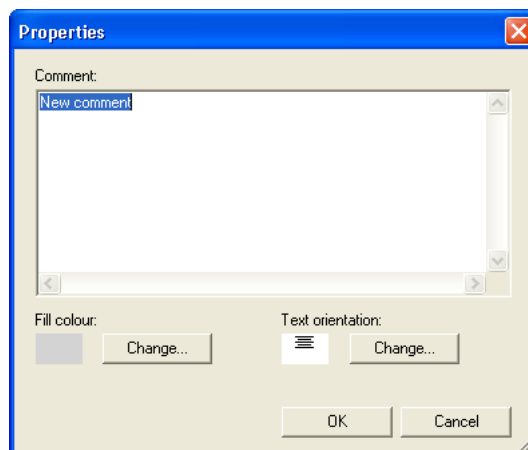
Note!

The term "Arrangement" does not mean a logical arrangement of the function blocks. The comments are only graphical presentation elements of the FB Editor.



How to insert a new comment into the interconnection:

1. Move the mouse pointer to the (free) position in the drawing area where the comment is to be inserted.
2. Go to the *Context menu* (right mouse key) and select the **New comment** command.
 - The *Properties* dialog box is displayed:



3. Enter the required comment into the text field.
4. Optional: Change preset interior colour.
 - For this purpose, click the left **Change...** button to open the *Colour* dialog box to select another interior colour.

5. Optional: Change preset text alignment.
 - For this purpose, click the right **Change...** button to open the *Text alignment* dialog box to select another text alignment.
6. Press **OK** to close the *Properties* dialog box and insert the comment.
 - After being inserted, the corner points of the comment are shown:



7. Optional: Change size of the comment.
 - For this purpose click one of the corner points with the left mouse button and enlarge the comment to the required size with the mouse button pressed.



8. Optional: Drag comment.
 - For this purpose click the comment with the left mouse button and move the comment to the required position with the mouse button pressed.

**Tip!**

The *Properties* dialog box for a comment already available can be opened by double-clicking the comment.

Related topics

- ▶ [Deleting objects that are no longer required](#) (📖 1359)
- ▶ [Arranging objects in the drawing area](#) (📖 1361)
- ▶ [Creating/deleting connections](#) (📖 1362)

18.4.1.5 Deleting objects that are no longer required

Objects that are no longer required can be easily deleted again. "Delete" only means that the object is removed from the drawing area. If you have deleted an object from the drawing area, you can reinsert it any time into the interconnection.



Note!

Deleting an object cannot be undone.

Together with the object, all available connections to this object are deleted.



How to delete objects that are no longer required:

1. Select objects to be deleted.
 - You can select a single object by clicking the header of the object.
 - You can select objects that are placed together by drawing a frame around these objects while keeping the mouse button pressed.
 - If you click the header of further objects while pressing **<Ctrl>**, these will be added to an already existing selection (multi-selection).
 - All selected objects are highlighted by a light green header.
2. Press ****.

Related topics

▶ [Deleting connections that are no longer required](#) (📖 1367)

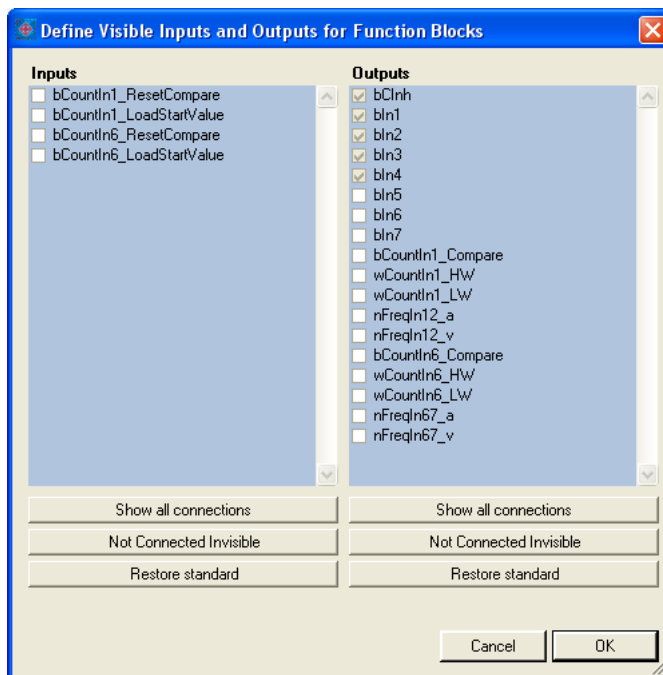
18.4.2 Changing connector visibilities

Inputs and outputs that are not connected can be hidden for each block. This serves to reduce the dimension of the block. The interconnection becomes clearer.



How to define the visible inputs and outputs:

- Go to the context menu of the block and select the **Connector visibilities** command.
 - The *Define Visible Inputs and Outputs for Function Blocks* is displayed:



- All visible connections have a checkmark.
 - In case of a block that is inserted anew, all inputs and outputs are visible at first.
 - Inputs and outputs with a light grey checkbox are already connected and thus cannot be hidden.
- By setting/removing the checkmarks or via the buttons you can define the visible inputs and outputs.
 - Press **OK** to accept the selected definition and close the dialog box.

18.4.3 Arranging objects in the drawing area

All objects can be freely arranged in the drawing area by dragging with the mouse.

We recommend to make an arrangement in which the required connections between the inputs and outputs can be created easily. A division into functional areas may also be sensible to get a better understanding of the application.

Objects which are already connected, can also be dragged to another (free) position in the drawing area. The available connections will be automatically re-routed after dragging.



How to drag an object:

1. Click the header of the object (and keep the button pressed).
2. Keep the button pressed and drag the object to the required position in the drawing area.
 - Via **<Esc>** you can cancel this action.



How to drag several objects at the same time:

1. Select the objects to be dragged.
 - You can select a single object by clicking the header of the object.
 - If you click the header of further objects while pressing **<Ctrl>**, these will be added to an already existing selection (multi-selection).
 - You can easily select objects that are placed together by drawing a frame around these objects while keeping the mouse button pressed.
 - All selected objects are highlighted by a light green header.
2. Keep the mouse button pressed on the header of one of the selected objects and drag it to the required position in the drawing area.
 - Via **<Esc>** you can cancel this action.



Note!

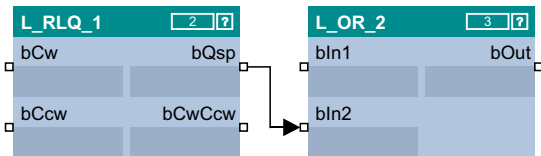
A red header indicates that the object overlaps with other objects in the drawing area!
Arrange the objects so that no overlap occurs.

18.4.4 Creating/deleting connections

After adding objects and arranging them in a reasonable manner within the drawing area, you can create the connections between the available objects which are required for the desired function.

A connection always has a direction and therefore always has a source and a target.

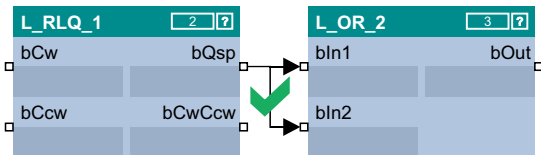
- An output represents a possible source in the interconnection.
- An input represents a possible target in the interconnection.



Permissible/impermissible connections

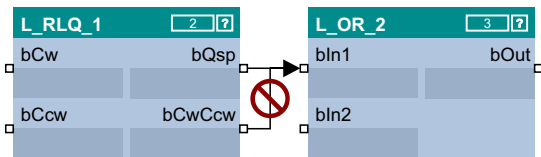
Several connections can lead from one output.

- Therefore it is always possible to start a new connection from an output.



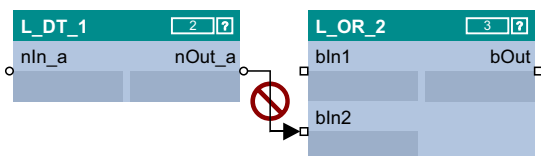
However, maximally one connection may end in an input.

- Therefore it is only possible to start a new connection from an input if there is no connection already ending in this input.



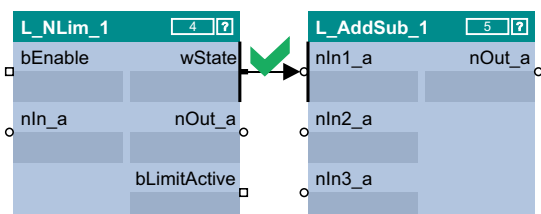
Only inputs/outputs of the same signal type can be connected.

- Thus, a connection between different port symbol cannot be established.



From the »Engineer« V2.12 "Analog/scaled" (_a) and "Miscellaneous (WORD)" signal types can also be interconnected.

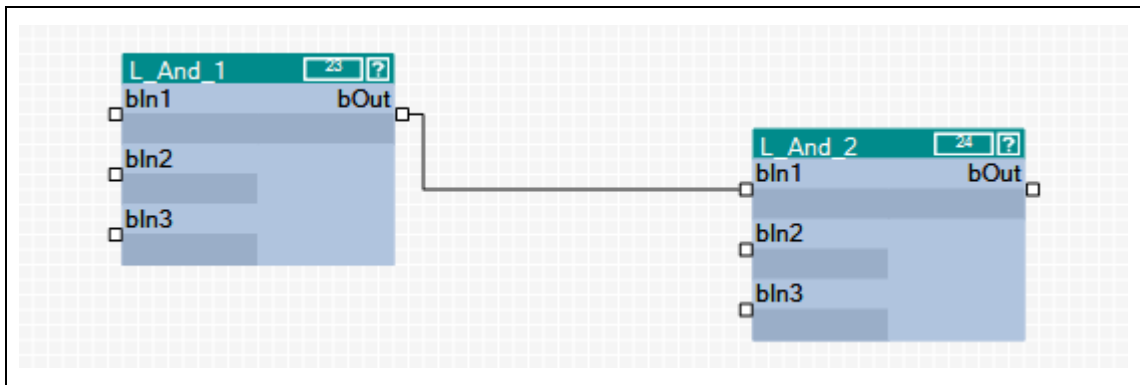
- The implicit type conversion is indicated by a vertical black bar at the port symbol.



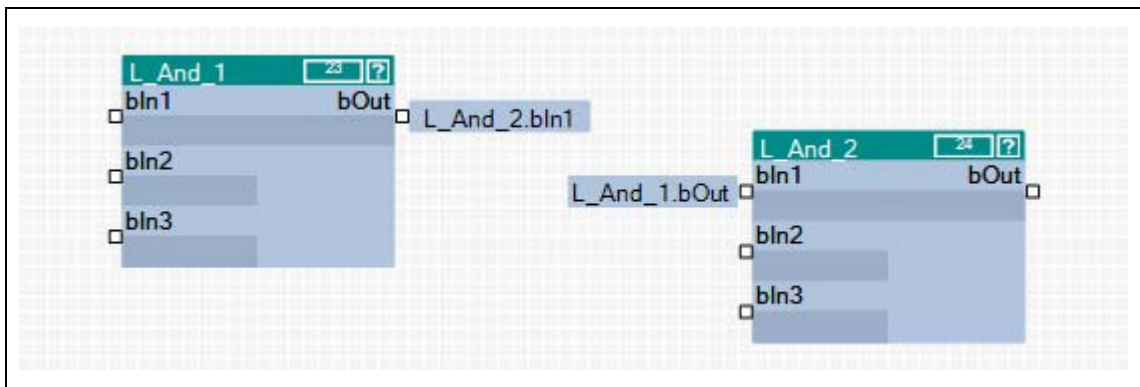
From the »Engineer« V2.13 "Analog/scaled" (_a) and "Angular velocity" (_v) signal types can also be interconnected.

Connection types

Connections can either be created by means of connection lines or port identifiers ("flags")



[18-8] Example 1: Connection via connection line



[18-9] Example 2: Connection via flags



Tip!

The commands **Show as flag** or **Show as line** in the *context menu* of a connection serve to change the representation of the connection at any time.

When an output is connected to several inputs via flags, three points are displayed ("...") at the output instead of the concrete input identifier. The *context menu* of the port symbol shows all inputs which are connected to the output.

18.4.4.1 Creating a connection using the connection line



How to create a connection using the connection line:

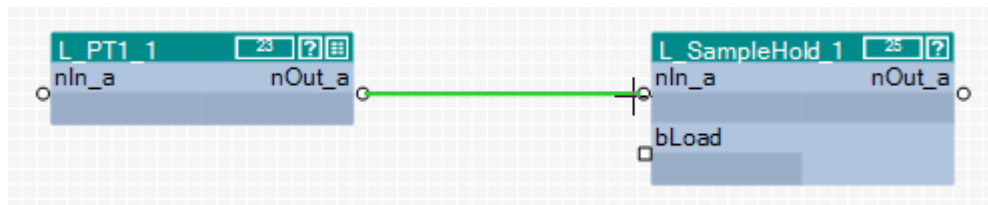
1. Click the port symbol from which the new connection is to be started.
 - It is only possible to start a new connection from an input if there is no connection already ending in this input.
 - If you then move the mouse pointer away from the port symbol, a new connection is "drawn" from this port symbol.
 - Via <Esc> you can cancel this action.
2. Click the port symbol where the connection is to end.
 - Thereupon the corresponding connection is routed automatically if the connection is permissible.



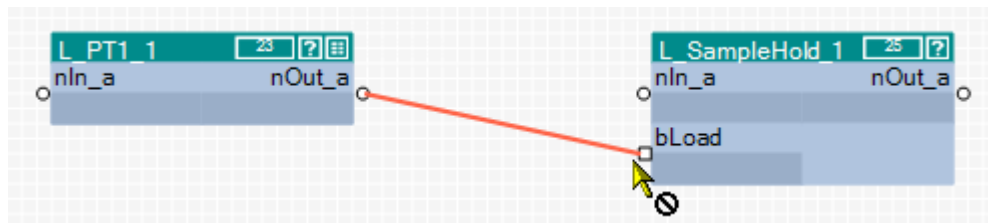
Tip!

If you move the mouse pointer across the port symbol while drawing a new connection, you can see whether the connection is permissible or not from the colour of the drawn line and from the mouse pointer symbol.

- Permissible connection:



- Impermissible connection (different port symbol):



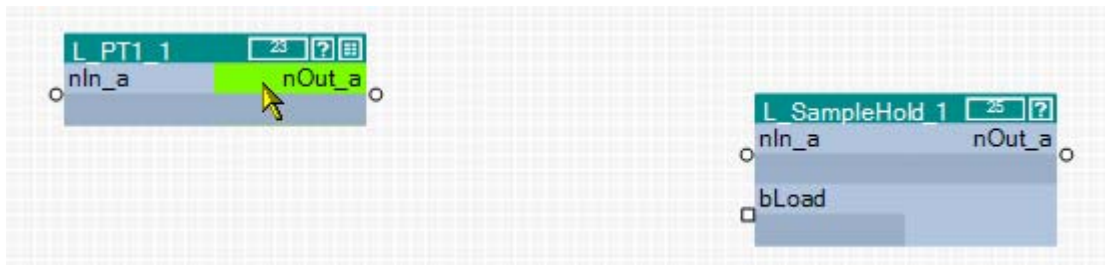
The command **Show as flag** in the *context menu* of a line serves to change the representation of the connection at any time.

18.4.4.2 Creating a connection using port identifiers

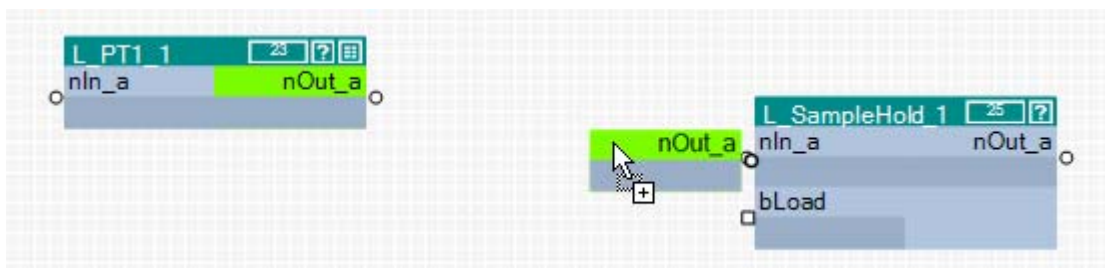


How to create a connection with port identifiers:

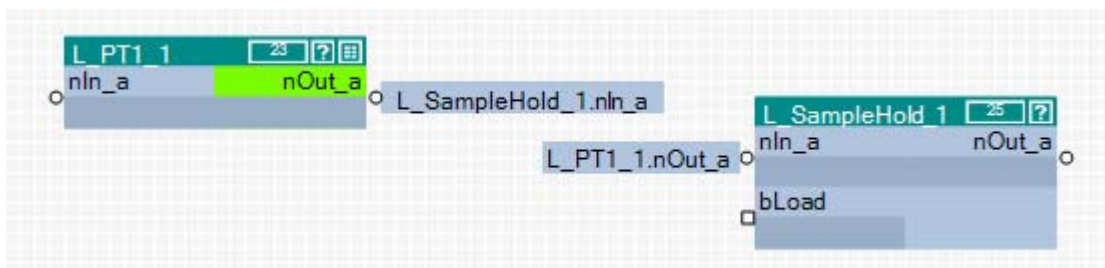
1. Click the port identifier.
 - The selected port is highlighted in light green:



2. Drag the port segment to the required port while keeping the left mouse button pressed:



After releasing the mouse button, the connection via port identifiers (flags) is created. The corresponding port identifier consists of the block name and the name of the input/output:



Tip!

The command **Show as line** in the *context menu* of a flag serves to change the representation of the connection at any time.

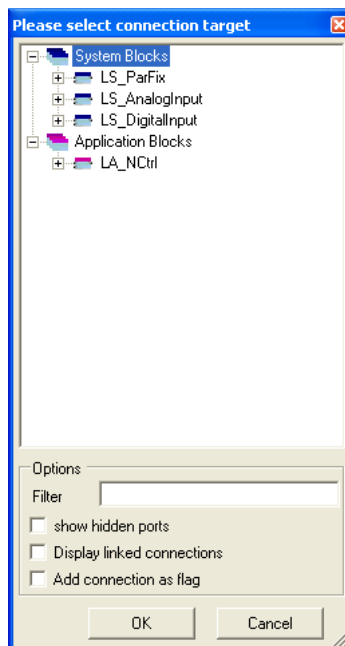
18.4.4.3 Creating a connection via connection dialog

You can also create connections by means of a selection dialog instead of dragging by mouse. This especially makes sense if there is a great distance between the ports to be connected in the drawing area.



How to create a connection using the selection dialog:

1. Right-click the port identifier or click the port symbol from which the connection is to start.
 - The *context menu* for the port is displayed.
2. Go to the *context menu* for the port and select the **Add/change connection...** command.
 - The *Add/change connection* dialog box is displayed:



- In a tree structure all inputs and outputs of the application are shown to which a connection is permissible.
 - You can enter an optional text into the **Filter** input field to reduce the selection to the blocks or ports which contain the entered text.
 - If you activate the **Show hidden ports** control field, the hidden ports for system and function blocks are shown as well.
3. Select the port where the connection is to end from the tree structure.
 4. Activate the **Add connection as flag** control field if a port identifier (flag) is to be inserted instead of a connection line.
 5. Press **OK** to create the connection to the selected port and close the dialog box.

18.4.4.4 Deleting connections that are no longer required



How to delete connection lines:

1. Select connection lines to be deleted.
 - Select a single connection line by directly clicking on the connection line with the right mouse button.
 - If you click further connection lines while pressing **<Ctrl>** they are added to an already existing selection (multi-selection).
 - All connection lines are highlighted in red.
2. Press ****.



How to delete port identifiers/flags:

1. Select the port identifiers to be deleted.
 - Select a single port identifier by directly clicking on the port identifier with the left mouse button.
 - If you click further port identifiers while pressing **<Ctrl>** they are added to an already existing selection (multi-selection).
 - All selected port identifiers are highlighted by a light green header.
2. Press ****.

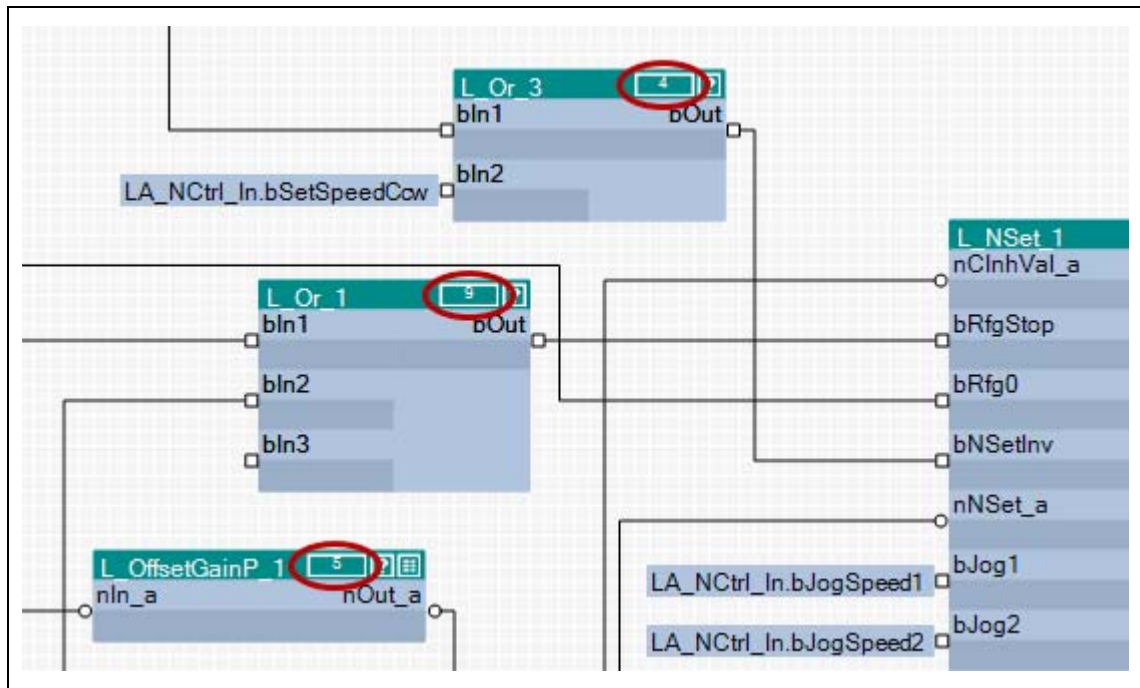
Related topics

- ▶ [Deleting objects that are no longer required](#) (1359)

18.4.5 Changing the processing order

If you insert a function block into the interconnection, an order index is automatically assigned to this function block. By means of this order index it is defined in which order the individual function blocks are calculated at runtime.

- The first function block inserted contains the order index "1", the next function block inserted contains the order index "2", etc.
- The respective order index is displayed in the header of the function block in the rectangle after the block name.



[18-10] Example: Function blocks with order index



Note!

When a function block is shifted, its order index is maintained.

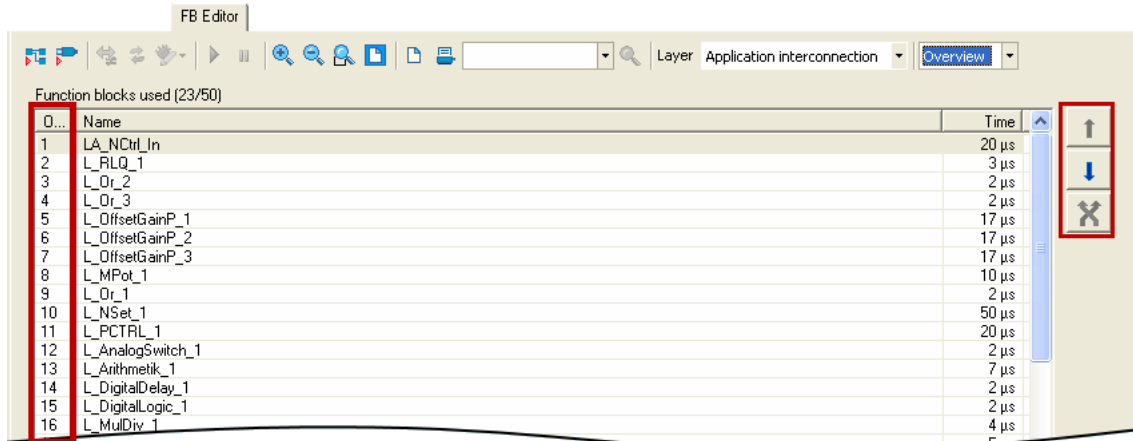
The processing order influences the result!




- In certain cases it may be sensible to change the processing order, but if you select an unfavourable processing order, errors may arise!



How to change the processing order manually:

1. Use the list field at the top right to change from the Editor to the overview.
 - The overview displays all function blocks of the interconnection in the order of their processing
 - In the first "Order" column the order index of each function block is listed.
2. Unless already selected, select the entry "Manual selection" in the **Optimisation...** list field.



3. Select the function block which is to receive a different position within the processing order.
 - If you click further function blocks while pressing **<Ctrl>** they are added to an already existing selection (multi-selection).
 - The **<Shift>** key serves to select a related area of function blocks.
4. Move the function block(s) to the desired position using the  and  buttons.
 - The  button serves to exchange two selected function blocks with regard to their order.
5. Repeat steps 3 and 4 until the required processing order has been established.

Changing the processing order according to an automatically generated selection

In addition to the manual selection, the **Optimisation...** list field also offers two options for an automatic adaptation of the processing order:

- **Signal flow:** The processing order is optimised according to the signal flow.
- **Topology:** The processing order is optimised according to the x/y arrangement of the function blocks in the FB Editor.

As long as an automatic adaptation has been selected, a manual change of the processing order is not possible.

18.4.6 Copying interconnection elements (across all devices)

Interconnection elements can be copied across the devices within the project if the devices belong to the same product family (e.g. Inverter Drives 8400).

All types of blocks and comments can be copied to the clipboard via the **Copy** command or the **<Ctrl>+<c>** shortcut and then be inserted into the FB interconnection of the same or another project device of the same product family using the **Paste** command or the **<Ctrl>+<v>** shortcut.

- During the copy process into the clipboard, existing connections between copied blocks are copied as well, and the layout is kept too. Moreover, the separate technical objects (e.g. port definition) are copied. Selected connections cannot be copied on their own.
- The **Paste** command is available if the clipboard is not empty and if it was copied from a device of the same product family. Within this product family, all device types (e.g. 8400 xxxxLine Vxx.xx) are permitted.
- After the **Paste** command has been selected, a dialog box is displayed which serves to select which elements are to be inserted from the clipboard and how to solve name conflicts, if any.
- After inserting the elements, they are marked in the target interconnection in order to be repositioned or deleted again to undo the insertion.
- Inserting from the clipboard can be repeated. The originally copied contents of the clipboard remains unchanged when it is inserted.



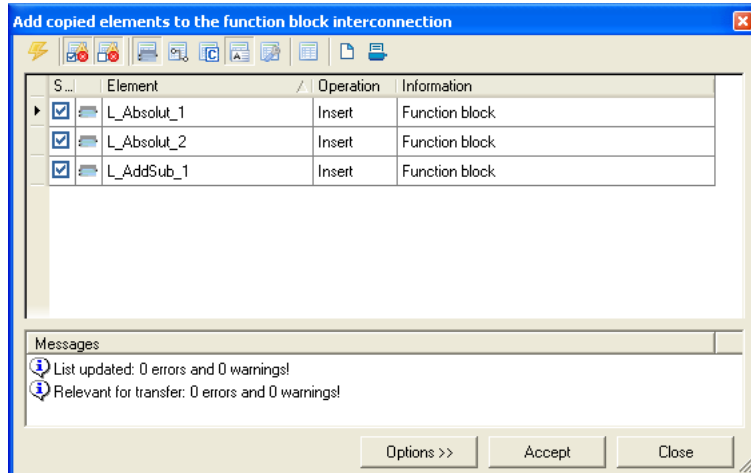
How to copy one or several interconnection elements:

1. Select the objects to be copied.
 - You can select a single object by clicking the header of the object.
 - If you click the header of further objects while pressing **<Ctrl>**, these will be added to an already existing selection (multi-selection).
 - You can easily select elements that are placed together by drawing a frame around these elements while keeping the mouse button pressed.
 - All selected objects are highlighted by a light green header.
2. Go to the *context menu* and select the **Copy** command (or **<Ctrl>+<c>**).
 - The selected elements are copied into the clipboard of the FB Editor.
3. If the elements are to be copied into a function block interconnection of another project device, change to the corresponding interconnection via the *project view*.
4. Go to the *context menu* and select the **Paste** command (or **<Ctrl>+<v>**).
5. Go to the *Insert FB interconnection* dialog box and select the elements to be inserted from the clipboard.
 - Detailed information on this dialog box can be obtained from the following subchapter ["Insert options for copied elements"](#). (1372)

6. Click **Insert** to insert the selected elements into the target interconnection as defined.
 - Only possible if at least one element in the list has been selected for insertion.
 - Insertion is also possible via the **<Enter>** button if at least one element is selected from the list for insertion.
 - The original layout and the relative position of the inserted blocks to each other are maintained.
 - When copying across the devices, you also insert the corresponding separate technical objects (e.g. port definition).
 - The inserted elements are deleted from the list. If the list is empty, the dialog box is closed and the connections are inserted depending on the selected option.
7. If there are still elements to be entered in the list, repeat steps 5 and 6 until all elements are inserted as intended.
8. Press **Close** to stop the insertion and close the dialog box.
 - You can also use **<Esc>** or **<Enter>** to close the dialog box if "Insert" is not active.
 - The elements inserted into the target interconnection so far are maintained.
 - The connections for the blocks inserted so far are inserted depending on the selected option.

18.4.6.1 Insert options for copied elements

If interconnection elements have been copied to the clipboard, the »Engineer« will display a list of all elements contained in the clipboard when selecting the command **Insert** in the *Insert FB interconnection* dialog box:



The list shows the elements which can be added to the target interconnection, and the elements which cannot be added.

- In the "Selection" column, you can check/uncheck the elements to be added.
- Connections are only inserted when the dialog box is closed, which applies to all modules inserted so far. They are displayed as lines or flags, like in the original, but re-routed.
- The symbols in the *Toolbar* serve to execute the following functions:

Icon	Function
	Add the selected elements to the interconnection
	Show the elements to be added but are marked with an error or warning.
	Show the elements not to be added and marked with an error or warning.
	Show blocks
	Show connections
	Show parameters
	Show comments
	Show system elements
	Show all
	Print view
	Print list

- The buttons serve to execute the following functions:

Button	Function
Insert	Add elements selected in the list to the target interconnection <ul style="list-style-type: none"> • Only possible if at least one element in the list has been selected for insertion. • Insertion is also possible via the <Enter> button if at least one element is selected from the list for insertion. • The original layout and the relative position of the inserted blocks to each other are maintained. • When copying across the devices, you also insert the corresponding separate technical objects (e.g. port definition). • The added elements are simultaneously deleted from the list. The connections are added depending on the selected option.
Close	Close dialog box. <ul style="list-style-type: none"> • You can also use <Esc> or <Enter> to close the dialog box if "Insert" is not active. • The elements inserted into the target interconnection so far are maintained. • The connections for the blocks inserted so far are inserted depending on the selected option.

18.4.7 Resetting changed interconnection

If you only made changes on the I/O level, you can reset them by selecting a predefined control scheme in [C00007](#). If you have also made changes on the application level, you must first reset the changed application to a predefined application in [C00005](#).



How to reset the application interconnection to a predefined application:

1. Go to the **Application parameters** tab.
2. Select the required application in the **Application** list field.

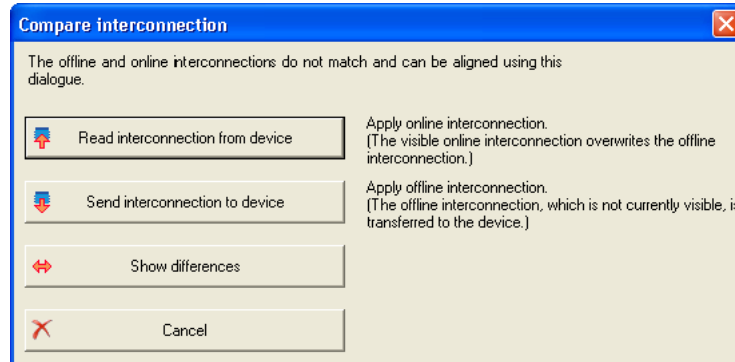


How to reset the I/O interconnection to a predefined control scheme:


1. Go to the **Application parameters** tab.
2. Select the required control scheme in the **Control source** list field.

18.5 Adjusting online and offline interconnection

If the »Engineer« detects that online and offline interconnection differ from each other, the *Compare interconnection* dialog box is displayed with various options for the adjustment:



Tip!

The dialog box can also be opened via the  symbol in the *FB Editor toolbar*.


Button	Function
Accepting the interconnection from the device	Add the interconnection in the device to the FB Editor. The interconnection existing in the FB Editor will be overwritten by this action.
Transferring the interconnection to the device	Transfer the offline interconnection which is currently not visible in the FB Editor to the device. The interconnection existing in the device will be overwritten by this action.
Showing differences	Showing differences between online and offline interconnection.
Cancel	Close the <i>Adjust interconnection</i> dialog box without making an adjustment.

18.6 Printing the interconnection

The interconnection can be printed for documentation purposes, optionally on one page, on four pages, or not scaled.




Tip!

By clicking the  icon in the *FB Editor toolbar*, you can get a print view before printing.



How to print the interconnection:

1. In the *FB Editor toolbar*, click the  icon.
 - The *Circuit print size* dialog box is displayed.
2. Select the desired size and press **OK**.
 - The standard dialog box *Print* appears.
3. Press **OK** to start the printing process.

18.7 Comparing interconnections

The comparison operation serves to compare FB interconnections of 8400 devices within the project. An offline<>online comparison and the comparison of two online devices are possible.



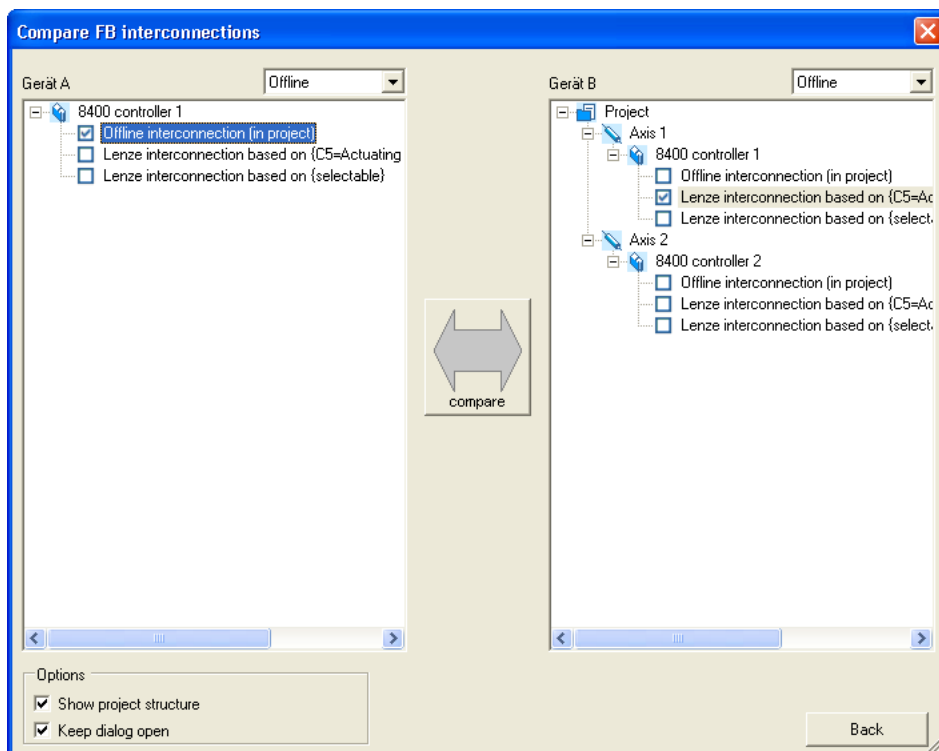
Note!

Only applications can be compared which have been enabled in the FB Editor!
Block positions, line representations, and connector visibilities are not compared.



How to compare two FB interconnections:

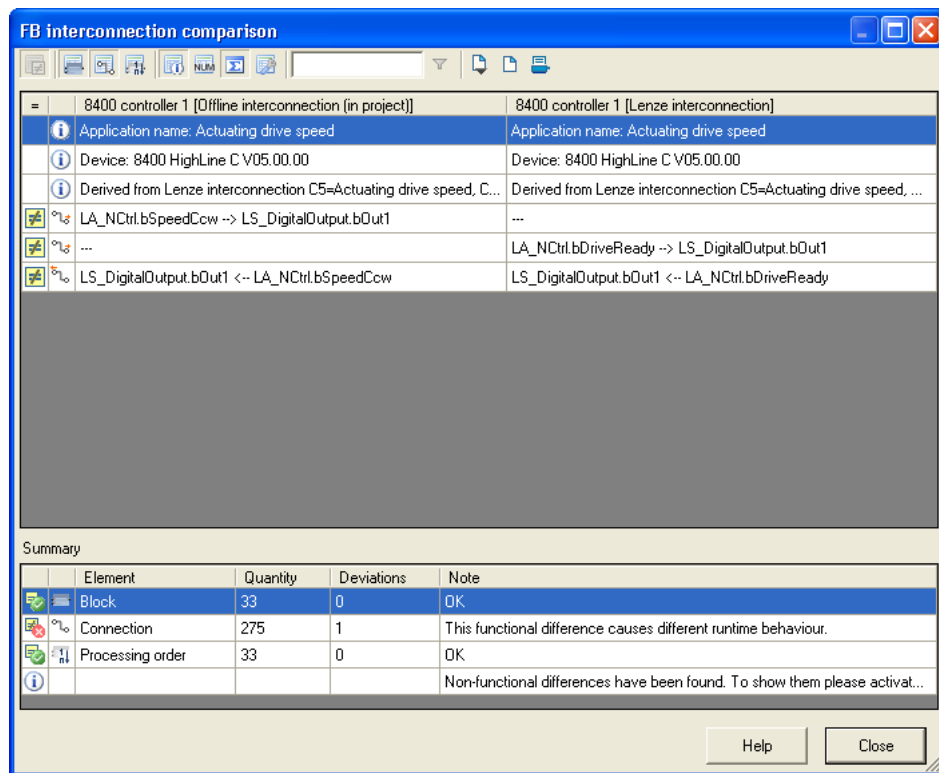
1. Select the command **Application data→Compare FB interconnections....**
 - The *Compare FB interconnections* dialog box is displayed:



2. Select the interconnections to be compared in the project view represented on the left and right.
 - In order to execute a comparison with an online device, select "Online" in one of the two upper list fields. Then all available online devices are displayed for selection.
 - If you select "Online" in one of the two upper list fields, you can also compare the interconnections of two available online devices.
3. Click **Compare**.
 - If the comparison was executed successfully, the comparison result is displayed as a list (see the following section).
 - If a comparison of the selected interconnections is not possible, a corresponding message is displayed.
4. In order to stop the comparison operation and close the dialog box: Press **Back**.






Representation of the comparison result

The comparison result is displayed in the form of a list in the *FB interconnection comparison* dialog box:



- The symbols in the *Toolbar* serve to show or hide different details and export and print the shown list.

Icon	Function
	Only show differences • Button can only be activated in expert mode.
	Show blocks
	Show connections
	Show processing order
	Show properties of blocks and connections • Function is only available in expert mode.
	Show comments • Function is only available in expert mode.
	Show block parameters • Function is only available in expert mode.
	Show application parameters • Function is only available in expert mode.
	Show all • Function is only available in expert mode.
	Show general information
	Show summary

Icon	Function
	Activate expert mode <ul style="list-style-type: none">• In the expert mode, also non-functional differences are shown.
	Apply filter <ul style="list-style-type: none">• Only show list entries which contain the text entered in the input field.• Function is only available in expert mode.
	Export shown list as comma-separated list (*.csv)
	Print view
	Print list

18.8 Copying an interconnection

In contrast to copying/inserting selected interconnection elements via the clipboard, the function described in this chapter serves to replace the current FB interconnection of a device completely by the FB interconnection of another project device.



Note!

The complete FB interconnection can only be copied between devices of the same device type and version (e.g. 8400 HighLine C V1.0).

A complete interconnection comprises:

- Function blocks (use and parameter values)
- System blocks (application and parameter values)
- Port blocks (use and parameter values)
- Connections
- Comments
- Interconnection layout (arrangement of the modules)
- Port definition of the ports used in the FB interconnection



How to copy the complete interconnection into another project device:

1. Select the application with the FB interconnection to be copied in the *project view*.
2. Select the command **Application data→Copy FB interconnections....**
3. Go to *project view* and select the application which is to be inserted into the copied FB interconnection.
4. Select the command **Application data→Add FB interconnection....**
 - The command can only be activated if an FB interconnection has been copied from a device of the same device type and version.
 - After the command has been executed, the module assembly is compared. If there are relevant deviations, the insertion is refused and a corresponding message is displayed.
 - If an insertion is possible, you are asked if the FB interconnection is to be inserted.
5. Confirm the question if the copied FB interconnection is to be inserted with **Yes**.
 - After the insertion, an update of the project is required.

18.9 Exporting/Importing an interconnection

The interconnection existing in the project can be exported to a file for reuse/transfer to other devices.



Note!

The file can only be imported to devices of the same device type and version (e.g. 8400 HighLine C V1.0).



How to export the interconnection from the project to a file:

1. Go to the *Project view* in the *context menu* of the controller and select the **Export FB interconnection...** command.
2. Enter the memory location and the file name for the interconnection to be exported in the *Export FB interconnection* dialog box.
3. Click **Save** to export the interconnection and close the dialog box.



How to import the interconnection from a file to the project:

1. Go to the *Project view* in the *context menu* of the controller and select the **Import FB interconnection...** command.
2. Select the file with the interconnection to be imported in the *Import FB interconnection* dialog box.
3. Click **Open** to import the interconnection and close the dialog box.

19 Function library

19.1 Function blocks

This chapter describes the function blocks which are available for the controller in the FB Editor.



The system blocks are described in the chapter "[System blocks](#)". (📖 1698)



Note!

A maximum of 75 function blocks can be used for a function block interconnection. The maximum calculating time is approx. 300 µs.

Overview of function blocks available

Function block	Runtime	Function
L_Absolute_1 L_Absolute_2	2 µs	... converts a bipolar input signal into a unipolar output signal.
L_AddSub_1	3 µs	... adds / subtracts analog input signals.
L_AnalogSwitch_1 L_AnalogSwitch_2 L_AnalogSwitch_3 L_AnalogSwitch_4 L_AnalogSwitch_5	2 µs	... switches between two analog input signals.
L_And_1 L_And_2 L_And_3	2 µs	... ANDs three binary signals.
L_And5_1 L_And5_2	2 µs	... ANDs five binary signals.
L_Arithmetik_1 L_Arithmetik_2 L_Arithmetik_3 L_Arithmetik_4 L_Arithmetik_5	7 µs	... combines two analog signals arithmetically.
L_ArithmetikPhi_1 L_ArithmetikPhi_2 L_ArithmetikPhi_3 L_ArithmetikPhi_4 L_ArithmetikPhi_5 L_ArithmetikPhi_6	7 µs	... combines two angle signals arithmetically. • L_ArithmetikPhi_4 ... L_ArithmetikPhi_6 are available from version 12.00.00.
L_CalcDiameter_1	2 µs	... can calculate the reel diameter from line speed and winding speed. • This FB is available from version 02.00.00.
L_Compare_1 L_Compare_2 L_Compare_3 L_Compare_4 L_Compare_5	5 µs	... compares two analog signals and can be used e.g. to implement a trigger.

Function block	Runtime	Function
L_ComparePhi_1 L_ComparePhi_2 L_ComparePhi_3 L_ComparePhi_4 L_ComparePhi_5	5 µs	... compares two angle signals.
L_ConvActPos_1	0 µs	... filters and scales a dancer position value to an available setting range. • This FB is available from version 12.00.00.
L_ConvAP_1 L_ConvAP_2 L_ConvAP_3	0 µs	... converts an analog value into a position. • These FBs are available from version 02.00.00.
L_ConvBitsToWorld_1 L_ConvBitsToWorld_2 L_ConvBitsToWorld_3	3 µs	... converts 16 bit input values of the type "BOOL" into an output value of the type "WORD".
L_ConvDIntToWords_1 L_ConvDIntToWords_2 L_ConvDIntToWords_3	3 µs	... converts an input value of the type "DINT" into two output values of the type "WORD".
L_ConvPA_1 L_ConvPA_2 L_ConvPA_3	3 µs	... converts a position into an analog value. • These FBs are available from version 02.00.00.
L_ConvPP_1 L_ConvPP_2 L_ConvPP_3	3 µs	... converts a position with dynamic fraction. • These FBs are available from version 02.00.00.
L_ConvUnitsToIncr_1 L_ConvUnitsToIncr_2 L_ConvUnitsToIncr_3	3 µs	... converts a position value provided in the real unit of the machine into an internal 32-bit position value. • These FBs are available from version 12.00.00.
L_ConvW_1 L_ConvW_2 L_ConvW_3 L_ConvW_4	2 µs	... enables parameterisable conversion between analog signal forms. • Division is remainder considered.
L_ConvWordsToDInt_1 L_ConvWordsToDInt_2 L_ConvWordsToDInt_3	3 µs	... converts two inputs values of the type "WORD" into an output value of the type "DINT".
L_ConvWordToBits_1 L_ConvWordToBits_2 L_ConvWordToBits_3	3 µs	... converts an input value of "WORD" type into 16 individual binary signals.
L_ConvX_1 L_ConvX_2 L_ConvX_3	0 µs	... scales an analog value. • These FBs are available from version 02.00.00.
L_Counter_1 L_Counter_2 L_Counter_3	3 µs	... is a digital upcounter and downcounter.
L_Curve_1 L_Curve_2 L_Curve_3	4 µs	... can optionally display a characteristic function or a curve function $y=f(x)$, the X axis being the input signal and the Y axis being the output signal. From version 12.00.00, the FB L_Curve_3 for winding applications can also be used for creating a tensile force profile depending on the diameter. • L_Curve_2 and L_Curve_3 are available from version 02.00.00.
L_DFlipFlop_1 L_DFlipFlop_2	3 µs	... provides two stable states depending on the input signals.
L_DFRFG_1	3 µs	... synchronises a drive (slave) to the master value of a master drive and then executes a angular synchronism with regard to the digital frequency. • This FB is available from version 02.00.00.

Function block	Runtime	Function
L_DFSET_1	3 µs	... prepares the master value for a slave drive. This FB enables the controller to follow the master drive true to speed and angle. • This FB is available from version 02.00.00.
L_DigitalDelay_1 L_DigitalDelay_2 L_DigitalDelay_3	2 µs	... delays binary signals.
L_DigitalLogic_1 L_DigitalLogic_2 L_DigitalLogic_3	2 µs	... provides a binary output signal which is generated by the logic combination of three input signals. • L_DigitalLogic_3 is available from version 02.00.00.
L_DigitalLogic5_1 L_DigitalLogic5_2	2 µs	... provides a binary output signal which is generated by the logic combination of five input signals.
L_DT1_1	3 µs	...differentiates signals. The function block can, for instance, be used to apply an acceleration (dv/dt).
L_FixSet_a_1	2 µs	... outputs one of 16 parameterisable analog signals.
L_FixSet_w_1 L_FixSet_w_2	2 µs	... outputs one of 16 parameterisable data words.
L_GainOffset_1 L_GainOffset_2 L_GainOffset_3	3 µs	... can amplify an analog input signal and then add an offset to it. • Gain and offset can be set via FB inputs.
L_GainOffsetP_1 L_GainOffsetP_2 L_GainOffsetP_3	3 µs	... can amplify an analog input signal and then add an offset to it. • Gain and offset can be set via parameters.
L_GainOffsetPhiP_1 L_GainOffsetPhiP_2	3 µs	... can amplify an angle signal and then add an offset to it. • Gain and offset can be set via parameters.
L_GearComp_1	3 µs	... compensates elasticities in the drive train (gearbox compensation). • This FB is available from version 02.00.00.
L_Interpolator_1	5 µs	... can interpolate a position setpoint and/or an analog value e.g. to compensate for larger bus transmission cycles or to continue signal characteristics if data telegrams are missing.
L_JogCtrlExtension_1	5 µs	... can be connected upstream to the L_NSet ramp generator to implement a switch-off positioning at limit switch.
L_Limit_1 L_Limit_2	3 µs	... limits an analog input signal to an adjustable value range.
L_LimitPhi_1 L_LimitPhi_2 L_LimitPhi_3	3 µs	... limits an angle signal to an adjustable value range.
L_MckCtrlInterface_1	5 µs	... provides the application with process inputs for controlling various basic functions of the Motion Control Kernel. ▶ MCKInterface (□ 570)
L_MckStateInterface_1	5 µs	... provides the application with various items of status information of the Motion Control via process outputs. ▶ MCKInterface (□ 570)
L_MFail_1	0 µs	... can be used for implementing a mains failure control. • This FB is available from version 12.00.00.
L_MPot_1	10 µs	... replaces a hardware motor potentiometer as setpoint source.
L_MulDiv_1 L_MulDiv_2	4 µs	... multiplies the analog input signal with a factor. • Not remainder considered.
L_Mux_1	3 µs	... switches one of eight selectable input signals to the output.
L_Negation_1 L_Negation_2	2 µs	... negates an analog input signal.
L_NLim_1 L_NLim_2	3 µs	... can suppress up to three parameterisable blocking zones within a continuous signal characteristic of an analog input signal.

Function block	Runtime	Function
L Not 1 L Not 2 L Not 3 L Not 4 L Not 5 L Not 6 L Not 7	2 µs	... inverts a digital input signal.
L NSet 1	50 µs	... contains a ramp generator with comprehensive parameterisation and control options to condition a setpoint signal.
L Odometer 1	2 µs	... detects positions and calculates distances.
L OffsetGain 1 L OffsetGain 2 L OffsetGain 3	4 µs	... can add an offset to an analog input signal and amplify it afterwards. • Offset and gain can be set via FB inputs.
L OffsetGainP 1 L OffsetGainP 2 L OffsetGainP 3	17 µs	... can add an offset to an analog input signal and amplify it afterwards. • Offset and gain can be set via parameters.
L OffsetGainPhiP 1 L OffsetGainPhiP 2	17 µs	... can add an offset to an angle signal and amplify it afterwards. • Offset and gain can be set via parameters.
L Or 1 L Or 2 L Or 3 L Or 4	2 µs	... ORs three binary signals. • L Or 4 is available from version 02.00.00.
L Or5 1 L Or5 2	2 µs	... ORs five binary signals.
L PCTRL 1	20 µs	... is a PID controller and can be used for various control tasks.
L PhaseDiff 1 L PhaseDiff 2	2 µs	... generates a position difference for the defined position setpoint from a position value and a speed signal.
L PhaseIntK 1 L PhaseIntK 2	5 µs	... integrates a speed to an angle.
L PhiAdd 1	2 µs	... adds or subtracts angle signals. • This FB is available from version 12.00.00.
L PhiDiv 1	2 µs	... divides or multiplies angle signals in the power of two format. • This FB is available from version 12.00.00.
L PhiIntegrator 1	2 µs	... evaluates a speed with a gearbox factor and adds them in an integrator. • This FB is available from version 02.00.00.
L PosCtrlLin 1 L PosCtrlLin 2	2 µs	... is a simple linear profile generator. • These FBs are available from version 02.00.00.
L PosiShaftCtrlInterface 1	5 µs	FB in preparation!
L ProcessCtrl 1	2 µs	... can realise a dancer position or tension control. • This FB is available from version 02.00.00.
L PT1 1 L PT1 2 L PT1 3	3 µs	... filters and delays analog signals.
L RLO 1	3 µs	... links a selected direction of rotation to the QSP function with wire-break protection.
L RSFlipFlop 1 L RSFlipFlop 2	3 µs	... saves a binary input information element and resets it on command..
L SampleHold 1 L SampleHold 2	3 µs	... saves a value.
L Sequencer 1	10 µs	... processes a positioning program based on a sequence table. • This FB is available from version 12.00.00.
L SignalMonitor a	15 µs	... serves to output analog output signals of other FBs, SBs or LAs.

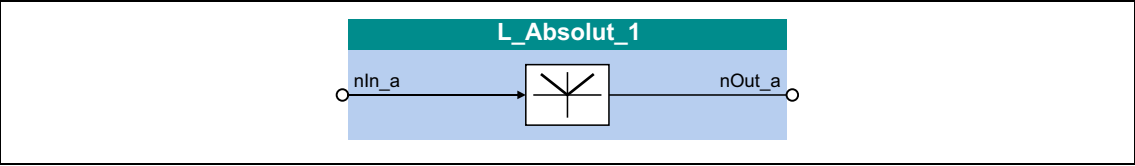
Function block	Runtime	Function
L_SignalMonitor_b	3 µs	... serves to output binary output signals of other FBs, SBs or LAs.
L_SignalSwitch_1 L_SignalSwitch_2 L_SignalSwitch_3 L_SignalSwitch_4	2 µs	... switches between two input signals of the "WORD" data type.
L_SignalSwitch32_1 L_SignalSwitch32_2 L_SignalSwitch32_3	2 µs	... switches between two input signals of "DINT" data type. • These FBs are available from version 02.00.00.
L_SQrt_1	3 µs	... outputs the square root for a DINT input value.
L_SRFG_1 L_SRFG_2	2 µs	... is a ramp function generator with S-shaped ramps for limiting the temporal rise of analog signals.
L_SwitchPoint_1	3 µs	... provides position switch points, i.e. digital switches the binary statuses (FALSE/TRUE) of which depend on the actual position. • The position switch point positions can be set via FB inputs. • This FB is available from version 02.00.00.
L_SwitchPointPar_1	3 µs	... provides position switch points, i.e. digital switches the binary statuses (FALSE/TRUE) of which depend on the actual position. • The position switch point positions can be set via parameters. • This FB is available from version 12.00.00.
L_Transient_1 L_Transient_2 L_Transient_3 L_Transient_4 L_Transient_5 L_Transient_6 L_Transient_7 L_Transient_8	3 µs	... evaluates digital signal edges and converts them into timed pulses.

Related topics:

- ▶ [Overview of system blocks available](#) (📖 1698)
- ▶ [Working with the FB Editor](#) (📖 1329)

19.1.1 L_Absolut_1

This FB converts a bipolar input signal into a unipolar output signal.



Inputs

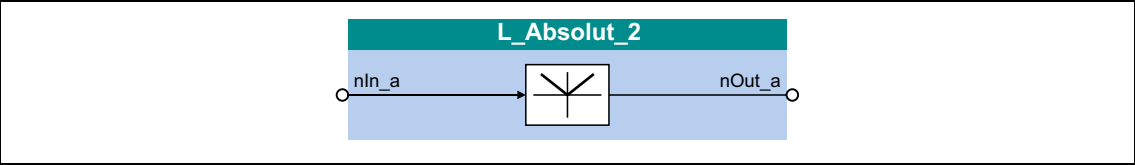
Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal

19.1.2 L_Absolut_2

This FB converts a bipolar input signal into a unipolar output signal.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal

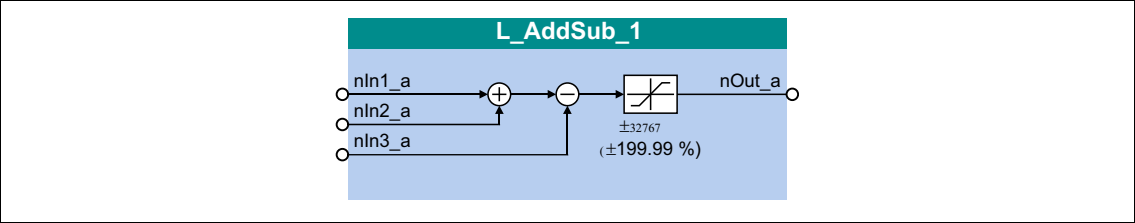
Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal

19.1.3 L_AddSub_1

This FB is provided with two adding inputs and one subtracting input.

- The value provided at the *nOut_a* output is internally limited to ± 32767 .



Inputs

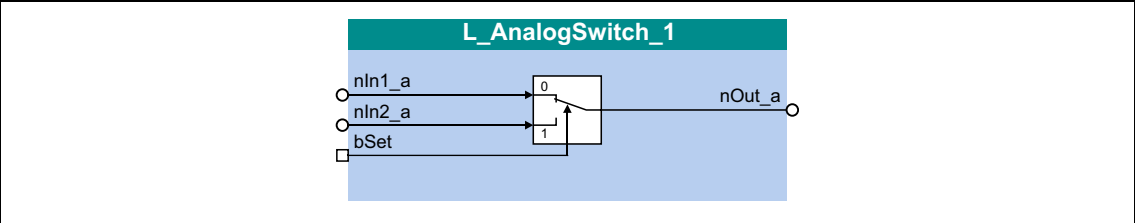
Identifier	Data type	Information/possible settings
<i>nIn1_a</i>	INT	Input signal 1 • This input is added
<i>nIn2_a</i>	INT	Input signal 2 • This input is added
<i>nIn3_a</i>	INT	Input signal 3 • This input is subtracted

Outputs

Identifier	Data type	Value/meaning
<i>nOut_a</i>	INT	Output signal • $nOut_a = nIn1_a + nIn2_a - nIn3_a$ • Internal limitation to ± 32767 ($\pm 199.99 \%$)

19.1.4 L_AnalogSwitch_1

This function block switches between two analog input signals. The switching is controlled via a boolean input signal.



Inputs

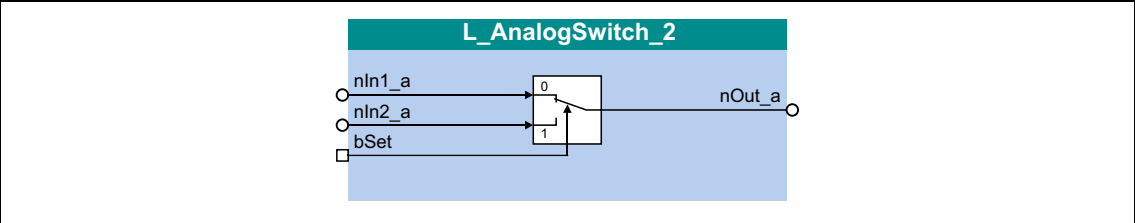
Identifier	Data type	Information/possible settings
<i>nln1_a</i>	INT	Input signal 1
<i>nln2_a</i>	INT	Input signal 2
<i>bSet</i>	BOOL	Selection of the input signal for the output to <i>nOut_a</i>
		FALSE <i>nln1_a</i>
		TRUE <i>nln2_a</i>

Outputs

Identifier	Data type	Value/meaning
<i>nOut_a</i>	INT	Output signal

19.1.5 L_AnalogSwitch_2

This function block switches between two analog input signals. The switching is controlled via a boolean input signal.



Inputs

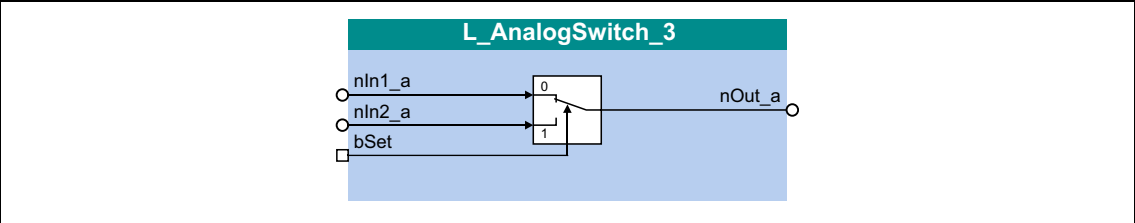
Identifier	Data type	Information/possible settings
<i>nln1_a</i>	INT	Input signal 1
<i>nln2_a</i>	INT	Input signal 2
<i>bSet</i>	BOOL	Selection of the input signal for the output to <i>nOut_a</i>
		FALSE <i>nln1_a</i>
		TRUE <i>nln2_a</i>

Outputs

Identifier	Data type	Value/meaning
<i>nOut_a</i>	INT	Output signal

19.1.6 L_AnalogSwitch_3

This function block switches between two analog input signals. The switching is controlled via a boolean input signal.



Inputs

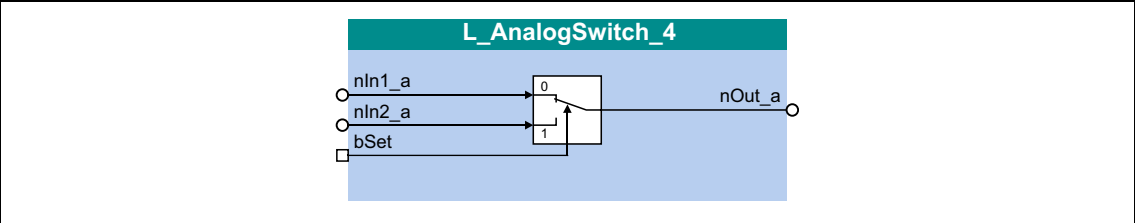
Identifier	Data type	Information/possible settings
<i>nln1_a</i>	INT	Input signal 1
<i>nln2_a</i>	INT	Input signal 2
<i>bSet</i>	BOOL	Selection of the input signal for the output to <i>nOut_a</i>
		FALSE <i>nln1_a</i>
		TRUE <i>nln2_a</i>

Outputs

Identifier	Data type	Value/meaning
<i>nOut_a</i>	INT	Output signal

19.1.7 L_AnalogSwitch_4

This function block switches between two analog input signals. The switching is controlled via a boolean input signal.



Inputs

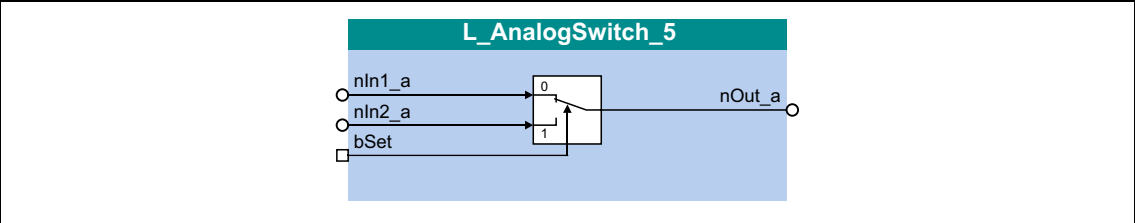
Identifier	Data type	Information/possible settings
nln1_a	INT	Input signal 1
nln2_a	INT	Input signal 2
bSet	BOOL	Selection of the input signal for the output to <i>nOut_a</i>
		FALSE <i>nln1_a</i>
		TRUE <i>nln2_a</i>

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal

19.1.8 L_AnalogSwitch_5

This function block switches between two analog input signals. The switching is controlled via a boolean input signal.



Inputs

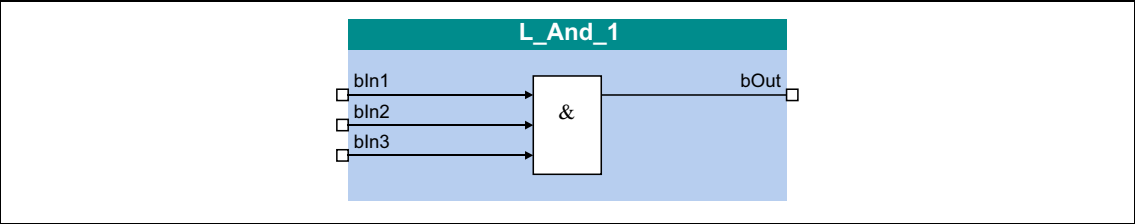
Identifier	Data type	Information/possible settings
<i>nln1_a</i>	INT	Input signal 1
<i>nln2_a</i>	INT	Input signal 2
<i>bSet</i>	BOOL	Selection of the input signal for the output to <i>nOut_a</i>
		FALSE <i>nln1_a</i>
		TRUE <i>nln2_a</i>

Outputs

Identifier	Data type	Value/meaning
<i>nOut_a</i>	INT	Output signal

19.1.9 L_And_1

This FB implements the ANDing of the input signals.



Inputs

Identifier	Information/possible settings
<div><div>bIn1</div><div>bIn2</div><div>bIn3</div><div>BOOL</div></div>	Input signal

Outputs

Identifier	Value/meaning
<div><div>bOut</div><div>BOOL</div></div>	Output signal

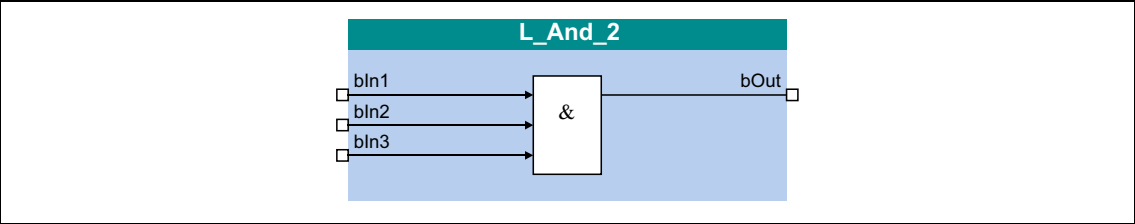
Function

Inputs			Output
bIn3	bIn2	bIn1	bOut
FALSE	FALSE	FALSE	FALSE
FALSE	FALSE	TRUE	
FALSE	TRUE	FALSE	
FALSE	TRUE	TRUE	
TRUE	FALSE	FALSE	
TRUE	FALSE	TRUE	
TRUE	TRUE	FALSE	
TRUE	TRUE	TRUE	TRUE

[19-1] Truth table of the FB L_And_1

19.1.10 L_And_2

This FB implements the ANDing of the input signals.



Inputs

Identifier	Data type	Information/possible settings
bIn1 bIn2 bIn3	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal

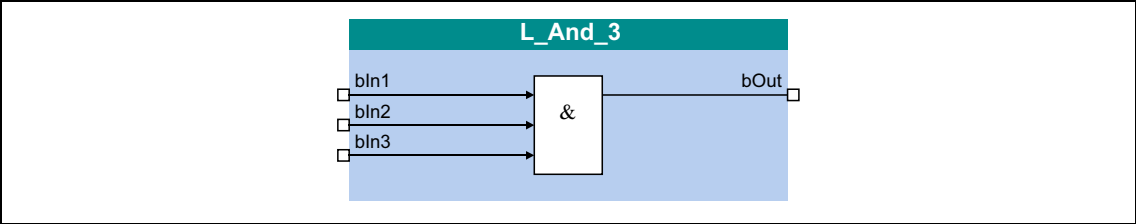
Function

Inputs			Output
bIn3	bIn2	bIn1	bOut
FALSE	FALSE	FALSE	FALSE
FALSE	FALSE	TRUE	
FALSE	TRUE	FALSE	
FALSE	TRUE	TRUE	
TRUE	FALSE	FALSE	
TRUE	FALSE	TRUE	
TRUE	TRUE	FALSE	
TRUE	TRUE	TRUE	TRUE

[19-2] Truth table of the FB L_And_2

19.1.11 L_And_3

This FB implements the ANDing of the input signals.



Inputs

Identifier	Data type	Information/possible settings
bIn1 bIn2 bIn3	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal

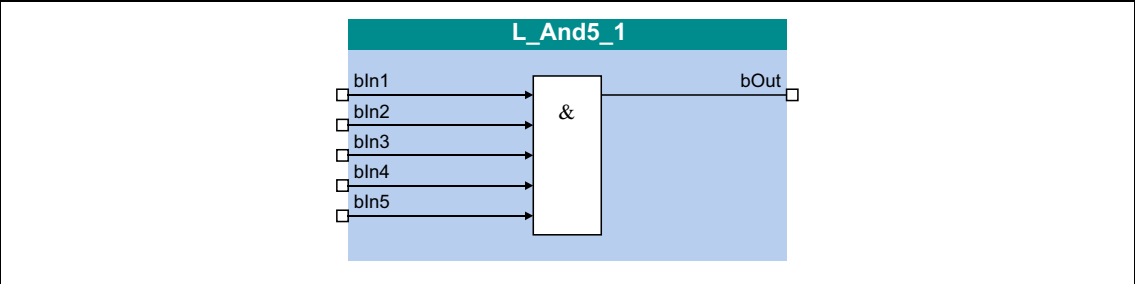
Function

Inputs			Output
bIn3	bIn2	bIn1	bOut
FALSE	FALSE	FALSE	FALSE
FALSE	FALSE	TRUE	
FALSE	TRUE	FALSE	
FALSE	TRUE	TRUE	
TRUE	FALSE	FALSE	
TRUE	FALSE	TRUE	
TRUE	TRUE	FALSE	
TRUE	TRUE	TRUE	TRUE

[19-3] Truth table of the FB L_And_3

19.1.12 L_And5_1

This FB implements the ANDing of the input signals.



Inputs

Identifier	Data type	Information/possible settings
bIn1 ... bIn5	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal

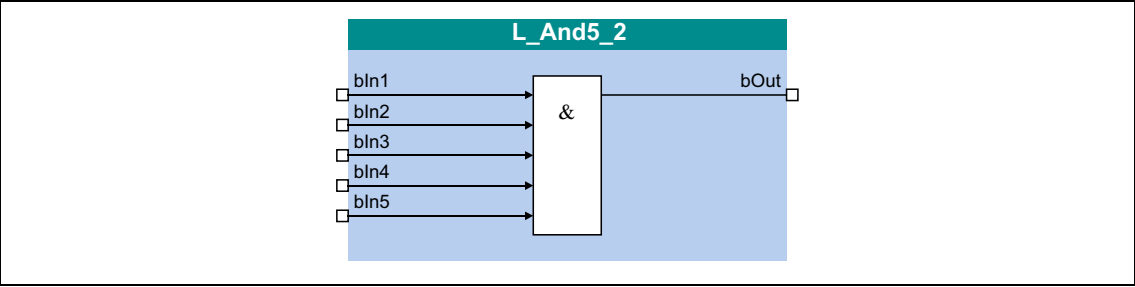
Function

Inputs					Output
bIn5	bIn4	bIn3	bIn2	bIn1	bOut
FALSE	FALSE	FALSE	FALSE	FALSE	FALSE
FALSE	FALSE	FALSE	FALSE	TRUE	
FALSE	FALSE	FALSE	TRUE	FALSE	
FALSE	FALSE	FALSE	TRUE	TRUE	
FALSE	FALSE	TRUE	FALSE	FALSE	
...					
TRUE	TRUE	TRUE	FALSE	TRUE	
TRUE	TRUE	TRUE	TRUE	FALSE	
TRUE	TRUE	TRUE	TRUE	TRUE	TRUE

[19-4] Truth table of the FB L_And5_1

19.1.13 L_And5_2

This FB implements the ANDing of the input signals.



Inputs

Identifier	Data type	Information/possible settings
bIn1 ... bIn5	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal

Function

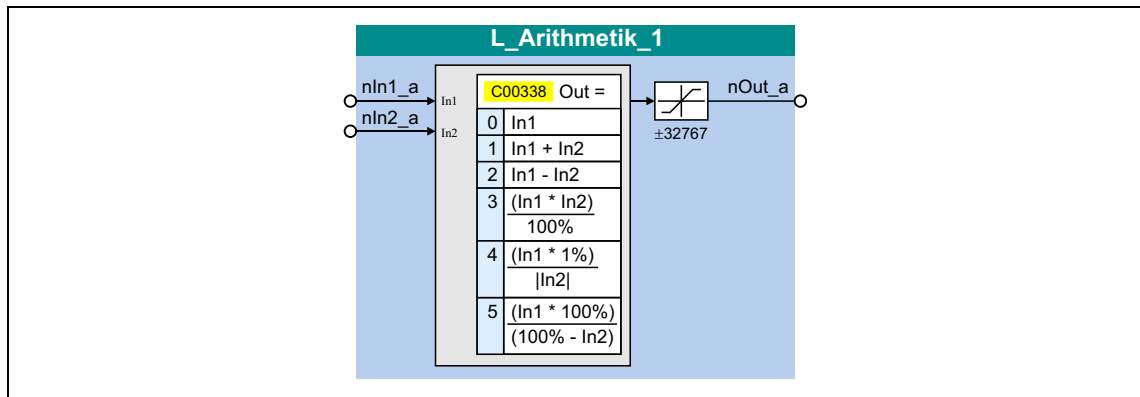
Inputs					Output
bIn5	bIn4	bIn3	bIn2	bIn1	bOut
FALSE	FALSE	FALSE	FALSE	FALSE	FALSE
FALSE	FALSE	FALSE	FALSE	TRUE	
FALSE	FALSE	FALSE	TRUE	FALSE	
FALSE	FALSE	FALSE	TRUE	TRUE	
FALSE	FALSE	TRUE	FALSE	FALSE	
...					
TRUE	TRUE	TRUE	FALSE	TRUE	
TRUE	TRUE	TRUE	TRUE	FALSE	
TRUE	TRUE	TRUE	TRUE	TRUE	TRUE

[19-5] Truth table of the FB L_And5_2

19.1.14 L_Arithmetik_1

This FB can combine two analog signals arithmetically.

- The arithmetic function is selected in [C00338](#).
- All internal intermediate results and the value output at the *nOut_a* output are internally limited to ± 32767 .
- Division is not remainder considered.



Inputs

Identifier	Data type	Information/possible settings
nln1_a	INT	Input signal 1
nln2_a	INT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal • Internal limitation to ± 32767 ($\pm 199.99\%$)

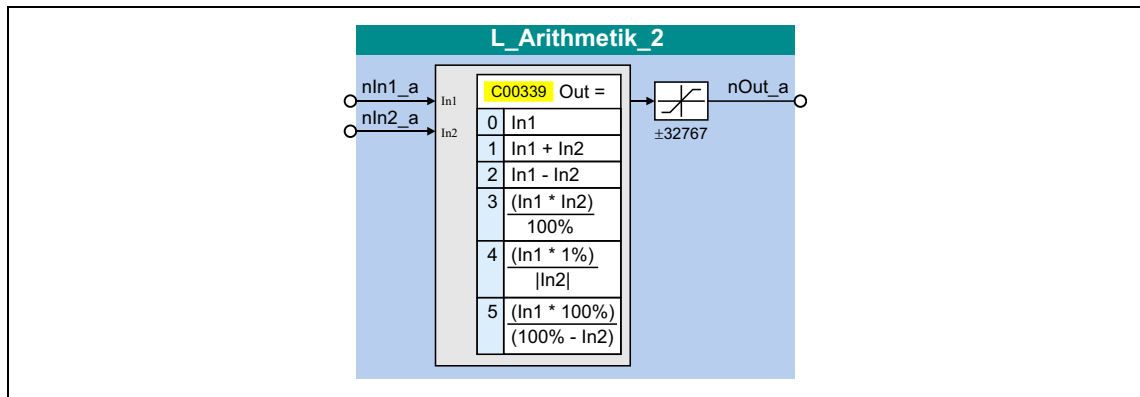
Parameter

Parameter	Possible settings	Info
C00338		Function selection
	0 $nOut_a = nln1_a$	
	1 $nOut_a = nln1_a + nln2_a$	
	2 $nOut_a = nln1_a - nln2_a$	
	3 $nOut_a = \frac{nln1_a \cdot nln2_a}{16384}$	
	4 $nOut_a = \frac{nln1_a}{ nln2_a } \cdot 164$	When the denominator has the value "0", it will be set to "1".
	5 $nOut_a = \frac{nln1_a}{16384 - nln2_a} \cdot 16384$	

19.1.15 L_Arithmetik_2

This FB can combine two analog signals arithmetically.

- The arithmetic function is selected in [C00339](#).
- All internal intermediate results and the value output at the *nOut_a* output are internally limited to ± 32767 .
- Division is not remainder considered.



Inputs

Identifier	Data type	Information/possible settings
nln1_a	INT	Input signal 1
nln2_a	INT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal • Internal limitation to ± 32767 ($\pm 199.99\%$)

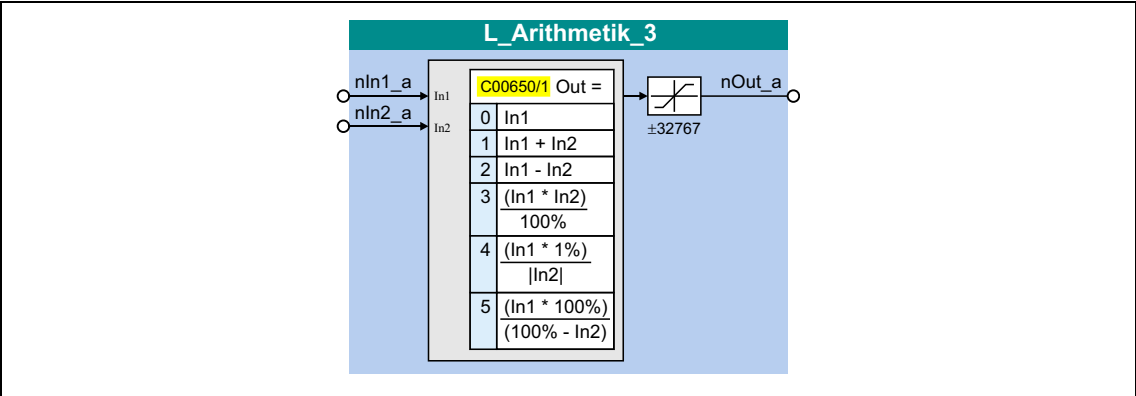
Parameter

Parameter	Possible settings	Info
C00339		Function selection
	0 $nOut_a = nln1_a$	
	1 $nOut_a = nln1_a + nln2_a$	
	2 $nOut_a = nln1_a - nln2_a$	
	3 $nOut_a = \frac{nln1_a \cdot nln2_a}{16384}$	
	4 $nOut_a = \frac{nln1_a}{ nln2_a } \cdot 164$	When the denominator has the value "0", it will be set to "1".
	5 $nOut_a = \frac{nln1_a}{16384 - nln2_a} \cdot 16384$	

19.1.16 L_Arithmetik_3

This FB can combine two analog signals arithmetically.

- The arithmetic function is selected in [C00650/1](#).
- All internal intermediate results and the value output at the *nOut_a* output are internally limited to ±32767.
- Division is not remainder considered.



Inputs

Identifier	Data type	Information/possible settings
nln1_a	INT	Input signal 1
nln2_a	INT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal • Internal limitation to ±32767 (±199.99 %)

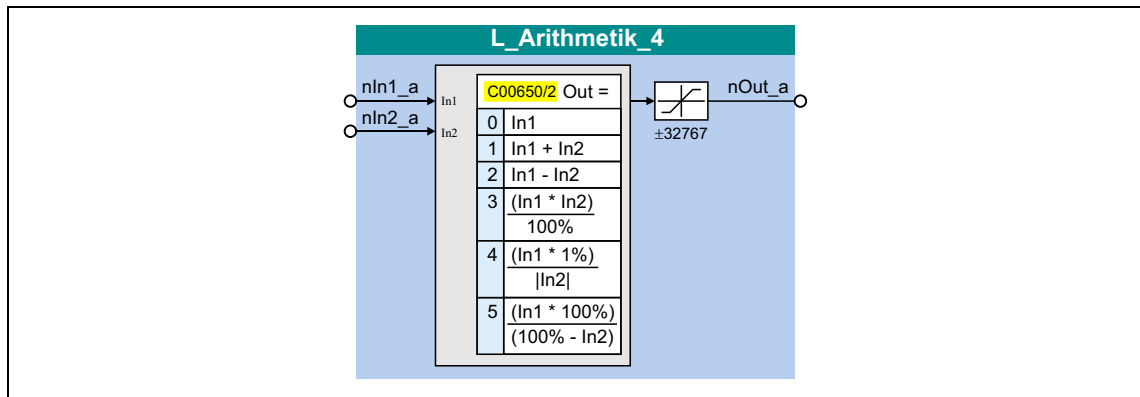
Parameter

Parameter	Possible settings	Info
C00650/1		Function selection
	0 $nOut_a = nln1_a$	
	1 $nOut_a = nln1_a + nln2_a$	
	2 $nOut_a = nln1_a - nln2_a$	
	3 $nOut_a = \frac{nln1_a \cdot nln2_a}{16384}$	
	4 $nOut_a = \frac{nln1_a}{ nln2_a } \cdot 164$	When the denominator has the value "0", it will be set to "1".
	5 $nOut_a = \frac{nln1_a}{16384 - nln2_a} \cdot 16384$	

19.1.17 L_Arithmetik_4

This FB can combine two analog signals arithmetically.

- The arithmetic function is selected in [C00650/2](#).
- All internal intermediate results and the value output at the *nOut_a* output are internally limited to ± 32767 .
- Division is not remainder considered.



Inputs

Identifier	Data type	Information/possible settings
nln1_a	INT	Input signal 1
nln2_a	INT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal • Internal limitation to ± 32767 ($\pm 199.99\%$)

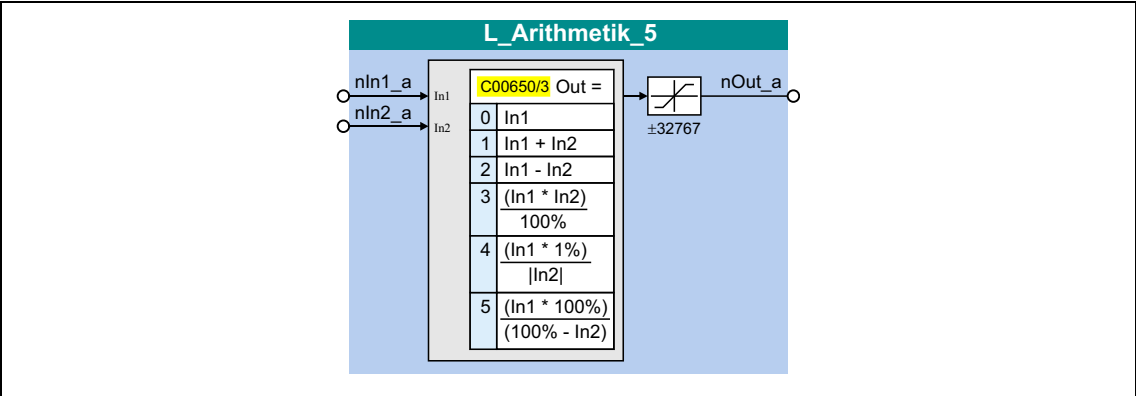
Parameter

Parameter	Possible settings	Info
C00650/2		Function selection
	0 $nOut_a = nln1_a$	
	1 $nOut_a = nln1_a + nln2_a$	
	2 $nOut_a = nln1_a - nln2_a$	
	3 $nOut_a = \frac{nln1_a \cdot nln2_a}{16384}$	
	4 $nOut_a = \frac{nln1_a}{ nln2_a } \cdot 164$	When the denominator has the value "0", it will be set to "1".
	5 $nOut_a = \frac{nln1_a}{16384 - nln2_a} \cdot 16384$	

19.1.18 L_Arithmetik_5

This FB can combine two analog signals arithmetically.

- The arithmetic function is selected in [C00650/3](#).
- All internal intermediate results and the value output at the *nOut_a* output are internally limited to ±32767.
- Division is not remainder considered.



Inputs

Identifier	Data type	Information/possible settings
nln1_a	INT	Input signal 1
nln2_a	INT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal <ul style="list-style-type: none">• Internal limitation to ±32767 (±199.99 %)

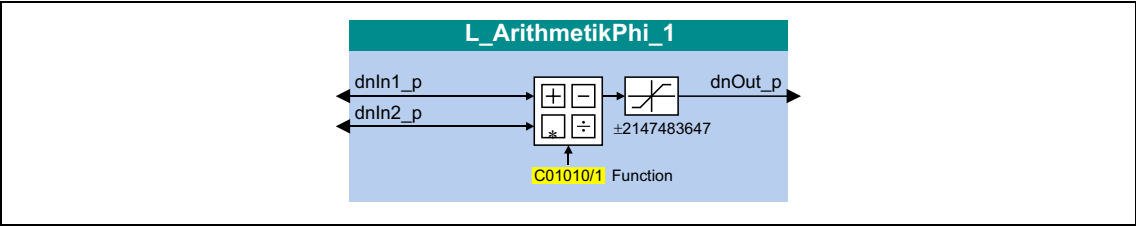
Parameter

Parameter	Possible settings	Info
C00650/3		Function selection
	0 $nOut_a = nln1_a$	
	1 $nOut_a = nln1_a + nln2_a$	
	2 $nOut_a = nln1_a - nln2_a$	
	3 $nOut_a = \frac{nln1_a \cdot nln2_a}{16384}$	
	4 $nOut_a = \frac{nln1_a}{ nln2_a } \cdot 164$	When the denominator has the value "0", it will be set to "1".
	5 $nOut_a = \frac{nln1_a}{16384 - nln2_a} \cdot 16384$	

19.1.19 L_ArithmetikPhi_1

This FB can combine two angle signals arithmetically.

- The arithmetic function is selected in [C01010/1](#).
- All internal intermediate results and the value provided at the *dnOut_p* output are internally limited to ± 2147483647 ($\pm 2^{31} - 1$).
- Division is not remainder considered.



Inputs

Identifier	Data type	Information/possible settings
dnln1_p	DINT	Input signal 1
dnln2_p	DINT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal <ul style="list-style-type: none">• Internal limitation to ± 2147483647

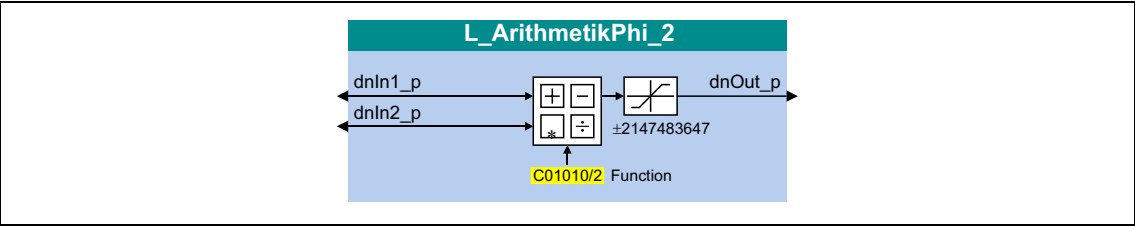
Parameter

Parameter	Possible settings	Info
C01010/1		Function selection
	0 dnOut_p = dnln1_p	
	1 dnOut_p = dnln1_p + dnln2_p	
	2 dnOut_p = dnln1_p - dnln2_p	
	3 dnOut_p = dnln1_p * dnln2_p	
	4 dnOut_p = dnln1_p / dnln2_p	

19.1.20 L_ArithmetikPhi_2

This FB can combine two angle signals arithmetically.

- The arithmetic function is selected in [C01010/2](#).
- All internal intermediate results and the value provided at the *dnOut_p* output are internally limited to ± 2147483647 ($\pm 2^{31} - 1$).
- Division is not remainder considered.



Inputs

Identifier	Data type	Information/possible settings
dnln1_p	DINT	Input signal 1
dnln2_p	DINT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal <ul style="list-style-type: none">• Internal limitation to ± 2147483647

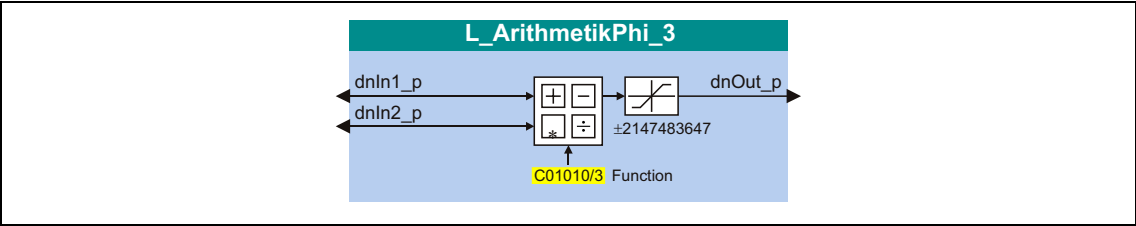
Parameter

Parameter	Possible settings	Info
C01010/2		Function selection
	0 dnOut_p = dnln1_p	
	1 dnOut_p = dnln1_p + dnln2_p	
	2 dnOut_p = dnln1_p - dnln2_p	
	3 dnOut_p = dnln1_p * dnln2_p	
	4 dnOut_p = dnln1_p / dnln2_p	

19.1.21 L_ArithmetikPhi_3

This FB can combine two angle signals arithmetically.

- The arithmetic function is selected in [C01010/3](#).
- All internal intermediate results and the value provided at the *dnOut_p* output are internally limited to ± 2147483647 ($\pm 2^{31} - 1$).
- Division is not remainder considered.



Inputs

Identifier	Data type	Information/possible settings
dnln1_p	DINT	Input signal 1
dnln2_p	DINT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal <ul style="list-style-type: none">• Internal limitation to ± 2147483647

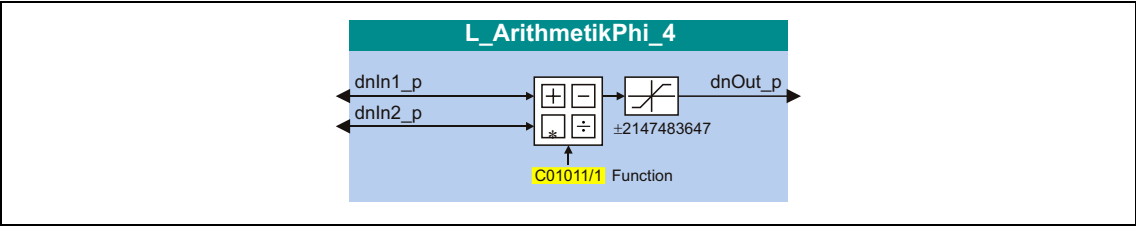
Parameter

Parameter	Possible settings	Info
C01010/3		Function selection
	0 dnOut_p = dnln1_p	
	1 dnOut_p = dnln1_p + dnln2_p	
	2 dnOut_p = dnln1_p - dnln2_p	
	3 dnOut_p = dnln1_p * dnln2_p	
	4 dnOut_p = dnln1_p / dnln2_p	

19.1.22 L_ArithmetikPhi_4

This FB can combine two angle signals arithmetically.

- The arithmetic function is selected in [C01011/1](#).
- All internal intermediate results and the value provided at the *dnOut_p* output are internally limited to ± 2147483647 ($\pm 2^{31} - 1$).
- Division is not remainder considered.



Inputs

Identifier	Data type	Information/possible settings
dnln1_p	DINT	Input signal 1
dnln2_p	DINT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal <ul style="list-style-type: none">• Internal limitation to ± 2147483647

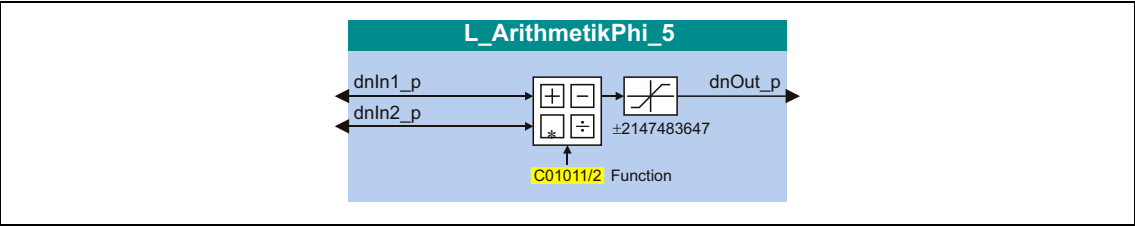
Parameter

Parameter	Possible settings	Info
C01011/1		Function selection
	0 dnOut_p = dnln1_p	
	1 dnOut_p = dnln1_p + dnln2_p	
	2 dnOut_p = dnln1_p - dnln2_p	
	3 dnOut_p = dnln1_p * dnln2_p	
	4 dnOut_p = dnln1_p / dnln2_p	

19.1.23 L_ArithmetikPhi_5

This FB can combine two angle signals arithmetically.

- The arithmetic function is selected in [C01011/2](#).
- All internal intermediate results and the value provided at the *dnOut_p* output are internally limited to ± 2147483647 ($\pm 2^{31} - 1$).
- Division is not remainder considered.



Inputs

Identifier	Data type	Information/possible settings
dnln1_p	DINT	Input signal 1
dnln2_p	DINT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal <ul style="list-style-type: none">• Internal limitation to ± 2147483647

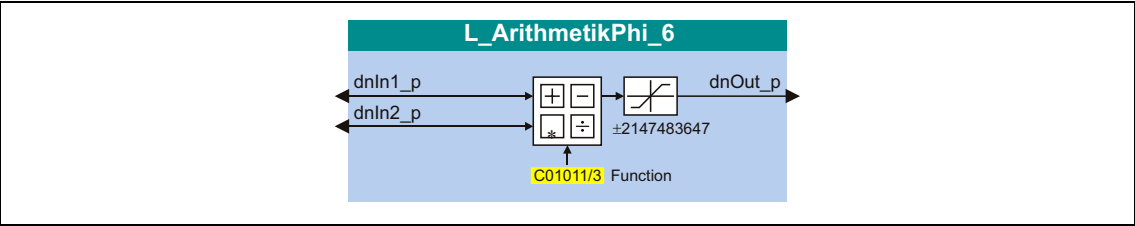
Parameter

Parameter	Possible settings	Info
C01011/2		Function selection
	0 dnOut_p = dnln1_p	
	1 dnOut_p = dnln1_p + dnln2_p	
	2 dnOut_p = dnln1_p - dnln2_p	
	3 dnOut_p = dnln1_p * dnln2_p	
	4 dnOut_p = dnln1_p / dnln2_p	

19.1.24 L_ArithmetikPhi_6

This FB can combine two angle signals arithmetically.

- The arithmetic function is selected in [C01011/3](#).
- All internal intermediate results and the value provided at the *dnOut_p* output are internally limited to ± 2147483647 ($\pm 2^{31} - 1$).
- Division is not remainder considered.



Inputs

Identifier	Data type	Information/possible settings
dnln1_p	DINT	Input signal 1
dnln2_p	DINT	Input signal 2

Outputs

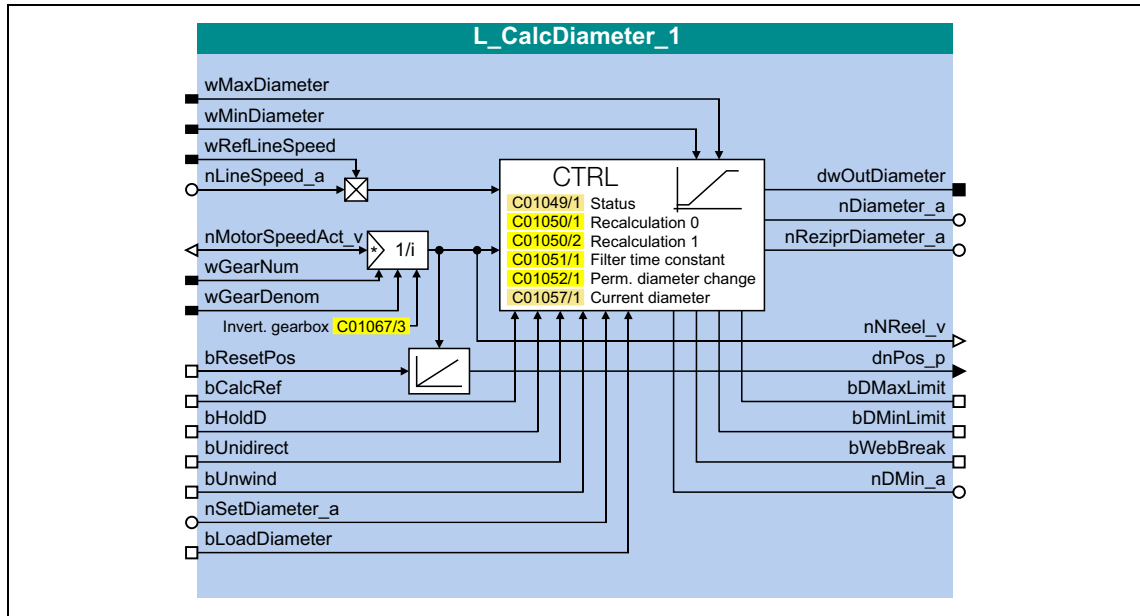
Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal <ul style="list-style-type: none">• Internal limitation to ± 2147483647

Parameter

Parameter	Possible settings	Info
C01011/3		Function selection
	0 dnOut_p = dnln1_p	
	1 dnOut_p = dnln1_p + dnln2_p	
	2 dnOut_p = dnln1_p - dnln2_p	
	3 dnOut_p = dnln1_p * dnln2_p	
	4 dnOut_p = dnln1_p / dnln2_p	

19.1.25 L_CalcDiameter_1

This FB serves to calculate the reel diameter from line speed and winding speed.



Inputs

Identifier	Data type	Information/possible settings
wMaxDiameter	WORD	Maximum diameter in [mm] • Internal limitation to 10000 mm (≈ 10 m)
wMinDiameter	WORD	Minimum diameter in [mm] • Internal limitation to 10000 mm (≈ 10 m)
wRefLineSpeed	WORD	Maximum material speed in [0.1 m/min] • Scaling: 2500 \approx 250.0 m/min • Internal limitation to 3000 m/min
nLineSpeed_a	INT	Material speed setpoint • Scaling: 16384 \approx maximum material speed (<i>wRefLineSpeed</i>)
nMotorSpeedAct_v	INT	Current motor speed in [increments/ms] • Scaling: 16384 \approx 15000 rpm
wGearNum	WORD	Gearbox factor (numerator) • Internal limitation to -32767 ... -1 / 1 ... 32767
wGearDenom	WORD	Gearbox factor (denominator) • Internal limitation to 1 ... 32767
bResetPos	BOOL	Reset angle of rotation <i>dnPos_p</i> TRUE The angle of rotation <i>dnPos_p</i> is reset.
bCalcRef	BOOL	Selection of the calculation cycle FALSE Use diameter recalculation 0 (C01050/1). TRUE Use diameter recalculation 1 (C01050/2).
bHoldD	BOOL	Hold last diameter value TRUE The diameter value output last is not overwritten by the new values.
bUnidirect	BOOL	Enable of only one change of direction and activation of the web break monitoring TRUE Only the change of direction defined via <i>bUnwind</i> is enabled.

Identifier	Data type	Information/possible settings
bUnwind	BOOL	Selection of the enabled change or direction • Only when <i>bUnidirect</i> = TRUE
		FALSE Clockwise rotation (Cw)
		TRUE Counter-clockwise rotation (Ccw)
nSetDiameter_a	DINT	Selection of an initial value/external diameter signal • Scaling: 16384 \equiv maximum diameter (<i>wMaxDiameter</i>) • The value is accepted by setting <i>bLoadDiameter</i> to TRUE.
bLoadDiameter	BOOL	Accept initial value <i>nSetDiameter_a</i> • This input has a higher priority than the <i>bHoldDinput</i> .
		TRUE Accept the value at <i>nSetDiameter_a</i> .

Outputs

Identifier	Data type	Value/meaning
dwOutDiameter	DWORD	Current diameter in [μ m] • Internal limitation to 10 m • Unfiltered
nDiameter_a	INT	Current diameter in [%] • 100 % \equiv Maximum diameter (<i>wMaxDiameter</i>) • filtered via PT1 element (filter time constant can be set in C01051/1)
nReziprDiameter_a	INT	Reciprocal value of the current diameter in [%] • 100 % \equiv Minimum diameter (<i>wMinDiameter</i>)
nNReel_v	INT	Current winding speed in [increments/ms] • Scaling: 16384 \equiv 15000 rpm
bDMaxLimit	BOOL	Limit value monitoring
		TRUE Upper limit value <i>wMaxDiameter</i> reached.
bDMinLimit	BOOL	Limit value monitoring
		TRUE Lower limit value <i>wMinDiameter</i> reached.
bWebBreak	BOOL	Web break monitoring
		TRUE Web break after passing the monitor window set in C01052/1 .
nDMin_a	INT	Minimum diameter in [%] • 100 % \equiv Maximum diameter (<i>wMaxDiameter</i>)

Parameter

Parameter	Possible settings	Info
C01049/1		Status
	-10 Line speed overflow	
	-1 <i>wMinDiameter</i> > <i>wMaxDiameter</i>	
	0 OK - diameter has been recalculated	
	10 Diameter has been initialised with minimum diameter (<i>wMinDiameter</i>)	
	20 Diameter is loaded (<i>bLoadDiameter</i> active)	
	30 Diameter is held (<i>bHoldD</i> active)	

Parameter	Possible settings			Info
C01050/1	0.001	Rev.	2.000	Diameter recalculation 0 <ul style="list-style-type: none">• Number of revolutions after which a diameter calculation is executed.• Setting is effective when <i>bCalcRef</i> = FALSE.• Initialisation: 1.000
C01050/2	0.001	Rev.	2.000	Diameter recalculation 1 <ul style="list-style-type: none">• Number of revolutions after which a diameter calculation is executed.• Setting is effective when <i>bCalcRef</i> = TRUE.• Initialisation: 0.100
C01051/1	0.010	s	3.000	Filter time constant for calculated diameter values <ul style="list-style-type: none">• Initialisation: 1.000 s
C01052/1	0.00	%	100.00	Permissible diameter change in opposite direction (web break monitoring) <ul style="list-style-type: none">• Only relevant when <i>bUnidirect</i> = TRUE.• Referring to the maximum diameter (<i>wMaxDiameter</i>).• Initialisation: 10.00 %
C01057/1	0.000	mm	10000.000	Current diameter <ul style="list-style-type: none">• Read only
C01067/3				Invert. gearbox nMotorSpeedAct_v
	0	not inverted		
	1	inverted		
	2	Automatically from MCK		

19.1.25.1 Set initial value

An initial value or an external diameter signal can be defined at the *nSetDiameter_a* input.

- this value is accepted if *bLoadDiameter* is set to TRUE.
- In case of acceptance, the diameter calculation will be reset and the filter for diameter calculation is loaded with the defined initial value.

19.1.25.2 Calculate diameter

For reel diameter calculation, the material speed and the current winding speed are integrated cyclically.

- The material speed is defined via *nLineSpeed_a*.
- The winding speed is calculated from the *nMotorSpeedAct_v* motor speed and the current *wGearNum/wGearDenom* gearbox factor.
- [C01050/1...2](#) can be used to define two different calculation cycles. The setting to be used is selected via *bCalcRef*.
- At the end of each integration interval, a new diameter value results from the division of the integrator values.
- An absolute value generation and smoothing via a first order low pass is carried out. The time constant of this filter can be set in [C01051/1](#). The *dwOutDiameter* output is not filtered.

19.1.25.3 Select change direction, web break monitoring

By setting *bUnidirect* to TRUE, you only enable one change direction for diameter calculation and simultaneously activate the web break monitoring.

- The permissible change direction can be defined via *bUnwind*.
- A recalculated value is only accepted if it exceeds the value saved last in the permissible direction.

After a web break, the diameter values calculated successively mostly run very quickly in the opposite direction.

- [C01052/1](#) serves to define the maximally permissible deviation in the opposite direction. If it is exceeded, the *bWebBreak* output is set to TRUE.
- If *bUnidirect* is set to FALSE, both change directions are enabled and the internal memory is always overwritten with the recalculated value which switches off the web break monitoring.

19.1.25.4 Holding the current value

By setting *bHoldD* to TRUE, you fix the diameter value *nDiameter_a* output last.

- The diameter calculation is reset and the filter for diameter calculation is loaded with the internally held diameter value.

19.1.25.5 Limit value monitoring

wMinDiameter and *wMaxDiameter* serve to define the limit values for the given diameter values. If they are reached/exceeded, the corresponding output (*bDMaxLimit/bDminLimit*) is set to TRUE.

- The unfiltered diameter value *dwOutDiameter* and the filtered diameter value *nDiameter_a* are limited.
- The limit values are entered in [mm].
- The hysteresis for resetting *bDMaxLimit/bDminLimit* is permanently set to 1 % of *wMaxDiameter*.
- For parameter setting of further FBs, the value in *wMinDiameter* with regard to *wMaxDiameter* is provided via the *nDMin_a* output.

19.1.25.6 Converting diameter in 1/D

For evaluating the material speed with 1/D (speed-controlled winder), the reciprocal value of the reel diameter is provided via *nReziprDiameter_a*.

- This value refers to the limitation value *wMinDiameter*.

19.1.25.7 Physical state variables

The *dwOutDiameter* output provides the current diameter as physical quantity (1 LSB \equiv 1 m).

nNReel_v outputs the winding speed which results from the *nMotorSpeedAct_v* motor speed and the current (*wGearNum/wGearDenom*) gearbox factor.

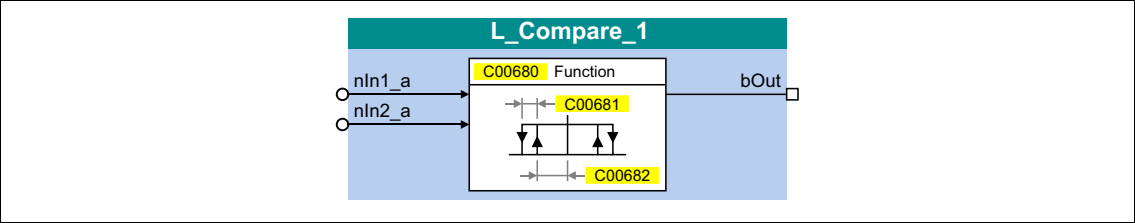
For supporting further functions (e.g. a traversing control), the winding speed is integrated additionally.

- The angle of rotation is output via *dnPos_p*.
- By setting *bResetPos* to TRUE, the angle of rotation is reset.

19.1.26 L_Compare_1

This FB compares two analog signals and can be used e.g. to implement a trigger.

- Comparison operation, hysteresis and window size can be parameterised.



Inputs

Identifier	Data type	Information/possible settings
nln1_a	INT	Input signal 1
nln2_a	INT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Status signal "Comparison statement is true"
		TRUE The statement of the selected comparison mode is true.

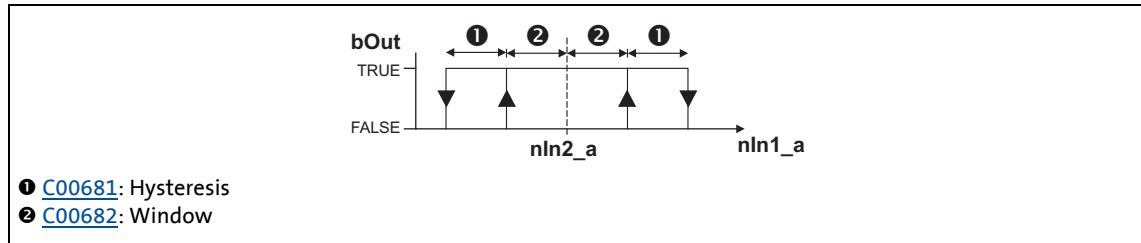
Parameter

Parameter	Possible settings			Info
C00680				Function selection
	1	$nln1 = nln2$		
	2	$nln1 > nln2$		
	3	$nln1 < nln2$		
	4	$ nln1 = nln2 $		
	5	$ nln1 > nln2 $		
	6	$ nln1 < nln2 $		
C00681	0.00	%	100.00	Hysteresis • Lenze setting: 0.50 %
C00682	0.00	%	100.00	Window • Lenze setting: 2.00 %

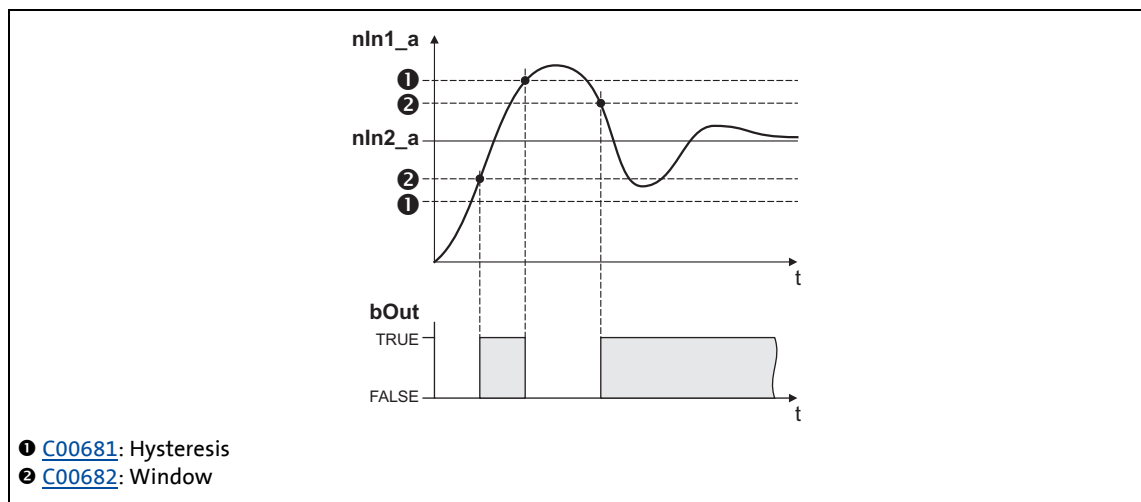
19.1.26.1 Function 1: nln1 = nln2

This function compares two signals with regard to equality. It can, for instance, provide the comparison "actual speed equals setpoint speed" ($n_{act} = n_{set}$).

- Use [C00682](#) to set the window within which the equality is to apply.
- Use [C00681](#) to set a hysteresis if the input signals are not stable and the output oscillates.



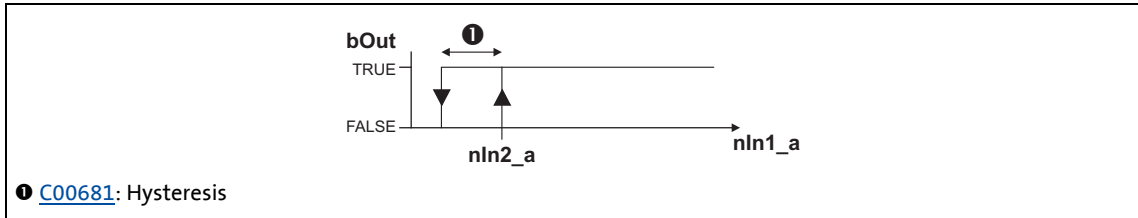
[19-6] Function 1: Switching performance



[19-7] Function 1: Example

19.1.26.2 Function 2: $nln1 > nln2$

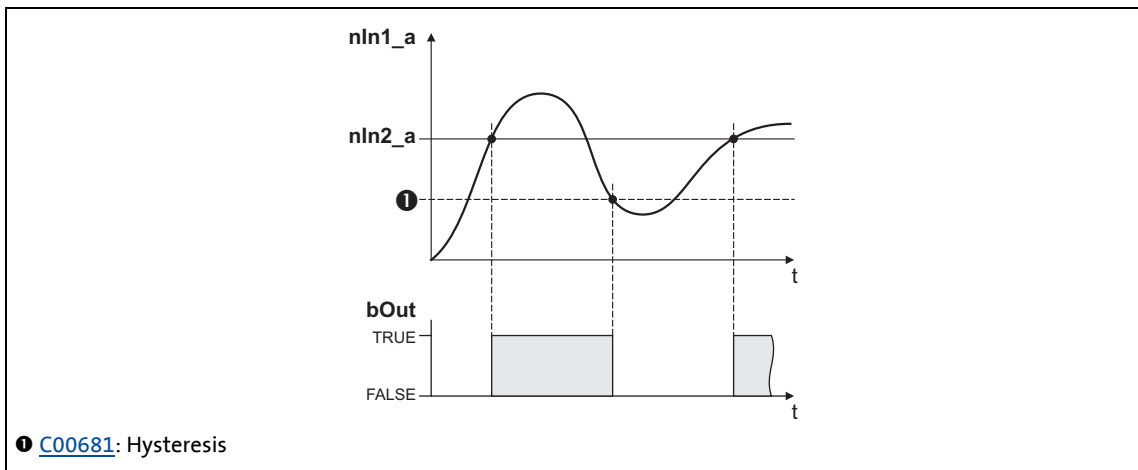
This function serves, for instance, to implement the comparison "actual speed is higher than a limit value" ($n_{act} > n_x$) for one direction of rotation.



[19-8] Function 2: Switching performance

Functional sequence

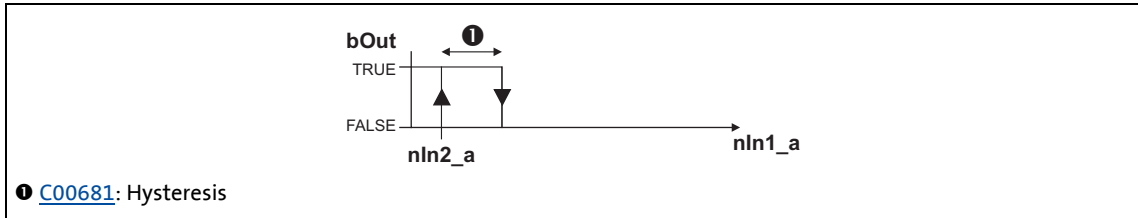
1. If the value at $nln1_a$ exceeds the value $nln2_a$, $bOut$ changes from FALSE to TRUE.
2. Only if the signal at $nln1_a$ falls below the value of $nln2_a$ - *hysteresis* again, $bOut$ changes back from TRUE to FALSE.



[19-9] Function 2: Example

19.1.26.3 Function 3: $nln1 < nln2$

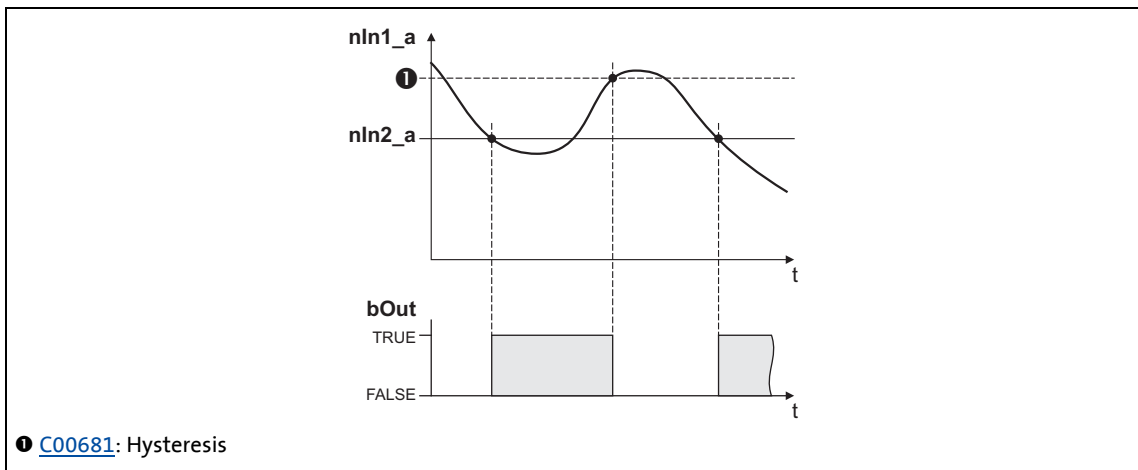
This function serves, for instance, to implement the comparison "actual speed is lower than a limit value" ($n_{act} < n_x$) for one direction of rotation.



[19-10] Function 3: Switching performance

Functional sequence

1. If the value at $nln1_a$ falls below the value at $nln2_a$, $bOut$ changes from FALSE to TRUE.
2. Only if the signal at $nln1_a$ exceeds the value of $nln2_a$ - *hysteresis* again, $bOut$ changes back from TRUE to FALSE.



[19-11] Function 3: Example

19.1.26.4 Function 4: $|n_{ln1}| = |n_{ln2}|$

This function serves to implement e.g. the comparison " $n_{act} = 0$ ". This function is similar to function 1. However, the amount is generated by the input signals before signal processing (without sign).

► [Function 1: \$n_{ln1} = n_{ln2}\$](#)

19.1.26.5 Function 5: $|n_{ln1}| > |n_{ln2}|$

This function serves to implement e.g. the comparison " $|n_{act}| > |n_x|$ " irrespective of the direction of rotation. This function is similar to function 2. However, the amount is generated by the input signals before signal processing (without sign).

► [Function 2: \$n_{ln1} > n_{ln2}\$](#)

19.1.26.6 Function 6: $|n_{ln1}| < |n_{ln2}|$

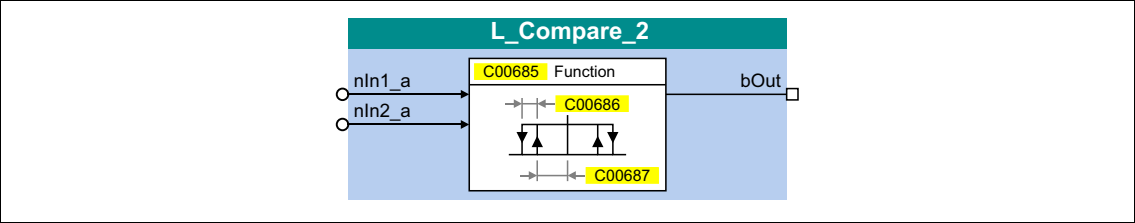
This function serves to implement the comparison " $|n_{act}| < |n_x|$ " independent of the direction of rotation. This function is similar to function 3. However, the amount is generated by the input signals before signal processing (without sign).

► [Function 3: \$n_{ln1} < n_{ln2}\$](#)

19.1.27 L_Compare_2

This FB compares two analog signals and can be used e.g. to implement a trigger.

- Comparison operation, hysteresis and window size can be parameterised.



Inputs

Identifier	Data type	Information/possible settings
nIn1_a	INT	Input signal 1
nIn2_a	INT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Status signal "Comparison statement is true"
		TRUE The statement of the selected comparison mode is true.

Parameter

Parameter	Possible settings			Info
C00685				Function selection
	1	$nIn1 = nIn2$		
	2	$nIn1 > nIn2$		
	3	$nIn1 < nIn2$		
	4	$ nIn1 = nIn2 $		
	5	$ nIn1 > nIn2 $		
	6	$ nIn1 < nIn2 $		
C00686	0.00	%	100.00	Hysteresis • Lenze setting: 0.50 %
C00687	0.00	%	100.00	Window • Lenze setting: 2.00 %

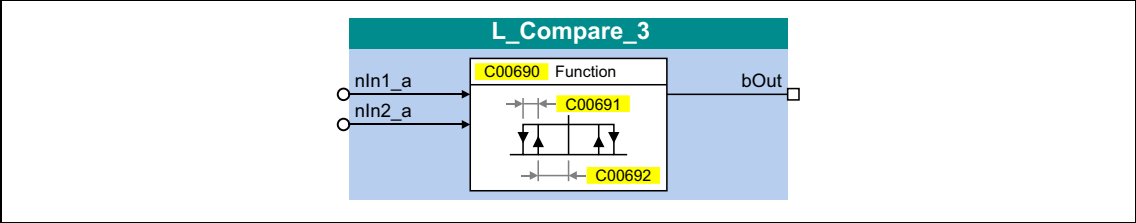


For a detailed functional description see [L_Compare_1](#).

19.1.28 L_Compare_3

This FB compares two analog signals and can be used e.g. to implement a trigger.

- Comparison operation, hysteresis and window size can be parameterised.



Inputs

Identifier	Data type	Information/possible settings
nln1_a	INT	Input signal 1
nln2_a	INT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Status signal "Comparison statement is true"
		TRUE The statement of the selected comparison mode is true.

Parameter

Parameter	Possible settings			Info
C00690				Function selection
	1	nln1 = nln2		
	2	nln1 > nln2		
	3	nln1 < nln2		
	4	nln1 = nln2		
	5	nln1 > nln2		
	6	nln1 < nln2		
C00691	0.00	%	100.00	Hysteresis • Lenze setting: 0.50 %
C00692	0.00	%	100.00	Window • Lenze setting: 2.00 %

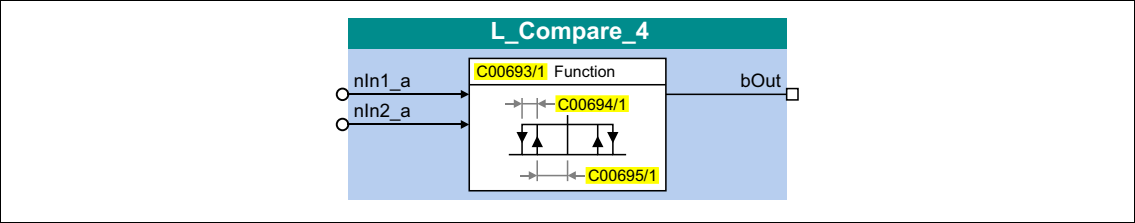


For a detailed functional description see [L_Compare_1](#).

19.1.29 L_Compare_4

This FB compares two analog signals and can be used e.g. to implement a trigger.

- Comparison operation, hysteresis and window size can be parameterised.



Inputs

Identifier	Data type	Information/possible settings
nln1_a	INT	Input signal 1
nln2_a	INT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Status signal "Comparison statement is true"
		TRUE The statement of the selected comparison mode is true.

Parameter

Parameter	Possible settings			Info
C00693/1				Function selection
	1	$nln1 = nln2$		
	2	$nln1 > nln2$		
	3	$nln1 < nln2$		
	4	$ nln1 = nln2 $		
	5	$ nln1 > nln2 $		
	6	$ nln1 < nln2 $		
C00694/1	0.00	%	100.00	Hysteresis <ul style="list-style-type: none">• Lenze setting: 0.00 %
C00695/1	0.00	%	100.00	Window <ul style="list-style-type: none">• Lenze setting: 0.00 %

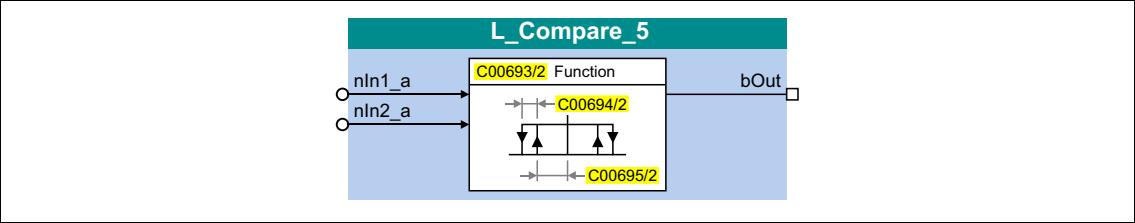


For a detailed functional description see [L_Compare_1](#).

19.1.30 L_Compare_5

This FB compares two analog signals and can be used e.g. to implement a trigger.

- Comparison operation, hysteresis and window size can be parameterised.



Inputs

Identifier	Data type	Information/possible settings
nln1_a	INT	Input signal 1
nln2_a	INT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Status signal "Comparison statement is true"
		TRUE The statement of the selected comparison mode is true.

Parameter

Parameter	Possible settings			Info
C00693/2				Function selection
	1	$nln1 = nln2$		
	2	$nln1 > nln2$		
	3	$nln1 < nln2$		
	4	$ nln1 = nln2 $		
	5	$ nln1 > nln2 $		
	6	$ nln1 < nln2 $		
C00694/2	0.00	%	100.00	Hysteresis • Lenze setting: 0.00 %
C00695/2	0.00	%	100.00	Window • Lenze setting: 0.00 %

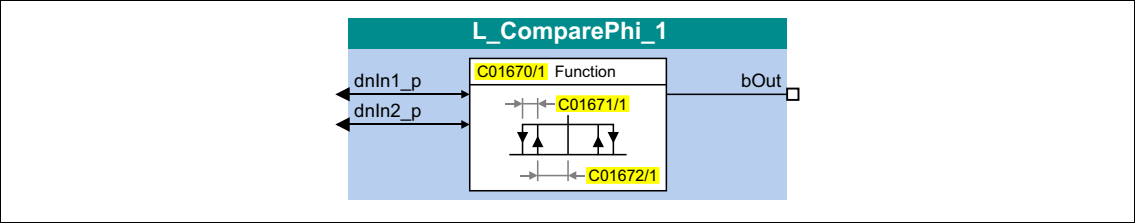


For a detailed functional description see [L_Compare_1](#).

19.1.31 L_ComparePhi_1

This FB compares two angle signals.

- Comparison operation, hysteresis and window size can be parameterised.



Inputs

Identifier	Data type	Information/possible settings
dnln1_p	DINT	Input signal 1
dnln2_p	DINT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Status signal "Comparison statement is true"
		TRUE The statement of the selected comparison mode is true.

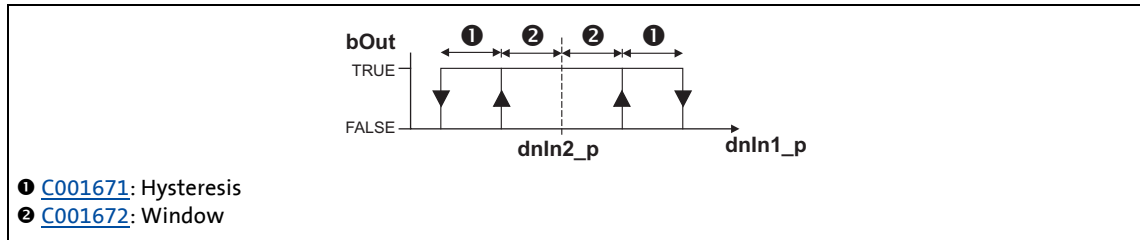
Parameter

Parameter	Possible settings			Info
C01670/1				Function selection
	1	dnln1 = dnln2		
	2	dnln1 > dnln2		
	3	dnln1 < dnln2		
	4	dnln1 = dnln2		
	5	dnln1 > dnln2		
	6	dnln1 < dnln2		
C01671/1	0	Incr.	1073741824	Hysteresis • Lenze setting: 0 incr.
C01672/1	0	Incr.	1073741824	Window • Lenze setting: 0 incr.

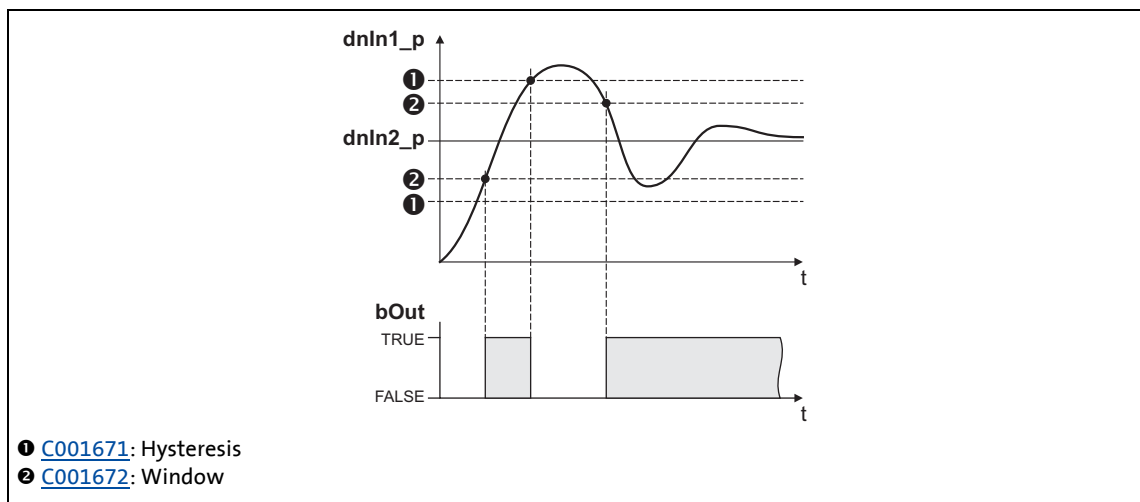
19.1.31.1 Function 1: $dnln1 = dnln2$

This function compares two signals with regard to equality. It can, for instance, provide the comparison "actual speed equals setpoint speed" ($n_{act} = n_{set}$).

- Use [C001672](#) to set the window within which the equality is to apply.
- Use [C001671](#) to set a hysteresis if the input signals are not stable and the output oscillates.



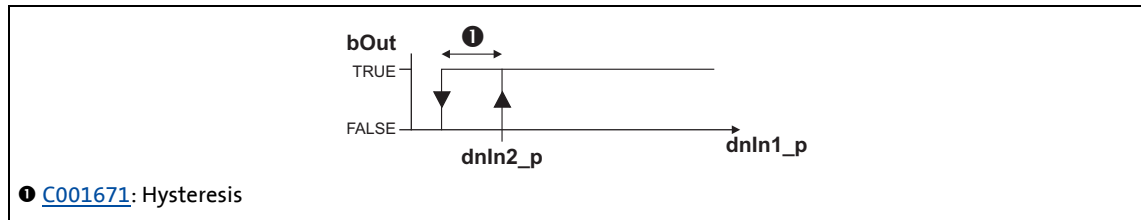
[19-12] Function 1: Switching performance



[19-13] Function 1: Example

19.1.31.2 Function 2: dnln1 > dnln2

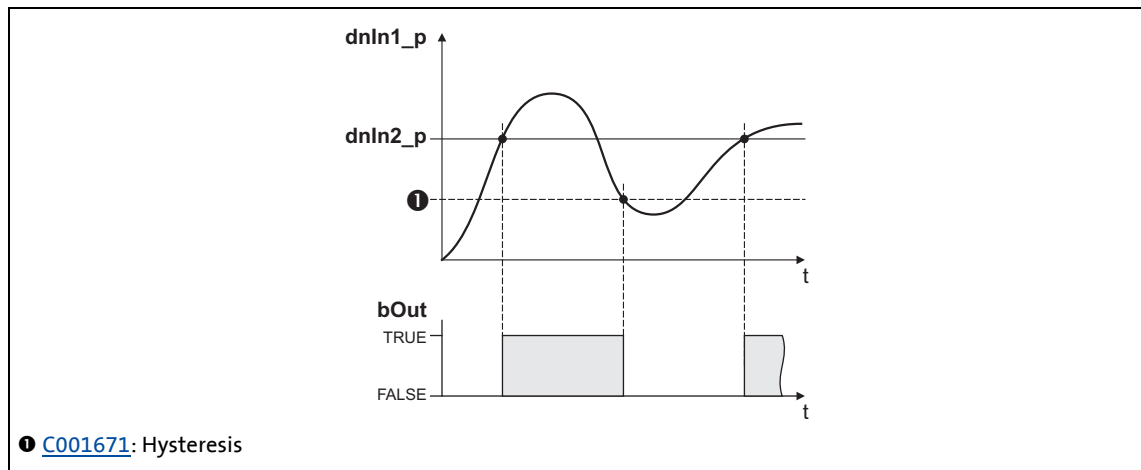
This function serves, for instance, to implement the comparison "actual speed is higher than a limit value" ($n_{act} > n_x$) for one direction of rotation.



[19-14] Function 2: Switching performance

Functional sequence

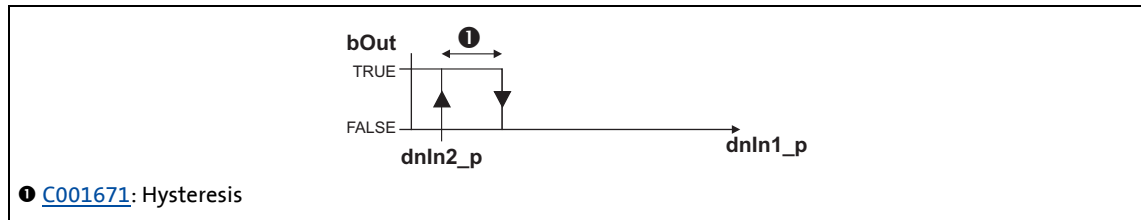
1. If the value at **dnln1_p** exceeds the value at **dnln2_p**, **bOut** changes from FALSE to TRUE.
2. Only if the signal at **dnln1_p** falls below the value of **dnln2_p** - *hysteresis* again, **bOut** changes back from TRUE to FALSE.



[19-15] Function 2: Example

19.1.31.3 Function 3: $dnln1 < dnln2$

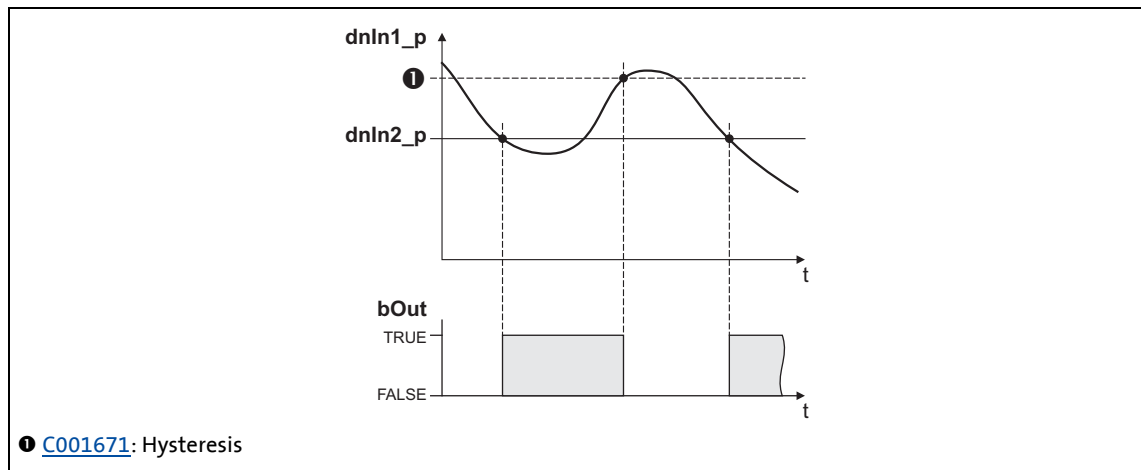
This function serves, for instance, to implement the comparison "actual speed is lower than a limit value" ($n_{act} < n_x$) for one direction of rotation.



[19-16] Function 3: Switching performance

Functional sequence

1. If the value at $dnln1_p$ falls below the value at $dnln2_p$, $bOut$ changes from FALSE to TRUE.
2. Only if the signal at $dnln1_p$ exceeds the value of $dnln2_p$ - *hysteresis* again, $bOut$ changes back from TRUE to FALSE.



[19-17] Function 3: Example

19.1.31.4 Function 4: $|\text{dnIn1}| = |\text{dnIn2}|$

This function serves to implement e.g. the comparison " $n_{\text{act}} = 0$ ". This function is similar to function 1. However, the amount is generated by the input signals before signal processing (without sign).

► [Function 1: \$\text{dnIn1} = \text{dnIn2}\$](#)

19.1.31.5 Function 5: $|\text{dnIn1}| > |\text{dnIn2}|$

This function serves to implement e.g. the comparison " $|n_{\text{act}}| > |n_x|$ " irrespective of the direction of rotation. This function is similar to function 2. However, the amount is generated by the input signals before signal processing (without sign).

► [Function 2: \$\text{dnIn1} > \text{dnIn2}\$](#)

19.1.31.6 Function 6: $|\text{dnIn1}| < |\text{dnIn2}|$

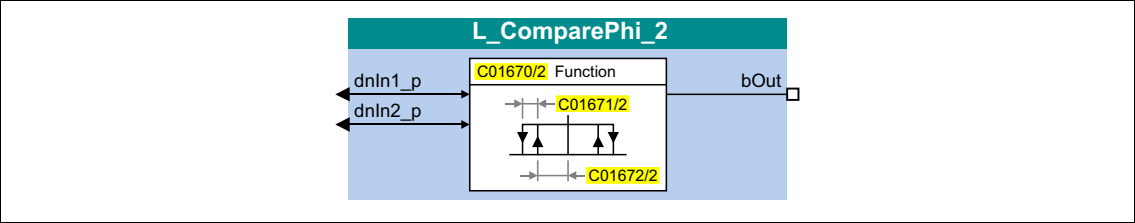
This function serves to implement the comparison " $|n_{\text{act}}| < |n_x|$ " independent of the direction of rotation. This function is similar to function 3. However, the amount is generated by the input signals before signal processing (without sign).

► [Function 3: \$\text{dnIn1} < \text{dnIn2}\$](#)

19.1.32 L_ComparePhi_2

This FB compares two angle signals.

- Comparison operation, hysteresis and window size can be parameterised.



Inputs

Identifier	Data type	Information/possible settings
dnln1_p	DINT	Input signal 1
dnln2_p	DINT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Status signal "Comparison statement is true"
		TRUE The statement of the selected comparison mode is true.

Parameter

Parameter	Possible settings			Info
C01670/2				Function selection
	1	dnln1 = dnln2		
	2	dnln1 > dnln2		
	3	dnln1 < dnln2		
	4	dnln1 = dnln2		
	5	dnln1 > dnln2		
	6	dnln1 < dnln2		
C01671/2	0	Incr.	1073741824	Hysteresis • Lenze setting: 0 incr.
C01672/2	0	Incr.	1073741824	Window • Lenze setting: 0 incr.

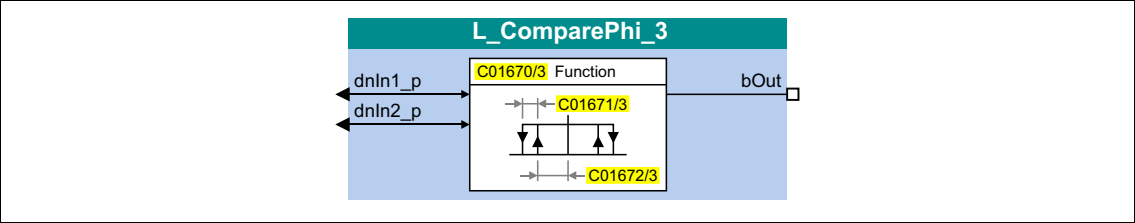


For a detailed functional description see [L_ComparePhi_1](#).

19.1.33 L_ComparePhi_3

This FB compares two angle signals.

- Comparison operation, hysteresis and window size can be parameterised.



Inputs

Identifier	Data type	Information/possible settings
dnln1_p	DINT	Input signal 1
dnln2_p	DINT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Status signal "Comparison statement is true"
		TRUE The statement of the selected comparison mode is true.

Parameter

Parameter	Possible settings			Info
C01670/3				Function selection
	1	dnln1 = dnln2		
	2	dnln1 > dnln2		
	3	dnln1 < dnln2		
	4	dnln1 = dnln2		
	5	dnln1 > dnln2		
	6	dnln1 < dnln2		
C01671/3	0	Incr.	1073741824	Hysteresis • Lenze setting: 0 incr.
C01672/3	0	Incr.	1073741824	Window • Lenze setting: 0 incr.

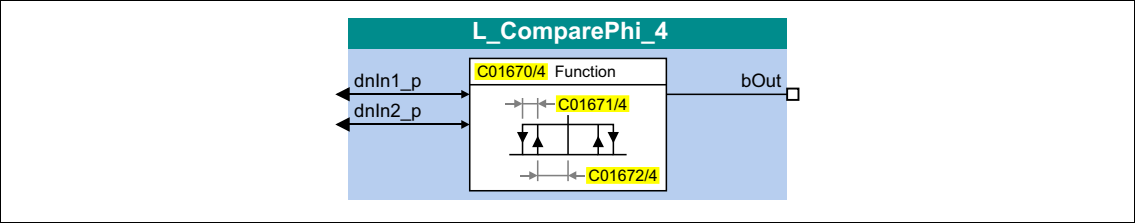


For a detailed functional description see [L_ComparePhi_1](#).

19.1.34 L_ComparePhi_4

This FB compares two angle signals.

- Comparison operation, hysteresis and window size can be parameterised.



Inputs

Identifier	Data type	Information/possible settings
dnln1_p	DINT	Input signal 1
dnln2_p	DINT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Status signal "Comparison statement is true"
		TRUE The statement of the selected comparison mode is true.

Parameter

Parameter	Possible settings			Info
C01670/4				Function selection
	1	dnln1 = dnln2		
	2	dnln1 > dnln2		
	3	dnln1 < dnln2		
	4	dnln1 = dnln2		
	5	dnln1 > dnln2		
	6	dnln1 < dnln2		
C01671/4	0	Incr.	1073741824	Hysteresis • Lenze setting: 0 incr.
C01672/4	0	Incr.	1073741824	Window • Lenze setting: 0 incr.

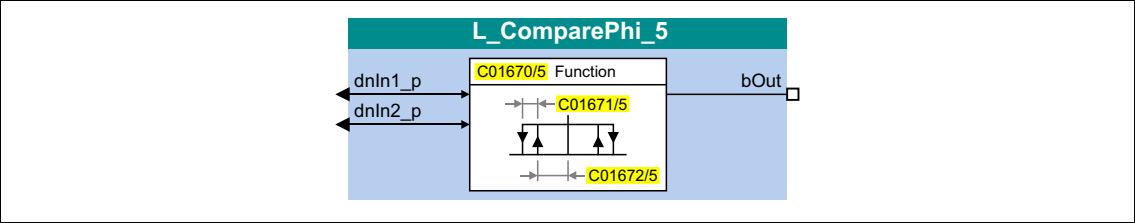


For a detailed functional description see [L_ComparePhi_1](#).

19.1.35 L_ComparePhi_5

This FB compares two angle signals.

- Comparison operation, hysteresis and window size can be parameterised.



Inputs

Identifier	Data type	Information/possible settings
dnln1_p	DINT	Input signal 1
dnln2_p	DINT	Input signal 2

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Status signal "Comparison statement is true"
		TRUE The statement of the selected comparison mode is true.

Parameter

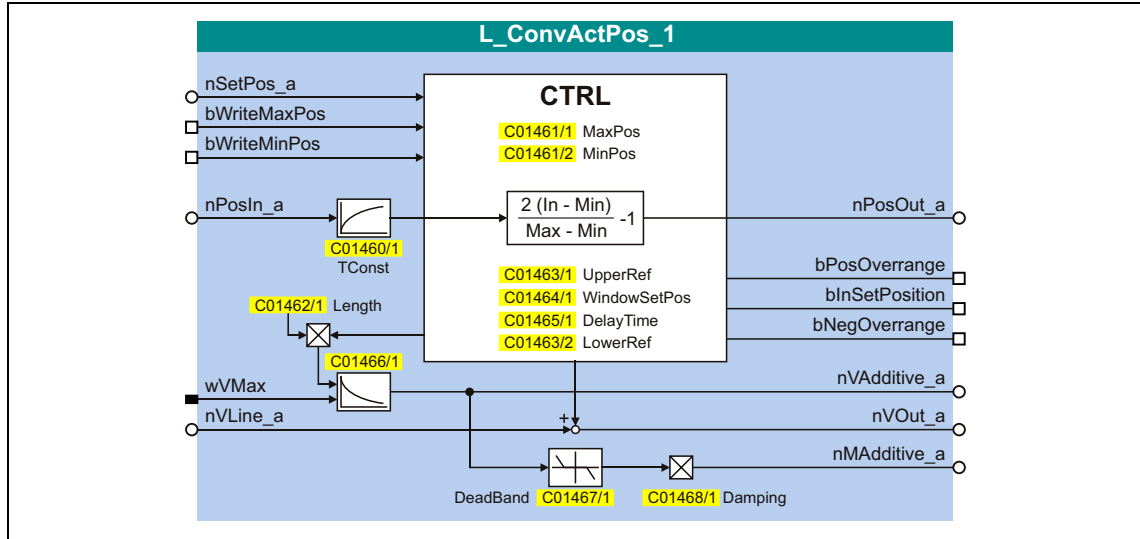
Parameter	Possible settings			Info
C01670/5				Function selection
	1	dnln1 = dnln2		
	2	dnln1 > dnln2		
	3	dnln1 < dnln2		
	4	dnln1 = dnln2		
	5	dnln1 > dnln2		
	6	dnln1 < dnln2		
C01671/5	0	Incr.	1073741824	Hysteresis • Lenze setting: 0 incr.
C01672/5	0	Incr.	1073741824	Window • Lenze setting: 0 incr.



For a detailed functional description see [L_ComparePhi_1](#).

19.1.36 L_ConvActPos_1

This FB serves to filter an actual dancer position value and scale it to the available setting range. The setting range is defined by parameterisable limit positions which can optionally be accepted automatically by a "teach-in" function.



Inputs

Identifier	Data type	Information/possible settings
nSetPos_a	INT	Current position setpoint • Scaling: 16384 ≡ 100 %
bWriteMaxPos	BOOL	"Teach-In" function for the upper limit position TRUE Actual position is saved as upper limit position in C01461/1 .
bWriteMinPos	BOOL	"Teach-In" function for the lower limit position TRUE Actual position is saved as lower limit position in C01461/2 .
nPosIn_a	INT	Actual position • Scaling: 16384 ≡ 100 %
wVMax	WORD	Maximum material speed in [0.1 m/min] • Scaling: 2500 ≡ 250.0 m/min • Internal limitation to 3000 m/min
nVLine_a	INT	Current material speed • Scaling: 16384 ≡ Maximum material speed (wVMax)

Outputs

Identifier	Data type	Value/meaning
nPosOut_a	INT	Converted actual position value • Scaling: 16384 ≡ 100 % ≡ upper limit position (C01461/1) -16384 ≡ -100 % ≡ lower limit position (C01461/2)
bPosOverrange	BOOL	Monitoring of upper home position TRUE Upper home position (C01463/1) reached.
bInSetPosition	BOOL	Monitoring of setpoint TRUE Setpoint nSetPos_a reached.

Identifier	Data type	Value/meaning
bNegOverrange	BOOL	Monitoring of lower home position
		TRUE Lower home position (C01463/2) reached.
nVAdditive_a	INT	Material speed caused by the dancer motion • Scaling: 16384 \equiv Maximum material speed (<i>wVMax</i>)
nVOut_a	INT	Current circumferential speed of the reel when the dancer hub is entered • Scaling: 16384 \equiv Maximum material speed (<i>wVMax</i>)
nMAdditive_a	INT	Additional torque for damping the dancer position control • Scaling: 16384 \equiv 100 %

Parameter

Parameter	Possible settings			Info
C01460/1	0	ms	1000	TConst • Time constant for filtering the actual position value. • Lenze setting: 10 ms
C01461/1		%		Upper limit position • Lenze setting: 100.00 %
C01461/2		%		Lower limit position • Lenze setting: -100.00 %
C01462/1		mm		dwLength • Storage volumen of the dancer (dancer hub). • Lenze setting:
C01463/1		%		Upper home position • Lenze setting: 90.00 %
C01463/2		%		Lower home position • Lenze setting: -90.00 %
C01464/1		%		nWindowSetPos • Tolerance zone for monitoring the dancer position. • Lenze setting: 10.00 %
C01465/1		s		wDelayTime • Delay time for monitoring the dancer position. • Lenze setting: 0.100 s
C01466/1		ms		wTConstVAdd • Time constant for filtering the additional speed. • Lenze setting: 10 ms
C01467/1		%		nDeadBand • Dead band area for feedforward control torque (<i>nMAdditive_a</i>). • Lenze setting: 1.00 %
C01468/1				wDamping • Damping factor for feedforward control torque (<i>nMAdditive_a</i>). • Lenze setting: 0.00

19.1.36.1 Determining limit positions

Option 1: Parameterising the limit positions

- Enter the actual value where the material stored in the dancer reaches its minimum length as upper limit position in [C01461/1](#).
- Enter the actual value where the material stored in the dancer reaches its maximum length as lower limit position in [C01461/2](#).
- If the dancer detection provides an inverse signal, the lower limit position can be greater than the upper limit position.

Option 2: Defining the limit positions using the "teach-in" function

Alternatively to the direct setting of the limit values in the two parameters mentioned above, it is possible to bring the dancer into the respective limit position and then transfer the current value into the corresponding parameter by setting *bWriteMaxPos* bzw. *bWriteMinPos* to TRUE ("teach-in" function).

19.1.36.2 Monitoring the dancer position

When the actual position value *nPosIn_a* reaches the current position setpoint *nSetPos_a*, the *bInSetPosition* output is set to TRUE.

- A tolerance zone can be set in [C01464/1](#) for reaching the setpoint. When the actual dancer value leaves this tolerance zone, the *bInSetPosition* output will only be reset to FALSE after the delay time set in [C01465/1](#) has elapsed (switch off delayed).
- In [C01463/1](#) and [C01463/2](#), reference values for the limit position monitoring can be set. If the actual dancer value reaches the set reference value towards the limit position, the corresponding (*bPosOverrange* output or *bNegOverrange*) output is set to TRUE (switch-off delayed) after the delay time set in [C01465/1](#) has elapsed.

19.1.36.3 Circumferential speed of the reel

If the storage of the dancer is set in [C01462/1](#), the additional speed of the material resulting from the motion of the dancer is provided at the *nVAdditive_a* output. When being added to the *nVLine_a* material speed, it results in the current circumferential speed of the reel via the *nVOut_a* output.

- The storage results from e.g. twice the distance between the two limit positions multiplied by the number of material wraps.
- The line speed is determined via *wVMax* and *nVLine_a*.
- In order to suppress the natural "noise" of the actual value signal with regard to the effect on the additional speed, the additional speed passes through a filter. The time constant of the filter can be set in [C01466/1](#).

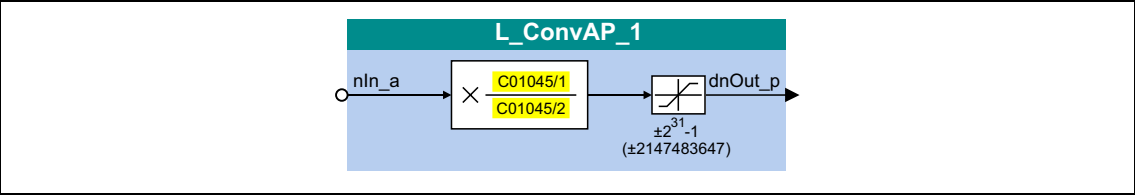
19.1.36.4 Additional torque for damping the dancer control

If the storage of the dancer is set in [C01462/1](#), an additional feedforward control torque *nMAdditive_a* can be generated for damping the dancer control.

- The feedforward control torque is derived from the negated additional speed (double dancer speed) evaluated with the damping factor set in [C01468/1](#).
- In order to suppress the natural "noise" of the actual value signal with regard to the effect on the additional torque, the additional speed passes through a dead band component in addition to the filter. The dead band area can be set in [C01467/1](#).

19.1.37 L_ConvAP_1

This FB converts an analog value into a position.



Inputs

Identifier	Data type	Information/possible settings
nln_a	INT	Input value • Scaling: 16384 ≡ 100 %


Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal • Internal limitation to ±2 ³¹ -1 (±2147483647)

Parameter

Parameter	Possible settings			Info
C01045/1	-32767		32767	Counter • Lenze setting: 1
C01045/2	-32767		32767	Denominator • Lenze setting: 1

Function

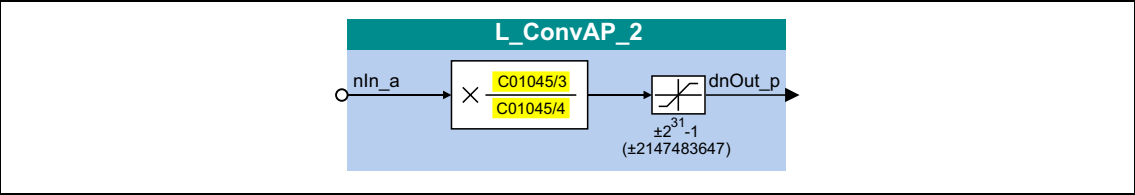
**Note!**

Conversion is remainder considered.

$$dnOut_p = nln_a \cdot \frac{C01045/1}{C01045/2}$$

19.1.38 L_ConvAP_2

This FB converts an analog value into a position.



Inputs

Identifier	Data type	Information/possible settings
nln_a	INT	Input value • Scaling: 16384 ≙ 100 %


Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal • Internal limitation to ±2 ³¹ -1 (±2147483647)

Parameter

Parameter	Possible settings			Info
C01045/3	-32767		32767	Counter • Lenze setting: 1
C01045/4	-32767		32767	Denominator • Lenze setting: 1

Function

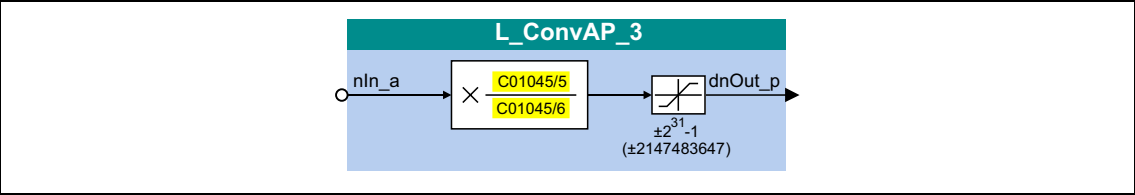
**Note!**

Conversion is remainder considered.

$$dnOut_p = nln_a \cdot \frac{C01045/3}{C01045/4}$$

19.1.39 L_ConvAP_3

This FB converts an analog value into a position.



Inputs

Identifier	Data type	Information/possible settings
nln_a	INT	Input value • Scaling: 16384 ≡ 100 %


Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal • Internal limitation to ±2 ³¹ -1 (±2147483647)

Parameter

Parameter	Possible settings			Info
C01045/5	-32767		32767	Counter • Lenze setting: 1
C01045/6	-32767		32767	Denominator • Lenze setting: 1

Function

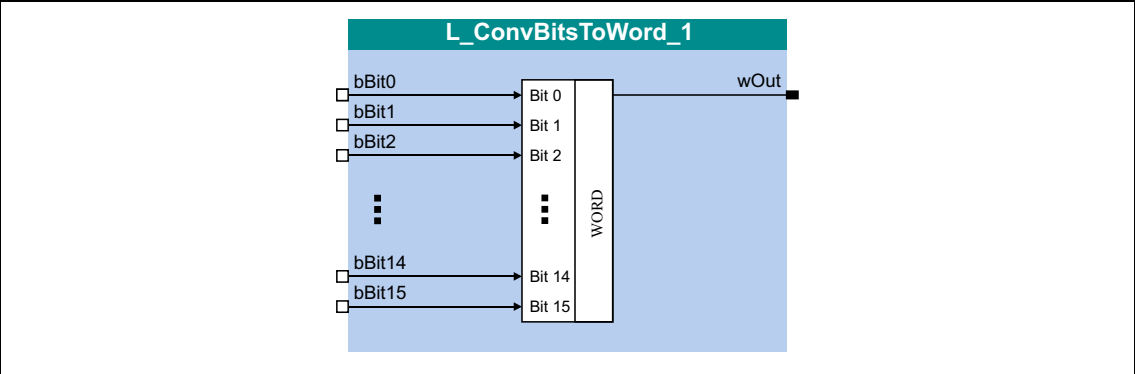
**Note!**

Conversion is remainder considered.

$$dnOut_p = nln_a \cdot \frac{C01045/5}{C01045/6}$$

19.1.40 L_ConvBitsToWorld_1

This FB converts 16 bit input values of the type "BOOL" into an output value of the type "WORD".



Inputs

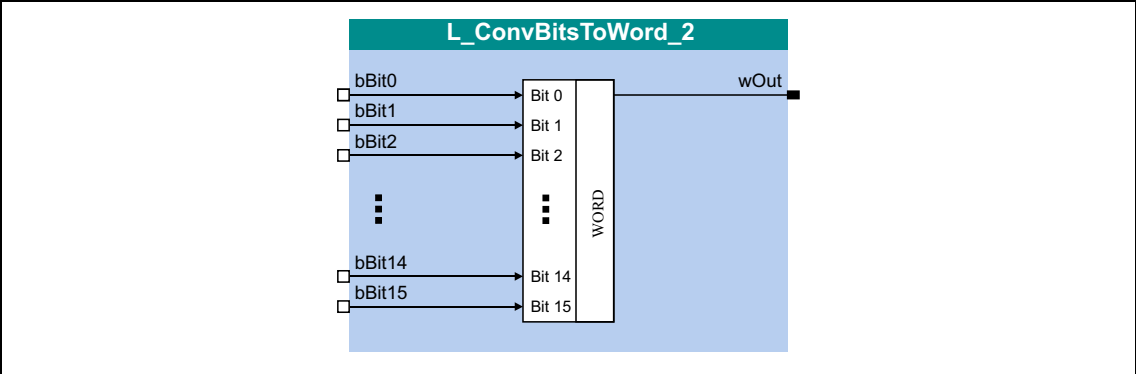
Identifier	Data type	Information/possible settings
bBit0 ... bBit15	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
wOut	WORD	Output signal

19.1.41 L_ConvBitsToWorld_2

This FB converts 16 bit input values of the type "BOOL" into an output value of the type "WORD".



Inputs

Identifier	Data type	Information/possible settings
bBit0 ... bBit15	BOOL	Input signal

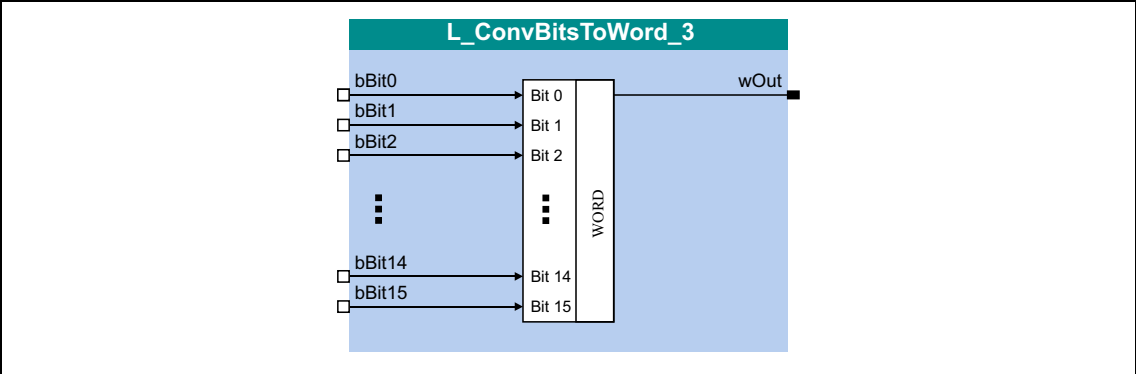
Outputs

Identifier	Data type	Value/meaning
wOut	WORD	Output signal

19.1.42

L_ConvBitsToWorld_3

This FB converts 16 bit input values of the type "BOOL" into an output value of the type "WORD".



Inputs

Identifier	Data type	Information/possible settings
bBit0 ... bBit15	BOOL	Input signal

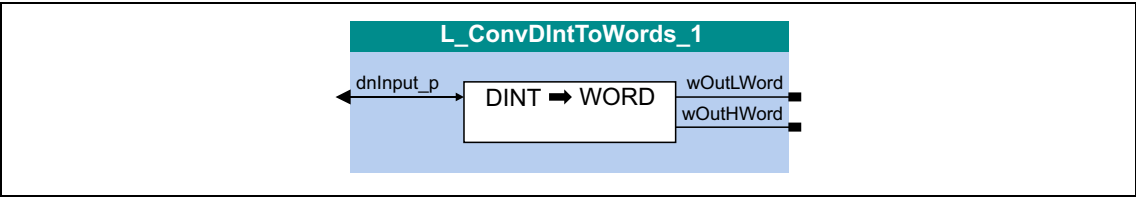
Outputs

Identifier	Data type	Value/meaning
wOut	WORD	Output signal

19.1.43

L_ConvDIntToWords_1

This FB converts an input value of the type "DINT" into two output values of the type "WORD".



Inputs

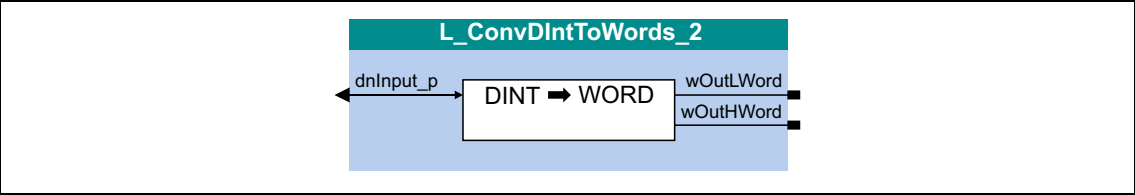
Identifier	Data type	Information/possible settings
dnInput_p	DINT	Input signal

Outputs

Identifier	Data type	Value/meaning
wOutLWord	WORD	Output signal Low Word
wOutHWord	WORD	Output signal High Word

19.1.44 L_ConvDIntToWords_2

This FB converts an input value of the type "DINT" into two output values of the type "WORD".



Inputs

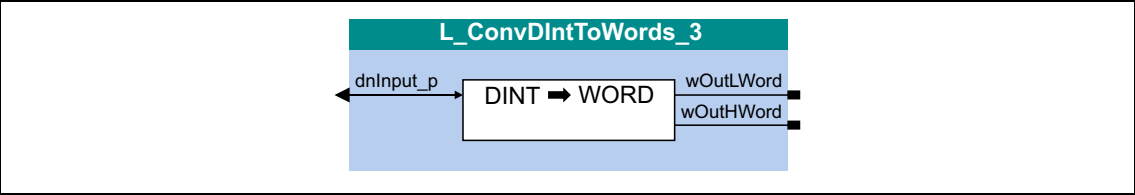
Identifier	Data type	Information/possible settings
dnInput_p	DINT	Input signal

Outputs

Identifier	Data type	Value/meaning
wOutLWord	WORD	Output signal Low Word
wOutHWord	WORD	Output signal High Word

19.1.45 L_ConvDIntToWords_3

This FB converts an input value of the type "DINT" into two output values of the type "WORD".



Inputs

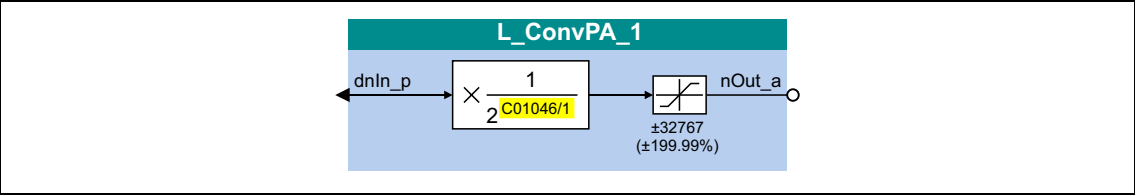
Identifier	Data type	Information/possible settings
dnInput_p	DINT	Input signal

Outputs

Identifier	Data type	Value/meaning
wOutLWord	WORD	Output signal Low Word
wOutHWord	WORD	Output signal High Word

19.1.46 L_ConvPA_1

This FB converts a position into an analog value.



Inputs

Identifier	Data type	Information/possible settings
dnIn_p	DINT	Input signal


Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal • Internal limitation to ±199 % (100 % ≡ 16384)

Parameter

Parameter	Possible settings	Info
C01046/1	0	31 Division factor • Lenze setting: 1

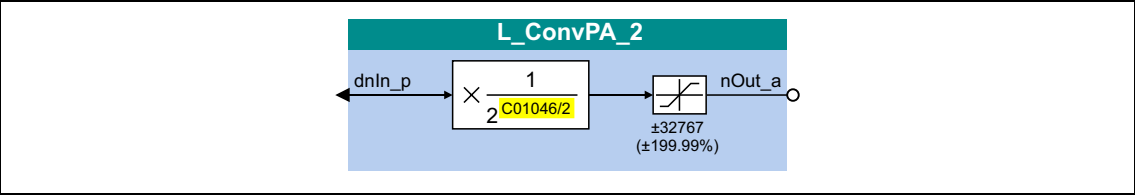
Function

**Note!**
Conversion is remainder considered.

$$nOut_a = dnIn_p \cdot \frac{1}{2^{C01046/1}}$$

19.1.47 L_ConvPA_2

This FB converts a position into an analog value.



Inputs

Identifier	Data type	Information/possible settings
dnIn_p	DINT	Input signal


Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal • Internal limitation to ±199 % (100 % ≡ 16384)

Parameter

Parameter	Possible settings	Info
C01046/2	0	31 Division factor • Lenze setting: 1

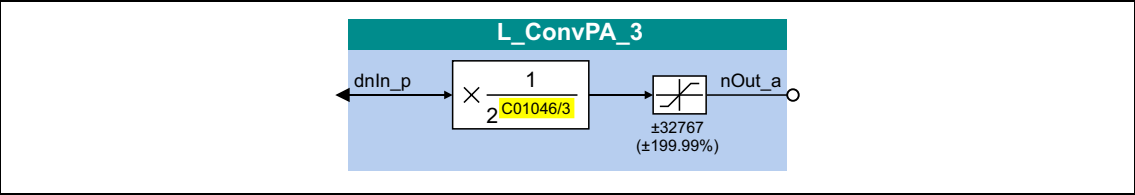
Function

**Note!**
Conversion is remainder considered.

$$nOut_a = dnIn_p \cdot \frac{1}{2^{C01046/2}}$$

19.1.48 L_ConvPA_3

This FB converts a position into an analog value.



Inputs

Identifier	Data type	Information/possible settings
dnIn_p	DINT	Input signal


Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal • Internal limitation to ±199 % (100 % ≡ 16384)

Parameter

Parameter	Possible settings	Info
C01046/3	0	31 Division factor • Lenze setting: 1

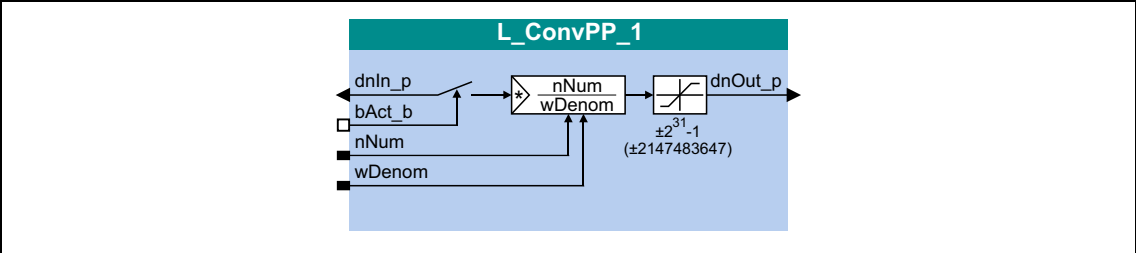
Function

**Note!**
Conversion is remainder considered.

$$nOut_a = dnIn_p \cdot \frac{1}{2^{C01046/3}}$$

19.1.49 L_ConvPP_1

This FB converts a position with dynamic fraction.



Inputs

Identifier	Data type	Information/possible settings
dnIn_p	DINT	Input signal
bAct_b	BOOL	Conversion mode
		FALSE $dnOut_p = \text{Remainder} \cdot \frac{nNum}{wDenom}$
		TRUE $dnOut_p = dnIn_p \cdot \frac{nNum}{wDenom}$
nNum	INT	Factor (numerator) • Internal limitation to -32767 ... -1 / 1 ... 32767
wDenom	WORD	Factor (denominator) • Internal limitation to 1 ... 32767

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal • Internal limitation to ±2 ³¹ -1 (±2147483647)

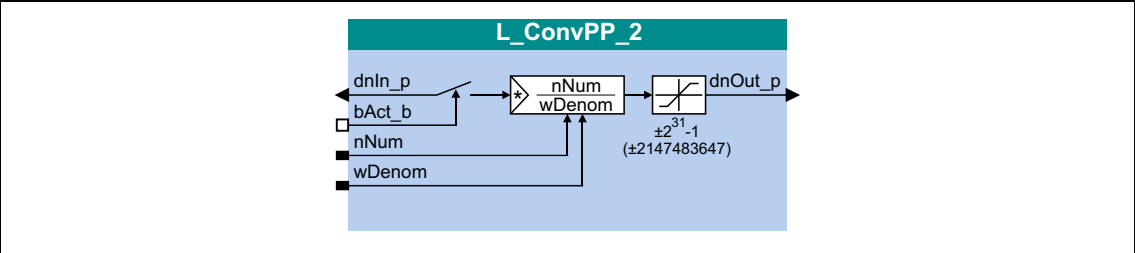


Note!

Conversion is remainder considered.

19.1.50 L_ConvPP_2

This FB converts a position with dynamic fraction.




Inputs

Identifier	Data type	Information/possible settings
dnIn_p	DINT	Input signal
bAct_b	BOOL	Conversion mode
		FALSE $dnOut_p = \text{Remainder} \cdot \frac{nNum}{wDenom}$
		TRUE $dnOut_p = dnIn_p \cdot \frac{nNum}{wDenom}$
nNum	INT	Factor (numerator) • Internal limitation to -32767 ... -1 / 1 ... 32767
wDenom	WORD	Factor (denominator) • Internal limitation to 1 ... 32767

Outputs

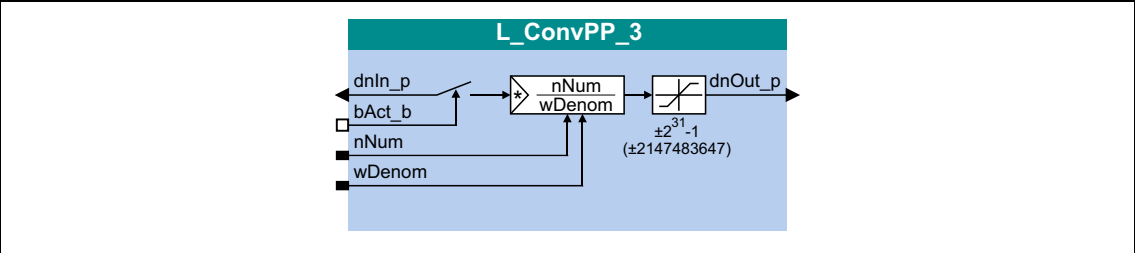
Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal • Internal limitation to $\pm 2^{31}-1$ (±2147483647)

**Note!**

Conversion is remainder considered.

19.1.51 L_ConvPP_3

This FB converts a position with dynamic fraction.



Inputs

Identifier	Data type	Information/possible settings
dnIn_p	DINT	Input signal
bAct_b	BOOL	Conversion mode
		FALSE $dnOut_p = \text{Remainder} \cdot \frac{nNum}{wDenom}$
		TRUE $dnOut_p = dnIn_p \cdot \frac{nNum}{wDenom}$
nNum	INT	Factor (numerator) • Internal limitation to -32767 ... -1 / 1 ... 32767
wDenom	WORD	Factor (denominator) • Internal limitation to 1 ... 32767

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal • Internal limitation to ±2 ³¹ -1 (±2147483647)



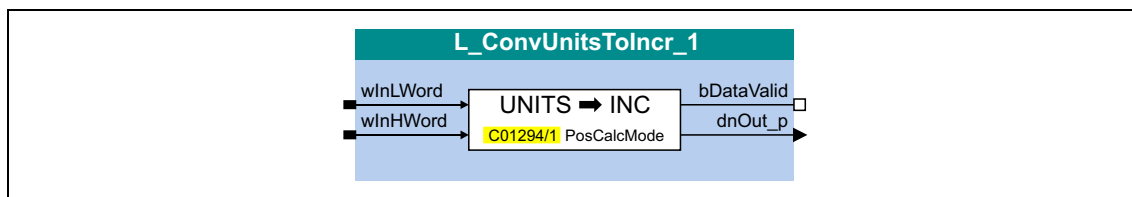
Note!

Conversion is remainder considered.

19.1.52 L_ConvUnitsToIncr_1

Taking into account the machine parameters, this FB converts a position value provided in the real unit of the machine into an internal 32-bit position value.

- The conversion mode has to be set in [C01294/1](#). In the Lenze setting, no conversion takes place due to compatibility reasons.
- Conversion and provision of the result to *dnOut_p* do not take place in real time! Hence, the *bDataValid* output signalises when the conversion has been completed and the *dnOut_p* output value is consistent for transfer to following processes.



Inputs

Identifier	Data type	Information/possible settings
wInLWord / wInHWord	WORD	Input signal Low Word / High Word

Outputs

Identifier	Data type	Value/meaning
bDataValid	BOOL	FALSE Conversion is active, <i>dnOut_p</i> is not valid.
		TRUE Conversion is completed, <i>dnOut_p</i> is valid (consistent).
dnOut_p	DINT	Result of conversion in [increments]

Parameter

Parameter	Possible settings	Info
C01294/1		Mode: Position calculation
	0 dnOut_p=HW+LW	No conversion (Lenze setting) Note! If a cycle length is set in C01201/1 , a calculation is made under the following conditions: <ul style="list-style-type: none"> • Position specification is higher than or equal to the cycle length. • Position specification is negative. For a correct positioning process, wait until <i>bDataValid</i> = TRUE.
	1 16 bits: LW=+/-32767	<i>wInLWord</i> = ±32767 [Unit]
	2 16 bits: HW=+/-; LW=0..65535	<i>wInLWord</i> = 0 ... 65535 [Unit] <i>wInHWord</i> = sign (0 = positive; ≠0 = negative)
	3 32 bits: HW_LW=+/-214748_3647	<i>wInHWord</i> and <i>wInLWord</i> = ±214748.3647 [Unit]

Conversion formula for modes 1 ... 3

$$\text{dnOut_p [incr.]} = \text{Input value [Unit]} \cdot \frac{\text{C01202/1}}{\text{C01202/2}} \cdot \frac{\text{C01203/2}}{\text{C01203/1}} \cdot \frac{65536[\text{Incr./rev.}]}{\text{C01204}}$$

[C01202/1](#): Gearbox factor (numerator)

[C01202/2](#): Gearbox factor (denominator)

[C01203/1](#): Encoder gearbox factor (numerator)

[C01203/2](#): Encoder gearbox factor (denominator)

[C01204](#): Feed constant

[19-18] Conversion formula for [Unit] → [increments]

Example

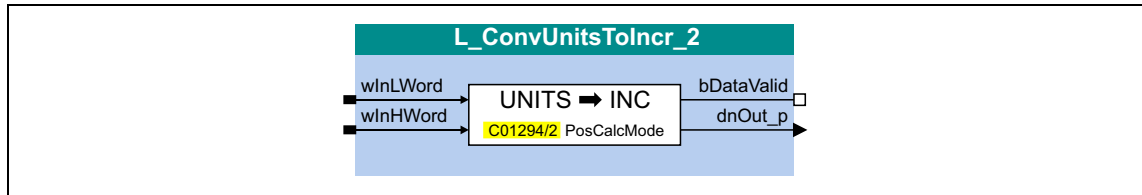
- All gearbox factors = 1
- Feed constant = 360°/revolution

Conversion mode (C01294)		wInHWord	wInLWord	Input value [Unit]	dnOut_p [Increments]
0	dnOut_p=HW+LW (no conversion)	32-bit input value*		-32000	-32000
		65535	33536		
1	16 bits: LW=+/-32767	No meaning	16-bit input value*	-32000	-5825422
		65535	33536		
2	16 bits: HW=+/-; LW=0..65535	Sign	16-bit input value	-33536	-6105042
		65535 ≡ negative	33536		
3	32 bits: HW_LW=+/-214748_3647	32-bit input value**		-3.2000	-582
		65535	33536		
* Two's complement ** Two's complement with four decimal positions					

19.1.53 L_ConvUnitsToIncr_2

Taking into account the machine parameters, this FB converts a position value provided in the real unit of the machine into an internal 32-bit position value.

- The conversion mode has to be set in [C01294/2](#). In the Lenze setting, no conversion takes place due to compatibility reasons.
- Conversion and provision of the result to *dnOut_p* do not take place in real time! Hence, the *bDataValid* output signalises when the conversion has been completed and the *dnOut_p* output value is consistent for transfer to following processes.



Inputs

Identifier	Data type	Information/possible settings
wInLWord / wInHWord	WORD	Input signal Low Word / High Word

Outputs

Identifier	Data type	Value/meaning
bDataValid	BOOL	FALSE Conversion is active, <i>dnOut_p</i> is not valid.
		TRUE Conversion is completed, <i>dnOut_p</i> is valid (consistent).
dnOut_p	DINT	Result of conversion in [increments]

Parameter

Parameter	Possible settings	Info
C01294/2		Mode: Position calculation
	0 dnOut_p=HW+LW	No conversion (Lenze setting) Note! If a cycle length is set in C01201/1 , a calculation is made under the following conditions: <ul style="list-style-type: none"> • Position specification is higher than or equal to the cycle length. • Position specification is negative. For a correct positioning process, wait until <i>bDataValid</i> = TRUE.
	1 16 bits: LW=+/-32767	<i>wInLWord</i> = ±32767 [Unit]
	2 16 bits: HW=+/-; LW=0..65535	<i>wInLWord</i> = 0 ... 65535 [Unit] <i>wInHWord</i> = sign (0 = positive; ≠0 = negative)
	3 32 bits: HW_LW=+/-214748_3647	<i>wInHWord</i> and <i>wInLWord</i> = ±214748.3647 [Unit]

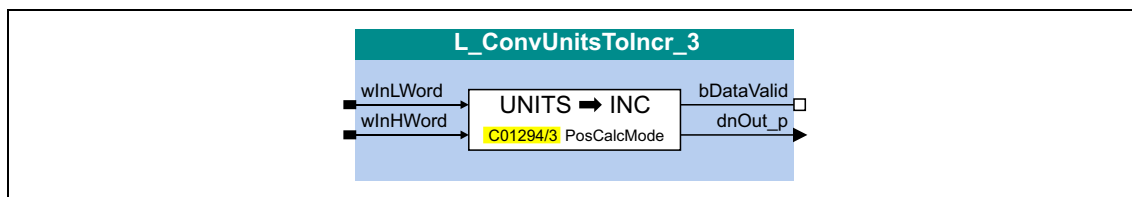


For a detailed functional description see [L_ConvUnitsToIncr 1](#).

19.1.54 L_ConvUnitsToIncr_3

Taking into account the machine parameters, this FB converts a position value provided in the real unit of the machine into an internal 32-bit position value.

- The conversion mode has to be set in [C01294/3](#). In the Lenze setting, no conversion takes place due to compatibility reasons.
- Conversion and provision of the result to *dnOut_p* do not take place in real time! Hence, the *bDataValid* output signalises when the conversion has been completed and the *dnOut_p* output value is consistent for transfer to following processes.



Inputs

Identifier	Data type	Information/possible settings
wInLWord / wInHWord	WORD	Input signal Low Word / High Word

Outputs

Identifier	Data type	Value/meaning
bDataValid	BOOL	FALSE Conversion is active, <i>dnOut_p</i> is not valid.
		TRUE Conversion is completed, <i>dnOut_p</i> is valid (consistent).
dnOut_p	DINT	Result of conversion in [increments]

Parameter

Parameter	Possible settings	Info
C01294/3		Mode: Position calculation
	0 dnOut_p=HW+LW	No conversion (Lenze setting) Note! If a cycle length is set in C01201/1 , a calculation is made under the following conditions: <ul style="list-style-type: none"> • Position specification is higher than or equal to the cycle length. • Position specification is negative. For a correct positioning process, wait until <i>bDataValid</i> = TRUE.
	1 16 bits: LW=+/-32767	<i>wInLWord</i> = ±32767 [Unit]
	2 16 bits: HW=+/-; LW=0..65535	<i>wInLWord</i> = 0 ... 65535 [Unit] <i>wInHWord</i> = sign (0 = positive; ≠0 = negative)
	3 32 bits: HW_LW=+/-214748_3647	<i>wInHWord</i> and <i>wInLWord</i> = ±214748.3647 [Unit]

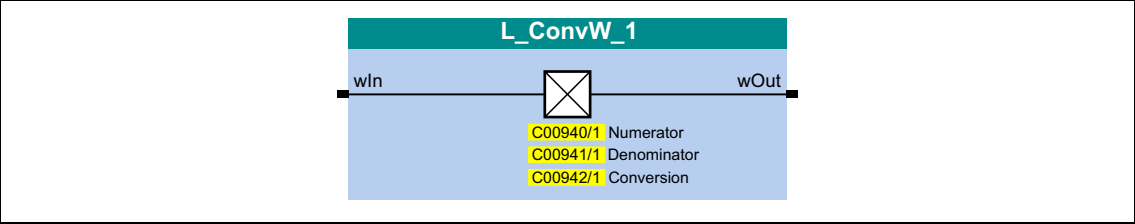


For a detailed functional description see [L_ConvUnitsToIncr 1](#).

19.1.55 L_ConvW_1

This FB serves to convert analog signal forms. The following conversions per parameter can be selected:

- [%] → [incr/ms]
- [incr/ms] → [%]
- Conversion via parameterisable factors
- Input signal is passed through without conversion



Inputs

Identifier	Data type	Information/possible settings
wIn	WORD	Input signal

Outputs

Identifier	Data type	Value/meaning
wOut	WORD	Output signal

Parameter

Parameter	Possible settings			Info
C00940/1	-32767		32767	Numerator • Lenze setting: 1
C00941/1	-32767		32767	Denominator • Lenze setting: 1
C00942/1				Selection of the conversion
	0	wOut = wIn (no conversion)		
	1	[%] → [incr/ms]		
	2	[incr/ms] → [%]		
	3	wOut = wIn * C00940 / C00941		

Conversion formulae

**Note!**

Division is remainder considered.

$$w_{\text{Out}} [\text{incr/ms}] = \frac{w_{\text{In}} [\%] \cdot C00011 [\text{rpm}] \cdot 65536 [\text{incr/rev.}]}{100 \% \cdot 60 [\text{s/min}] \cdot 1000 [\text{ms/s}]}$$

[19-19] Conversion formula for selection 1: [%] → [incr/ms]

$$w_{\text{Out}} [\%] = \frac{w_{\text{In}} [\text{incr/ms}] \cdot 100 \% \cdot 60 [\text{s/min}] \cdot 1000 [\text{ms/s}]}{C00011 [\text{rpm}] \cdot 65536 [\text{incr/rev.}]}$$

[19-20] Conversion formula for selection 2: [incr/ms] → [%]

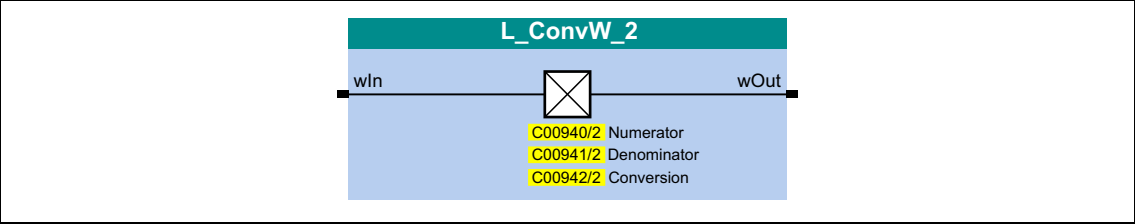
$$w_{\text{Out}} = w_{\text{In}} \cdot \frac{C00940}{C00941}$$

[19-21] Conversion formula for selection 3: Parameterisable factors

19.1.56 L_ConvW_2

This FB serves to convert analog signal forms. The following conversions per parameter can be selected:

- [%] → [incr/ms]
- [incr/ms] → [%]
- Conversion via parameterisable factors
- Input signal is passed through without conversion



Inputs

Identifier	Data type	Information/possible settings
wIn	WORD	Input signal

Outputs

Identifier	Data type	Value/meaning
wOut	WORD	Output signal

Parameter

Parameter	Possible settings			Info
C00940/2	-32767		32767	Numerator • Lenze setting: 1
C00941/2	-32767		32767	Denominator • Lenze setting: 1
C00942/2				Selection of the conversion
	0	wOut = wIn (no conversion)		
	1	[%] → [incr/ms]		
	2	[incr/ms] → [%]		
	3	wOut = wIn * C00940 / C00941		

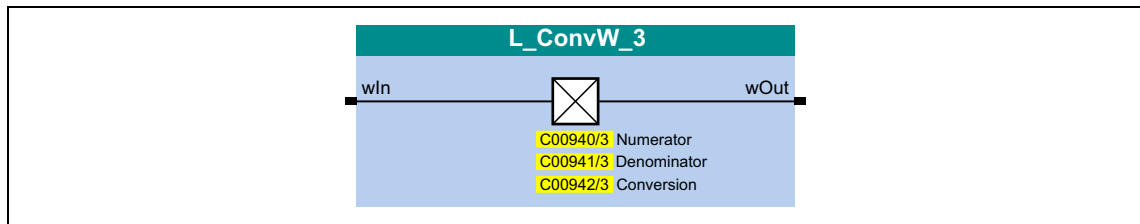


For conversion formulae see [L_ConvW_1](#).

19.1.57 L_ConvW_3

This FB serves to convert analog signal forms. The following conversions per parameter can be selected:

- [%] → [incr/ms]
- [incr/ms] → [%]
- Conversion via parameterisable factors
- Input signal is passed through without conversion



Inputs

Identifier	Data type	Information/possible settings
wIn	WORD	Input signal

Outputs

Identifier	Data type	Value/meaning
wOut	WORD	Output signal

Parameter

Parameter	Possible settings			Info
C00940/3	-32767		32767	Numerator • Lenze setting: 1
C00941/3	-32767		32767	Denominator • Lenze setting: 1
C00942/3				Selection of the conversion
	0	$wOut = wIn$ (no conversion)		
	1	[%] → [incr/ms]		
	2	[incr/ms] → [%]		
	3	$wOut = wIn * \frac{C00940}{C00941}$		

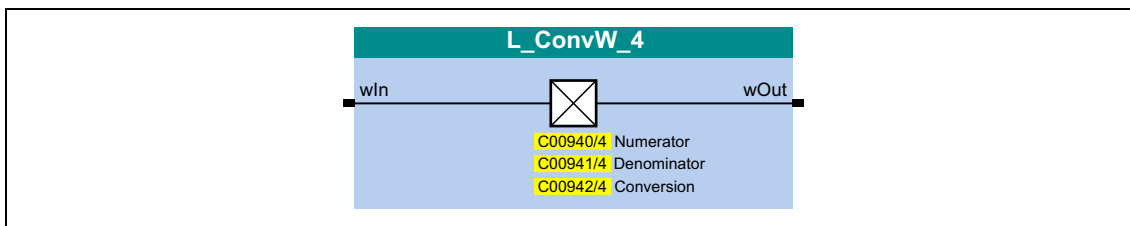


For conversion formulae see [L_ConvW_1](#).

19.1.58 L_ConvW_4

This FB serves to convert analog signal forms. The following conversions per parameter can be selected:

- [%] → [incr/ms]
- [incr/ms] → [%]
- Conversion via parameterisable factors
- Input signal is passed through without conversion

**Inputs**

Identifier	Data type	Information/possible settings
wIn	WORD	Input signal

Outputs

Identifier	Data type	Value/meaning
wOut	WORD	Output signal

Parameter

Parameter	Possible settings			Info
C00940/4	-32767		32767	Numerator <ul style="list-style-type: none">• Lenze setting: 1
C00941/4	-32767		32767	Denominator <ul style="list-style-type: none">• Lenze setting: 1
C00942/4				Selection of the conversion
	0	wOut = wIn (no conversion)		
	1	[%] → [incr/ms]		
	2	[incr/ms] → [%]		
	3	wOut = wIn * C00940 / C00941		

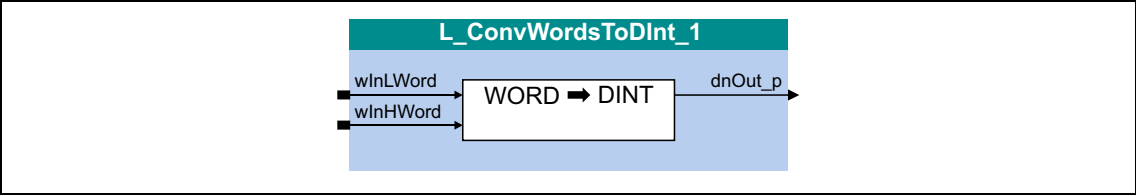


For conversion formulae see [L_ConvW_1](#).

19.1.59

L_ConvWordsToDInt_1

This FB converts two input values of the type "WORD" into one output value of the type "DINT".



Inputs

Identifier	Data type	Information/possible settings
wInLWord	WORD	Input signal Low Word
wInHWord	WORD	Input signal High Word

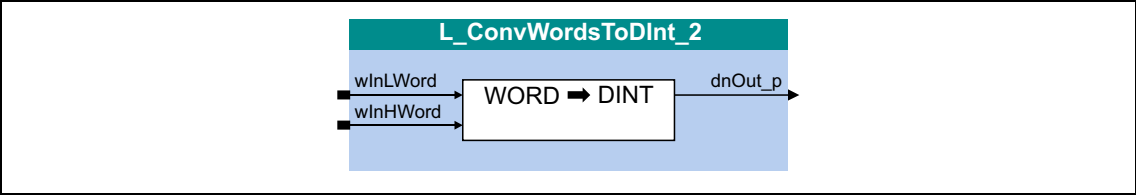
Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal

19.1.60

L_ConvWordsToDInt_2

This FB converts two input values of the type "WORD" into one output value of the type "DINT".



Inputs

Identifier	Data type	Information/possible settings
wInLWord	WORD	Input signal Low Word
wInHWord	WORD	Input signal High Word

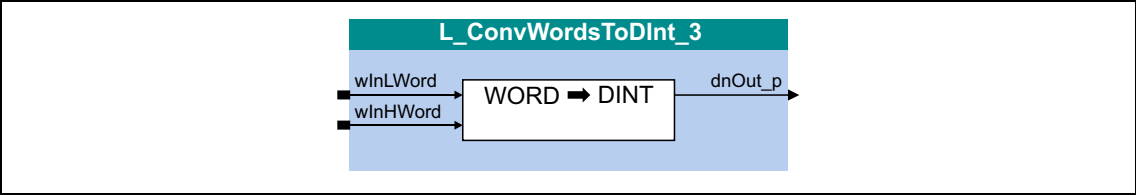
Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal

19.1.61

L_ConvWordsToDInt_3

This FB converts two input values of the type "WORD" into one output value of the type "DINT".



Inputs

Identifier	Data type	Information/possible settings
wInLWord	WORD	Input signal Low Word
wInHWord	WORD	Input signal High Word

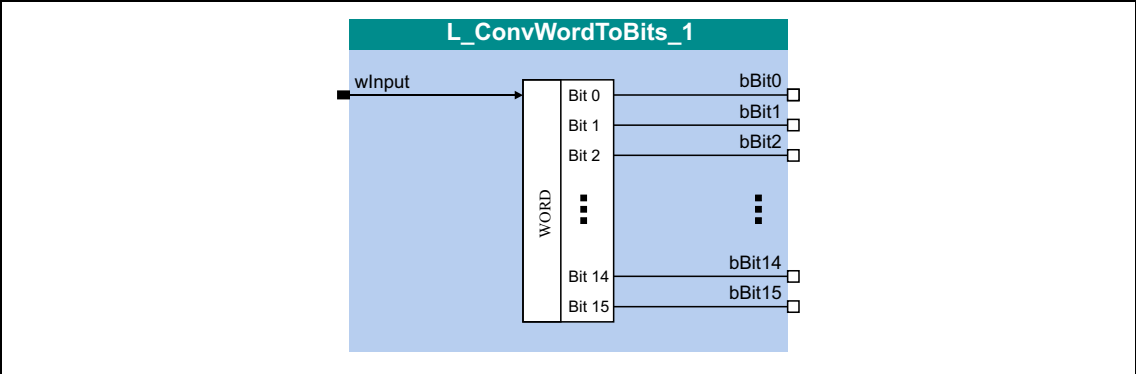
Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal

19.1.62

L_ConvWordToBits_1

This FB converts an input value of "WORD" type into 16 individual binary signals.



Inputs

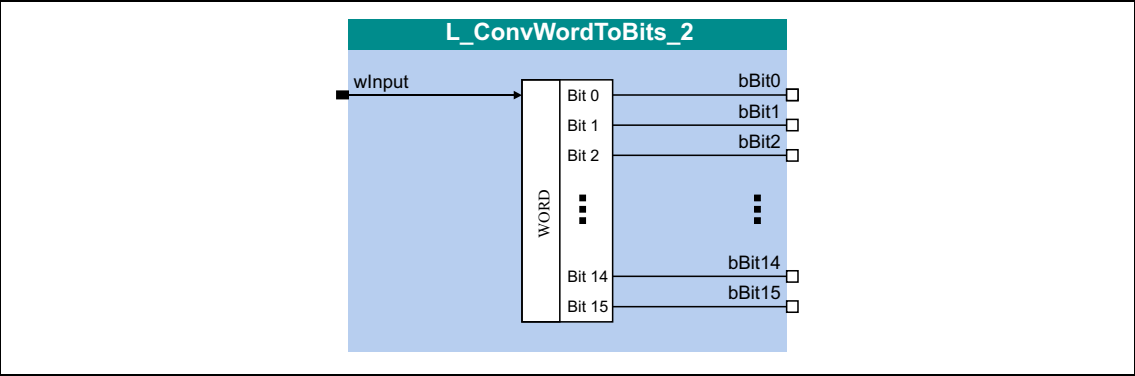
Identifier	Data type	Information/possible settings
wInput	WORD	Input signal

Outputs

Identifier	Data type	Value/meaning
bBit0 ... bBit15	BOOL	Output signal

19.1.63 L_ConvWordToBits_2

This FB converts an input value of "WORD" type into 16 individual binary signals.



Inputs

Identifier	Data type	Information/possible settings
wInput	WORD	Input signal

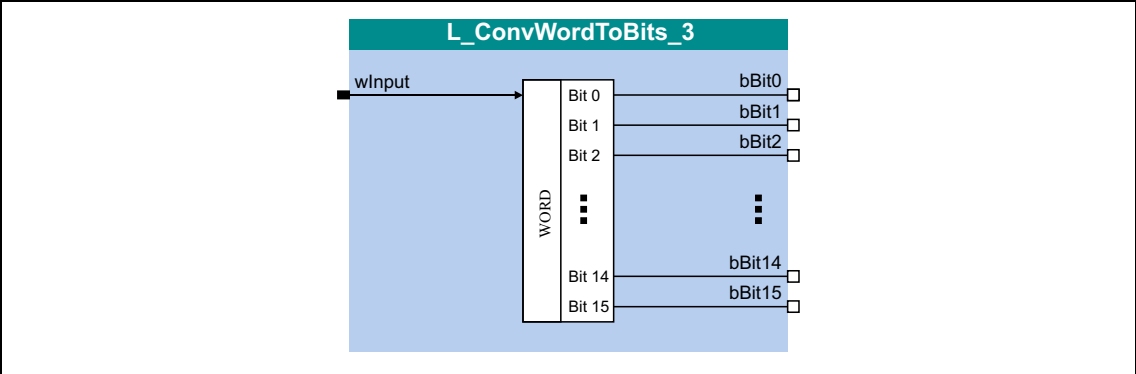
Outputs

Identifier	Data type	Value/meaning
bBit0 ... bBit15	BOOL	Output signal

19.1.64

L_ConvWordToBits_3

This FB converts an input value of "WORD" type into 16 individual binary signals.



Inputs

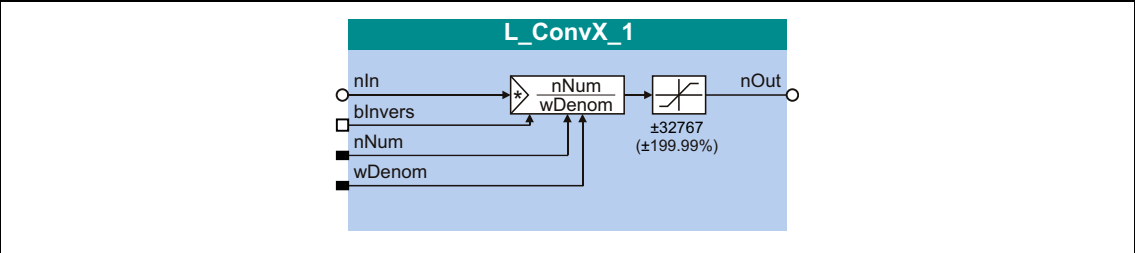
Identifier	Data type	Information/possible settings
wInput	WORD	Input signal

Outputs

Identifier	Data type	Value/meaning
bBit0 ... bBit15	BOOL	Output signal

19.1.65 L_ConvX_1

This FB scales an analog value.



Inputs

Identifier	Data type	Information/possible settings
nIn	INT	Input signal
blInvers	BOOL	Invert sign of the output signal
		FALSE $nOut = nIn \cdot \frac{nNum}{wDenom}$
		TRUE $nOut = nIn \cdot \frac{nNum}{wDenom} \cdot (-1)$
nNum	INT	Factor (numerator) • Internal limitation to -32767 ... -1 / 1 ... 32767
wDenom	WORD	Factor (denominator) • Internal limitation to 1 ... 32767

Outputs

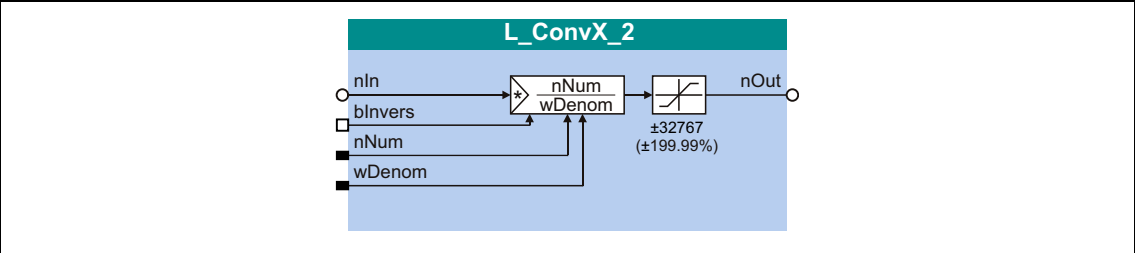
Identifier	Data type	Value/meaning
nOut	INT	Output signal • Internal limitation to ±199 % (100 % ≡ 16384)

Note!

Conversion is remainder considered.

19.1.66 L_ConvX_2

This FB scales an analog value.



Inputs

Identifier	Data type	Information/possible settings
nIn	INT	Input signal
blInvers	BOOL	Invert sign of the output signal
		FALSE $nOut = nIn \cdot \frac{nNum}{wDenom}$
		TRUE $nOut = nIn \cdot \frac{nNum}{wDenom} \cdot (-1)$
nNum	INT	Factor (numerator) • Internal limitation to -32767 ... -1 / 1 ... 32767
wDenom	WORD	Factor (denominator) • Internal limitation to 1 ... 32767

Outputs

Identifier	Data type	Value/meaning
nOut	INT	Output signal • Internal limitation to ±199 % (100 % ≡ 16384)

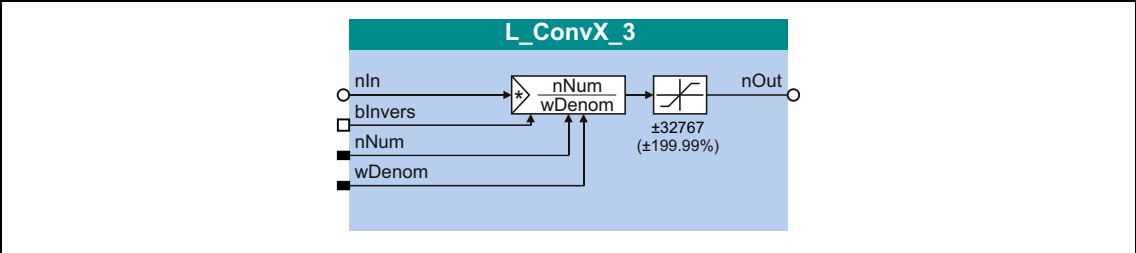


Note!

Conversion is remainder considered.

19.1.67 L_ConvX_3

This FB scales an analog value.



Inputs

Identifier	Data type	Information/possible settings
nIn	INT	Input signal
blInvers	BOOL	Invert sign of the output signal
		FALSE $nOut = nIn \cdot \frac{nNum}{wDenom}$
		TRUE $nOut = nIn \cdot \frac{nNum}{wDenom} \cdot (-1)$
nNum	INT	Factor (numerator) • Internal limitation to -32767 ... -1 / 1 ... 32767
wDenom	WORD	Factor (denominator) • Internal limitation to 1 ... 32767

Outputs

Identifier	Data type	Value/meaning
nOut	INT	Output signal • Internal limitation to ±199 % (100 % ≡ 16384)

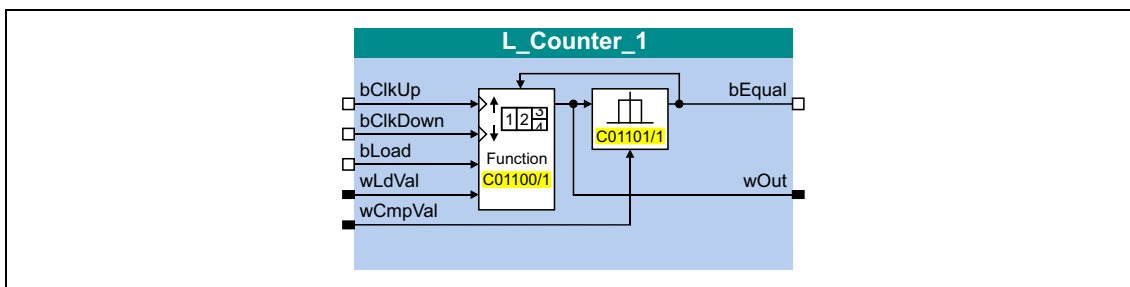


Note!

Conversion is remainder considered.

19.1.68 L_Counter_1

This FB is a digital upcounter and downcounter with a parameterisable comparison operation.



Inputs

Identifier	Data type	Information/possible settings
bClkUp	BOOL	Clock input <ul style="list-style-type: none"> With each edge, the module counts up by "1". Only FALSE-TRUE edges are evaluated. Note: The static state "1" is not permissible at this input.
bClkDown	BOOL	Clock input <ul style="list-style-type: none"> With each edge, the module counts down by "1". Only FALSE-TRUE edges are evaluated. Note: The static state "1" is not permissible at this input.
bLoad	BOOL	Load input <ul style="list-style-type: none"> The input has the highest priority. <div>TRUE Accept starting value <i>wLdVal</i>.</div>
wLdVal	WORD	Starting value <ul style="list-style-type: none"> Assigned value is internally interpreted as "INT" data type (-32767 ... +32767), i.e. the most significant bit determines the sign.
wCmpVal	WORD	Comparison value <ul style="list-style-type: none"> Assigned value is internally interpreted as "INT" data type (-32767 ... +32767), i.e. the most significant bit determines the sign.

Outputs

Identifier	Data type	Value/meaning
bEqual	BOOL	Status signal "Comparison statement is true" <ul style="list-style-type: none"> The TRUE output is active in the Lenze setting if the current counter content is greater than or equal to the comparison value <i>wCmpVal</i>. <div>TRUE The statement of the comparison mode selected in C01101/1 is true.</div>
wOut	WORD	Counter content <ul style="list-style-type: none"> Internal limitation to ± 32767 The most significant bit determines the sign!

Parameter

Parameter	Possible settings	Info
C01100/1		Function selection • Lenze setting: Normal counting
	0 Normal counting	
	1 Auto reset	
	2 Manual reset	
C01101/1		Selection of comparison operation • Lenze setting: Counter content \geq comparison value
	0 Counter content \geq comparison value	
	1 Counter content \leq comparison value	
	2 Counter content = comparison value	

General function

- Every FALSE/TRUE edge at the *bClkUp* input causes the block to count upwards by "1".
- Every FALSE/TRUE edge at the *bClkDown* input causes the block to count downwards by "1".

Function "Normal counting"

If the statement of the comparison mode selected in [C01101/1](#) is true, the *bCompare* output is set to TRUE.

Function "Auto reset"

If the statement of the comparison mode selected in [C01101/1](#) is true, the *bCompare* output is set to TRUE for 1 ms and the counter is reset to the *wLdVal* starting value.

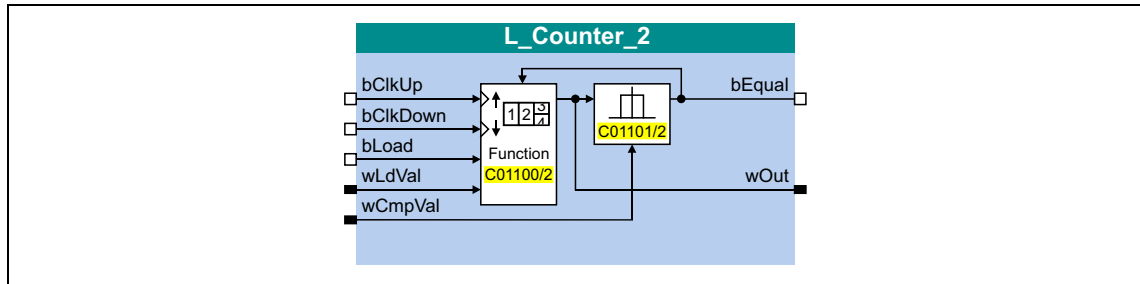
Function "Manual reset"

If the statement of the comparison mode selected in [C01101/1](#) is true, the *bCompare* output is set to TRUE and the counter stops.

- Edges at *bClkUp* and *bClkDown* are ignored.
- The counter must be reset via the *bLoad* input.

19.1.69 L_Counter_2

This FB is a digital upcounter and downcounter with a parameterisable comparison operation.



Inputs

Identifier	Data type	Information/possible settings
bClkUp	BOOL	Clock input <ul style="list-style-type: none"> With each edge, the module counts up by "1". Only FALSE-TRUE edges are evaluated. Note: The static state "1" is not permissible at this input.
bClkDown	BOOL	Clock input <ul style="list-style-type: none"> With each edge, the module counts down by "1". Only FALSE-TRUE edges are evaluated. Note: The static state "1" is not permissible at this input.
bLoad	BOOL	Load input <ul style="list-style-type: none"> The input has the highest priority.
wLdVal	WORD	Starting value <ul style="list-style-type: none"> Assigned value is internally interpreted as "INT" data type (-32767 ... +32767), i.e. the most significant bit determines the sign.
wCmpVal	WORD	Comparison value <ul style="list-style-type: none"> Assigned value is internally interpreted as "INT" data type (-32767 ... +32767), i.e. the most significant bit determines the sign.

Outputs

Identifier	Data type	Value/meaning
bEqual	BOOL	Status signal "Comparison statement is true" <ul style="list-style-type: none"> The TRUE output is active in the Lenze setting if the current counter content is greater than or equal to the comparison value <i>wCmpVal</i>.
		TRUE The statement of the comparison mode selected in C01101/2 is true.
wOut	WORD	Counter content <ul style="list-style-type: none"> Internal limitation to ± 32767 The most significant bit determines the sign!

Parameter

Parameter	Possible settings	Info
C01100/2		Function selection • Lenze setting: Normal counting
	0 Normal counting	
	1 Auto reset	
	2 Manual reset	
C01101/2		Selection of comparison operation • Lenze setting: Counter content \geq comparison value
	0 Counter content \geq comparison value	
	1 Counter content \leq comparison value	
	2 Counter content = comparison value	

General function

- Every FALSE/TRUE edge at the *bClkUp* input causes the block to count upwards by "1".
- Every FALSE/TRUE edge at the *bClkDown* input causes the block to count downwards by "1".

Function "Normal counting"

If the statement of the comparison mode selected in [C01101/2](#) is true, the *bCompare* output is set to TRUE.

Function "Auto reset"

If the statement of the comparison mode selected in [C01101/2](#) is true, the *bCompare* output is set to TRUE for 1 ms and the counter is reset to the *wLdVal* starting value.

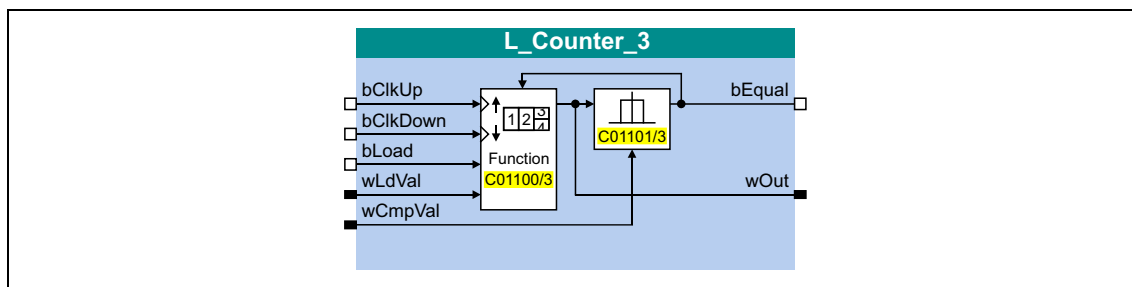
Function "Manual reset"

If the statement of the comparison mode selected in [C01101/2](#) is true, the *bCompare* output is set to TRUE and the counter stops.

- Edges at *bClkUp* and *bClkDown* are ignored.
- The counter must be reset via the *bLoad* input.

19.1.70 L_Counter_3

This FB is a digital upcounter and downcounter with a parameterisable comparison operation.



Inputs

Identifier	Data type	Information/possible settings
bClkUp	BOOL	Clock input <ul style="list-style-type: none"> With each edge, the module counts up by "1". Only FALSE-TRUE edges are evaluated. Note: The static state "1" is not permissible at this input.
bClkDown	BOOL	Clock input <ul style="list-style-type: none"> With each edge, the module counts down by "1". Only FALSE-TRUE edges are evaluated. Note: The static state "1" is not permissible at this input.
bLoad	BOOL	Load input <ul style="list-style-type: none"> The input has the highest priority.
wLdVal	WORD	Starting value <ul style="list-style-type: none"> Assigned value is internally interpreted as "INT" data type (-32767 ... +32767), i.e. the most significant bit determines the sign.
wCmpVal	WORD	Comparison value <ul style="list-style-type: none"> Assigned value is internally interpreted as "INT" data type (-32767 ... +32767), i.e. the most significant bit determines the sign.

Outputs

Identifier	Data type	Value/meaning
bEqual	BOOL	Status signal "Comparison statement is true" <ul style="list-style-type: none"> The TRUE output is active in the Lenze setting if the current counter content is greater than or equal to the comparison value <i>wCmpVal</i>.
		TRUE The statement of the comparison mode selected in C01101/3 is true.
wOut	WORD	Counter content <ul style="list-style-type: none"> Internal limitation to ± 32767 The most significant bit determines the sign!

Parameter

Parameter	Possible settings	Info
C01100/3		Function selection • Lenze setting: Normal counting
	0 Normal counting	
	1 Auto reset	
	2 Manual reset	
C01101/3		Selection of comparison operation • Lenze setting: Counter content \geq comparison value
	0 Counter content \geq comparison value	
	1 Counter content \leq comparison value	
	2 Counter content = comparison value	

General function

- Every FALSE/TRUE edge at the *bClkUp* input causes the block to count upwards by "1".
- Every FALSE/TRUE edge at the *bClkDown* input causes the block to count downwards by "1".

Function "Normal counting"

If the statement of the comparison mode selected in [C01101/3](#) is true, the *bCompare* output is set to TRUE.

Function "Auto reset"

If the statement of the comparison mode selected in [C01101/3](#) is true, the *bCompare* output is set to TRUE for 1 ms and the counter is reset to the *wLdVal* starting value.

Function "Manual reset"

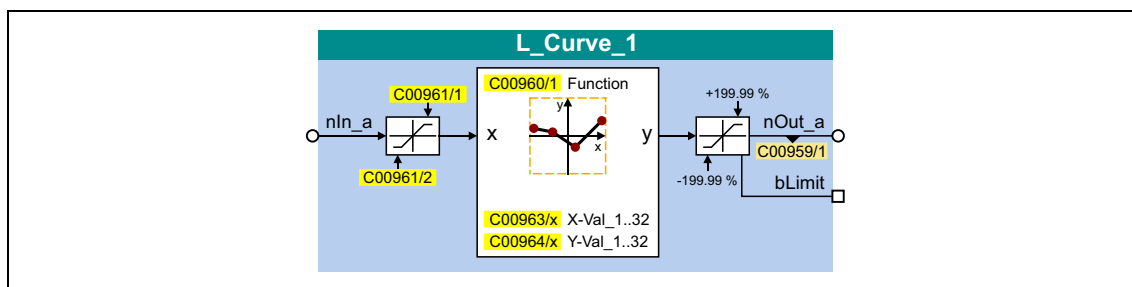
If the statement of the comparison mode selected in [C01101/3](#) is true, the *bCompare* output is set to TRUE and the counter stops.

- Edges at *bClkUp* and *bClkDown* are ignored.
- The counter must be reset via the *bLoad* input.

19.1.71 L_Curve_1

This FB can optionally display a characteristic function or a curve function $y=f(x)$, the X axis being the input signal and the Y axis being the output signal.

- A limitation of the input value can be set in [C00961/1](#) (upper limit) and [C00961/2](#) (lower limit).
- The output value is internally limited to $\pm 199.99\%$. If a limitation of the output value is active, *bLimit* is set to TRUE.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input value (x) <ul style="list-style-type: none"> • $\pm 16384 \equiv \pm 100\%$ • A limitation of the input value can be set in C00961/1 (upper limit) and C00961/2 (lower limit).

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output value (y) <ul style="list-style-type: none"> • $\pm 16384 \equiv \pm 100\%$ • Internal limitation to ± 32767 ($\pm 199.99\%$)
bLimit	BOOL	"Limitation active" status signal
		TRUE The output value is limited to $\pm 199.99\%$.

Parameter

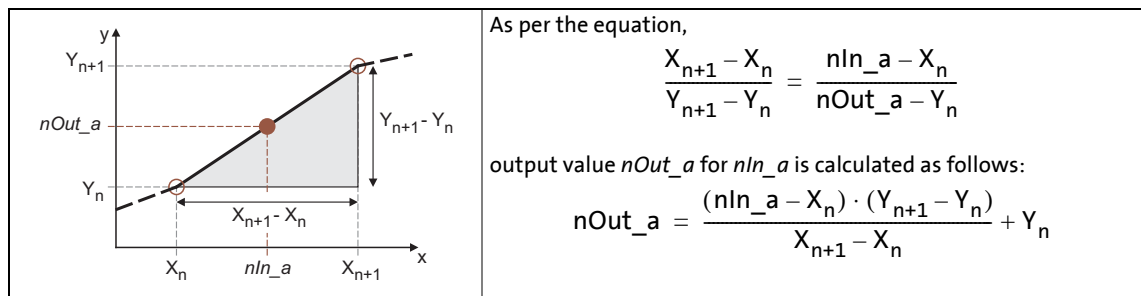
Parameter	Possible settings			Info
C00959/1 From version 02.00.00	-199.99	%	199.99	Output value <ul style="list-style-type: none"> • Read only
C00960/1				Function selection
	0	Out = 0		FB deactivated (Lenze setting)
	1	Out = In		
	2	Out = f(In)		In preparation!
	3	Out = f(table)		► Function 3: nOut_a = f(table)
C00961/1	-199.99	%	199.99	Upper limit for input value <ul style="list-style-type: none"> • Lenze setting: 199.99 %
C00961/2	-199.99	%	199.99	Lower limit for input value <ul style="list-style-type: none"> • Lenze setting: -199.99 %

Parameter	Possible settings			Info
C00963/1...32	-32767		32767	X values for characteristic function <ul style="list-style-type: none"> • Subcodes 1 ... 32 correspond to interpolation point values X1 ... X32. • $\pm 16384 \equiv \pm 100\%$ • Lenze setting: 0 ► Function 3: nOut_a = f(table)
C00964/1...32	-32767		32767	Y values for characteristic function <ul style="list-style-type: none"> • Subcodes 1 ... 32 correspond to interpolation point values Y1 ... Y32. • $\pm 16384 \equiv \pm 100\%$ • Lenze setting: 0 ► Function 3: nOut_a = f(table)

19.1.71.1 Function 3: nOut_a = f(table)

If function 3 has been selected in [C00960](#), the output value is calculated according to a characteristic.

- The characteristic may comprise up to 32 interpolation points which are defined by parameters.
- If the *nIn_a* input value is equal to one of the X interpolation points, the corresponding Y interpolation point will be output to *nOut_a*.
- If the *nIn_a* input value lies between two X interpolation points, the *nOut_a* output value will be interpolated linearly:



[19-22] Linear interpolation between two interpolation points

Selecting the characteristic

The max. 32 interpolation points of the characteristic are selected via the subcodes of [C00963](#) and [C00964](#).

- The values are to be set as raw values ($\pm 16384 \equiv \pm 100\%$).
- The same subcodes of [C00963](#) and [C00964](#) correspond to one pair of variates/interpolation point (x_n, y_n).

	1	2	...	32
X	C00963/1	C00963/2	C00963/...	C00963/32
Y	C00964/1	C00964/2	C00964/...	C00964/32

- The first pair of variates ([C00963/1](#) and [C00964/1](#)) is always valid.
- The X values of the characteristic must be entered in ascending order ($X_1 < X_2 < \dots < X_{32}$).
- An interruption of the ascending order of the X values represents the end of the characteristic (in our example: $X_5 < X_4$):

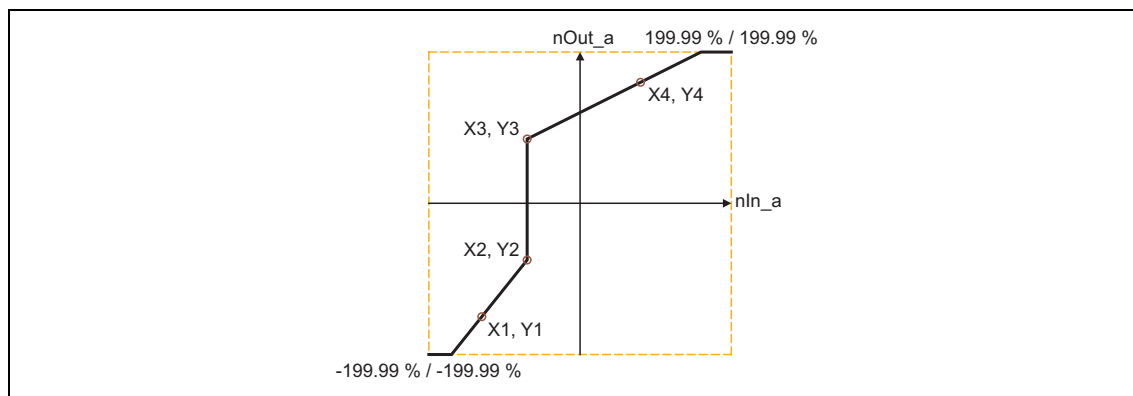
	1	2	3	4	5	6	7	...	32
X	-22938 (-140 %)	-14746 (-90 %)	11469 (70 %)	23757 (145 %)	0	0	0	0	0
Y	-22938 (-140 %)	-6554 (-40 %)	18842 (115 %)	26215 (160 %)	0	0	0	0	0

- Starting at the last valid pairs of variates, extrapolation is performed on both sides until the end of the X value range ($\pm 199.99\%$).

Special cases

- Step changes/discontinuities can be displayed by using the same parameter setting for two consecutive X values. A step change is only valid if it has a valid pair of variates. Otherwise, extrapolation continues, starting at the last valid pair of variates.

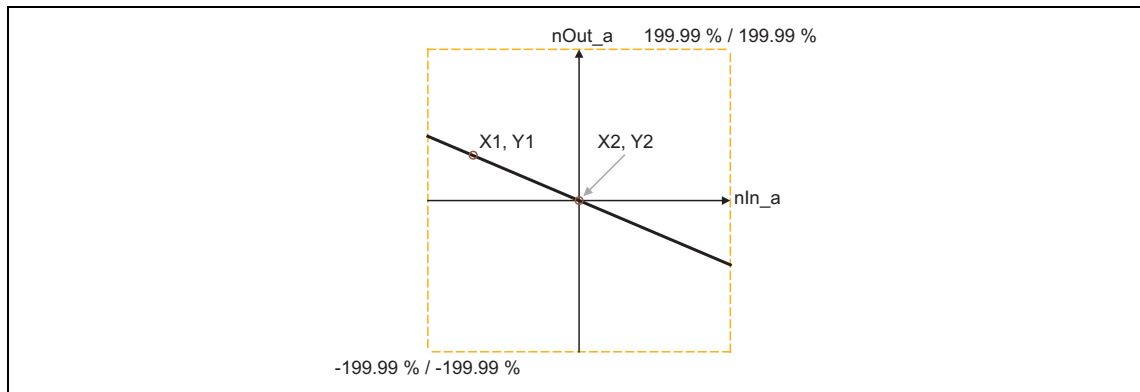
	1	2	3	4	5	6	7	...	32
X	-21300 (-130 %)	-11469 (-70 %)	-11469 (-70 %)	13107 (80 %)	0	0	0	0	0
Y	-24576 (-150 %)	-12288 (-75 %)	13927 (85 %)	26215 (160 %)	0	0	0	0	0



[19-23] Example: Characteristic with step change

- If only one interpolation point, X1, in the negative range is defined, X2 exists with the "0" Lenz setting being the valid interpolation point ($X2 > X1$), and a line is drawn through both interpolation points:

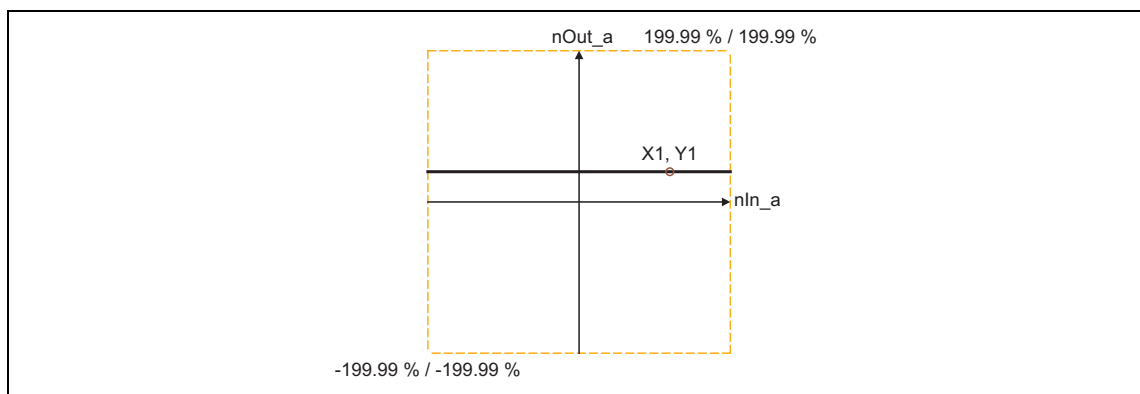
	1	2	3	4	5	6	7	...	32
X	-21300 (-130 %)	0 (0 %)	0	0	0	0	0	0	0
Y	6554 (40 %)	0 (0 %)	0	0	0	0	0	0	0



[19-24] Example: Characteristic with only one defined interpolation point and $X1 < 0$

- If only one interpolation point, X1, is defined in the positive range, a line is extrapolated:

	1	2	3	4	5	6	7	...	32
X	19661 (120 %)	0	0	0	0	0	0	0	0
Y	6554 (40 %)	0	0	0	0	0	0	0	0

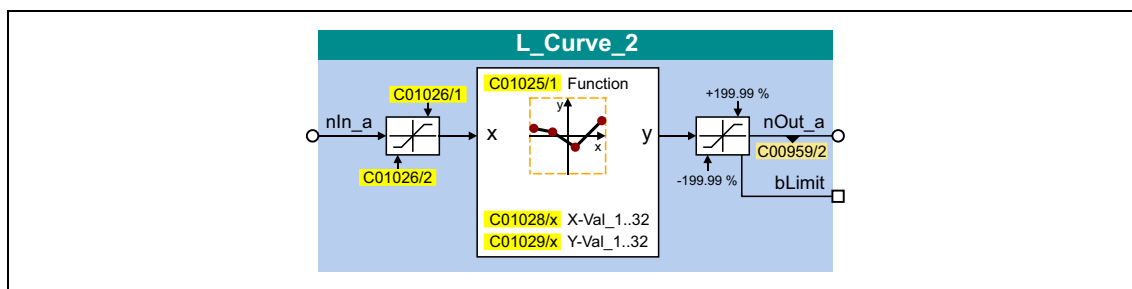


[19-25] Example: Characteristic with only one defined interpolation point and $X1 > 0$

19.1.72 L_Curve_2

This FB can optionally display a characteristic function or a curve function $y=f(x)$, the X axis being the input signal and the Y axis being the output signal.

- A limitation of the input value can be set in [C01026/1](#) (upper limit) and [C01026/2](#) (lower limit).
- The output value is internally limited to $\pm 199.99\%$. If a limitation of the output value is active, *bLimit* is set to TRUE.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input value (x) <ul style="list-style-type: none"> • $\pm 16384 \equiv \pm 100\%$ • A limitation of the input value can be set in C01026/1 (upper limit) and C01026/2 (lower limit).

Outputs

Identifier	Data type	Value/meaning	
nOut_a	INT	Output value (y) <ul style="list-style-type: none">• $\pm 16384 \equiv \pm 100\%$• Internal limitation to ± 32767 ($\pm 199.99\%$)	
bLimit	BOOL	"Limitation active" status signal	
		TRUE	The output value is limited to $\pm 199.99\%$.

Parameter

Parameter	Possible settings			Info
C00959/2	-199.99	%	199.99	Output value <ul style="list-style-type: none"> • Read only
C001025/1				Function selection
	0	Out = 0		FB deactivated (Lenze setting)
	1	Out = In		
	2	Out = f(In)		In preparation!
	3	Out = f(table)		See description of L_Curve_1 : ► Function 3: nOut_a = f(table)
C01026/1	-199.99	%	199.99	Upper limit for input value <ul style="list-style-type: none"> • Lenze setting: 199.99 %
C01026/2	-199.99	%	199.99	Lower limit for input value <ul style="list-style-type: none"> • Lenze setting: -199.99 %

Parameter	Possible settings			Info
C01028/1...32	-32767		32767	<p>X values for characteristic function</p> <ul style="list-style-type: none"> • Subcodes 1 ... 32 correspond to interpolation point values X1 ... X32. • $\pm 16384 \equiv \pm 100\%$ • Lenze setting: 0 <p>See description of L_Curve_1: ► Function 3: nOut a = f(table)</p>
C01029/1...32	-32767		32767	<p>Y values for characteristic function</p> <ul style="list-style-type: none"> • Subcodes 1 ... 32 correspond to interpolation point values Y1 ... Y32. • $\pm 16384 \equiv \pm 100\%$ • Lenze setting: 0 <p>See description of L_Curve_1: ► Function 3: nOut a = f(table)</p>

19.1.73 L_Curve_3

This FB can optionally display a characteristic function or a curve function $y=f(x)$, the X axis being the input signal and the Y axis being the output signal.

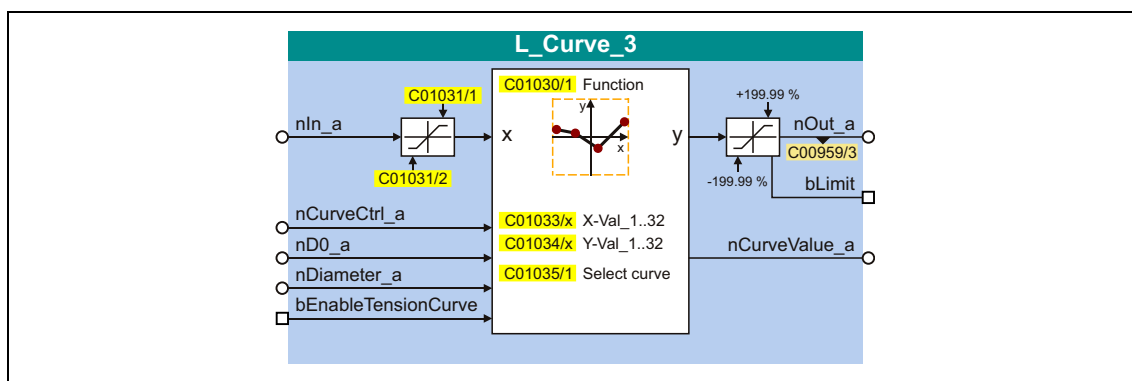
- A limitation of the input value can be set in [C01031/1](#) (upper limit) and [C01031/2](#) (lower limit).
- The output value is internally limited to $\pm 199.99\%$. If a limitation of the output value is active, *bLimit* is set to TRUE.



Tip!

From version 12.00.00 onwards the FB **L_Curve_3** can be used to create a tensile force depending on the diameter for winding applications. For this purpose, the FB has been extended by further inputs/outputs and parameters.

► [Use of the L_Curve_3 for tensile force characteristic](#)



Inputs

Identifier	Data type	Information/possible settings	
nIn_a	INT	Input value (x) <ul style="list-style-type: none">• $\pm 16384 \equiv \pm 100\%$• A limitation of the input value can be set in C01031/1 (upper limit) and C01031/2 (lower limit).	
		When using the FB for tensile force characteristic (from V12.00.00): Maximum tensile force setpoint in [%]	
The following inputs are only relevant when the FB is used for tensile force characteristic:			
nCurveCtrl_a From version 12.00.00	INT	Slope of the characteristic (torque characteristic) in [%] <ul style="list-style-type: none">• $\pm 16384 \equiv \pm 100\%$• Internal limitation to -100 ... +200 %• With 100 %, there is a constant tensile force curve and thus a torque proportionally rising with D.	
nD0_a From version 12.00.00	INT	Initial point of the characteristic <ul style="list-style-type: none">• $16384 \equiv 100\% \equiv$ maximum diameter	
nDiameter_a From version 12.00.00	INT	Current diameter in [%] <ul style="list-style-type: none">• $16384 \equiv 100\% \equiv$ maximum diameter	
bEnableTensionCurve From version 12.00.00	BOOL	Activate tensile force setpoint	
		FALSE	Tensile force setpoint is not influenced.
		TRUE	Tensile force setpoint is multiplied by the characteristic value.

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output value (y) <ul style="list-style-type: none">• $\pm 16384 \equiv \pm 100\%$• Internal limitation to ± 32767 ($\pm 199.99\%$)
		When using the FB for tensile force characteristic (from V12.00.00): Current tensile force setpoint in [%] <ul style="list-style-type: none">• $16384 \equiv 100\%$
bLimit	BOOL	"Limitation active" status signal
		TRUE The output value is limited to $\pm 199.99\%$.
nCurveValue_a	INT	Current characteristic value of the tensile force characteristic in [%]
From version 12.00.00		

Parameter

Parameter	Possible settings			Info
C00959/3	-199.99	%	199.99	Output value <ul style="list-style-type: none"> • Read only
C01030/1				Function selection
	0	Out = 0		FB deactivated (Lenze setting)
	1	Out = In		
	2	Out = f(In)		In preparation!
	3	Out = f(table)		See description of L_Curve_1 : ▶ Function 3: nOut_a = f(table)
	4	Out = f(characteristic)		▶ Use of the L_Curve_3 for tensile force characteristic
C01031/1	-199.99	%	199.99	Upper limit for input value <ul style="list-style-type: none"> • Lenze setting: 199.99 %
C01031/2	-199.99	%	199.99	Lower limit for input value <ul style="list-style-type: none"> • Lenze setting: -199.99 %
C01033/1...32	-32767		32767	X values for characteristic function <ul style="list-style-type: none"> • Subcodes 1 ... 32 correspond to interpolation point values X1 ... X32. • $\pm 16384 \equiv \pm 100\%$ • Lenze setting: 0 See description of L_Curve_1 : ▶ Function 3: nOut_a = f(table)
C01034/1...32	-32767		32767	Y values for characteristic function <ul style="list-style-type: none"> • Subcodes 1 ... 32 correspond to interpolation point values Y1 ... Y32. • $\pm 16384 \equiv \pm 100\%$ • Lenze setting: 0 See description of L_Curve_1 : ▶ Function 3: nOut_a = f(table)

Parameter	Possible settings	Info
C01035/1 (from V12.00.00)		Selection of the tensile force profile ► Use of the L_Curve_3 for tensile force characteristic
	0 Linear tensile force profile	Lenze setting
	1 Linear torque characteristic	
	2 Tensile force profile according to characteristic	

19.1.73.1 Use of the L_Curve_3 for tensile force characteristic

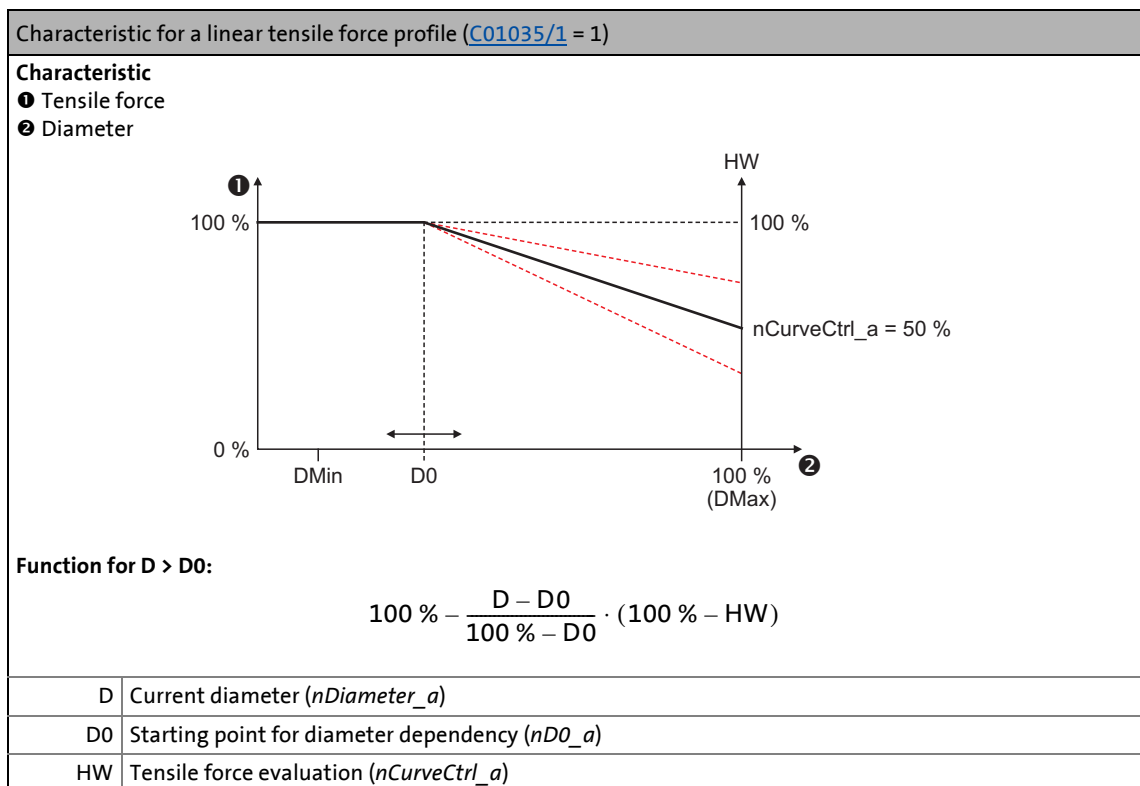
In case of centre winders, the drive torque is transmitted from the centre via the individual layers up to the winder surface. In case of smooth materials and high diameter areas, it is mostly required to reduce the tensile force depending on the diameter.

The FB **L_Curve_3** can be used to generate a tensile force profile depending on the diameter. For this purpose, the selection "4: Out = f(characteristic)" has to be set in [C01030/1](#).

The characteristic is marked by a starting area with constant evaluation (100 %) and a second area in which the tensile force is adapted to the diameter.

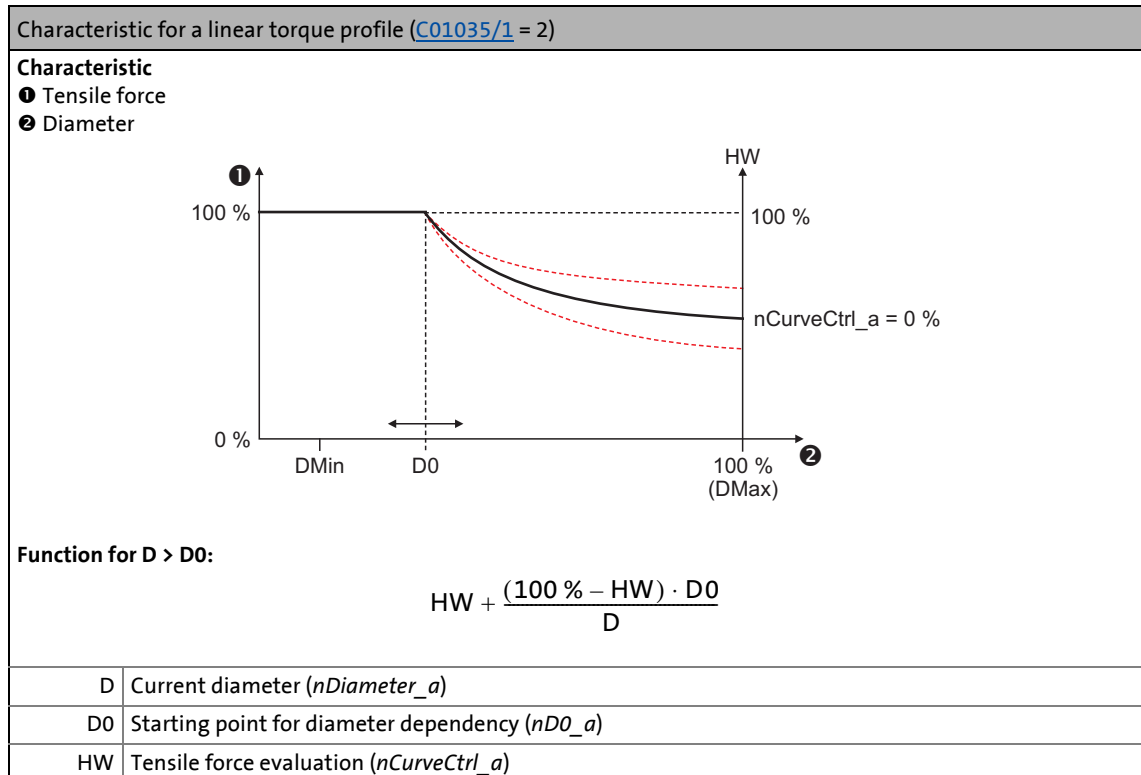
The part of the characteristic that depends on the diameter can be generated for a linear tensile force profile, a linear torque profile or based on a specified characteristic. The respective selection is made in [C01035/1](#).

Linear tensile force profile

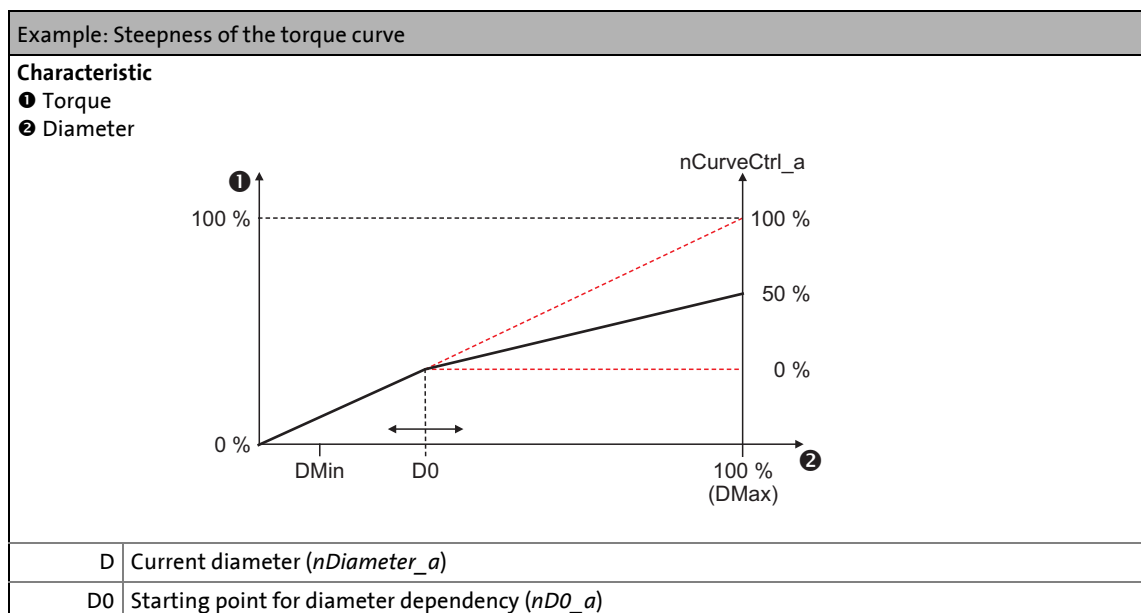


- *nD0_a* serves to define at which diameter the tensile force decrease is to start.

Linear torque characteristic



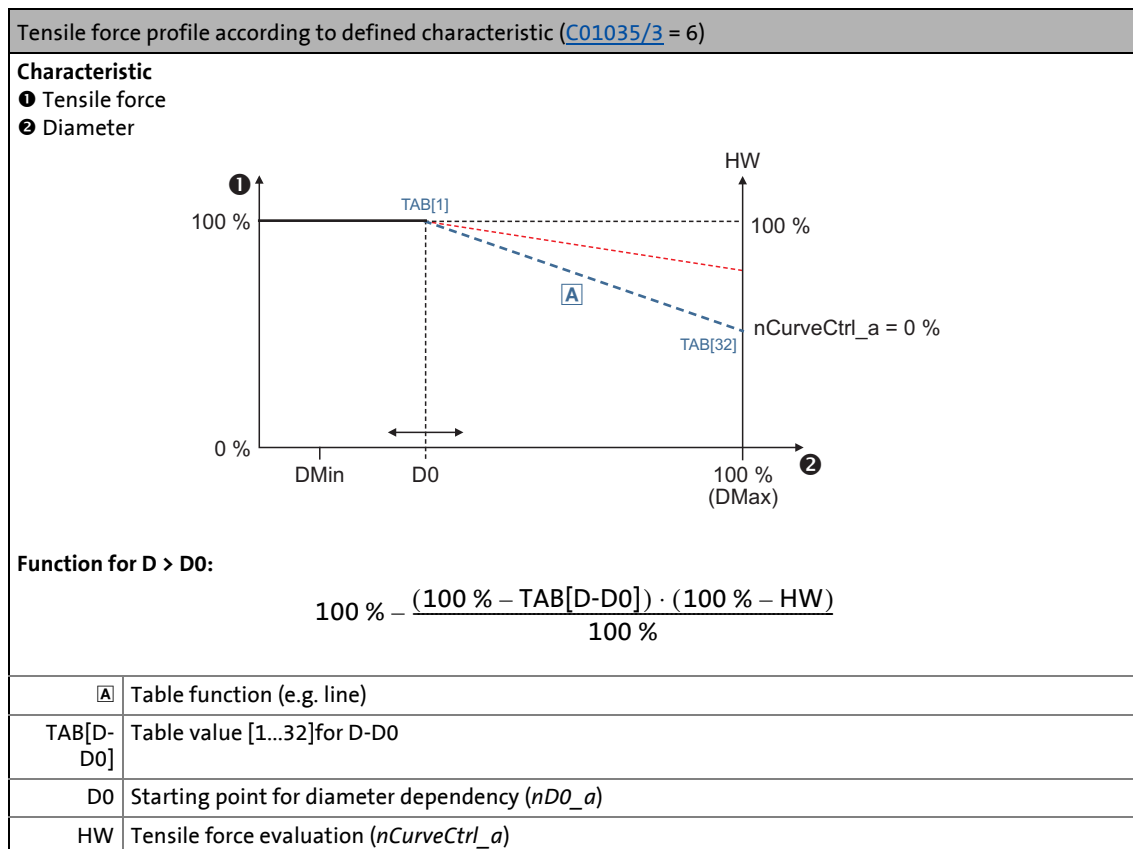
- *nD0_a* serves to define at which diameter the tensile force decrease is to start.
- Since in this characteristic selection, the linear torque profile is in the focus, define in this case the slope of the torque curve via *dnCurveCtrl_n*:
 - When *nCurveCtrl_a* = 100 %, the tensile force remains unchanged.
 - When *nCurveCtrl_a* = 0 %, the tensile force is reduced up to D0/DMax.



Tensile force profile according to characteristic

The characteristic (A) can be parameterised in [C01033/1...32](#).

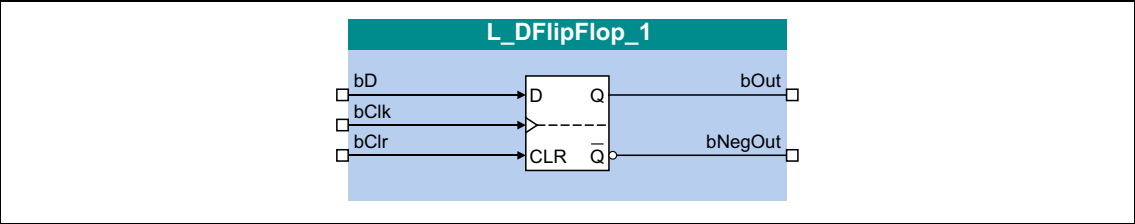
- The characteristic comprises 32 values, regularly distributed over the diameter range of D0 ... DMax.
- The values are to be set as raw values ($\pm 16384 \equiv \pm 100\%$).



- $nD0_a$ serves to define the start of the table range (D0).
- $nCurveCtrl_a$ serves to change the slope of the characteristic.
 - When $nCurveCtrl_a = 0\%$, the slope of the characteristic remains unchanged.

19.1.74 L_DFlipFlop_1

The FB saves binary signals (DFlipFlop) in a clock-controlled way.



Inputs

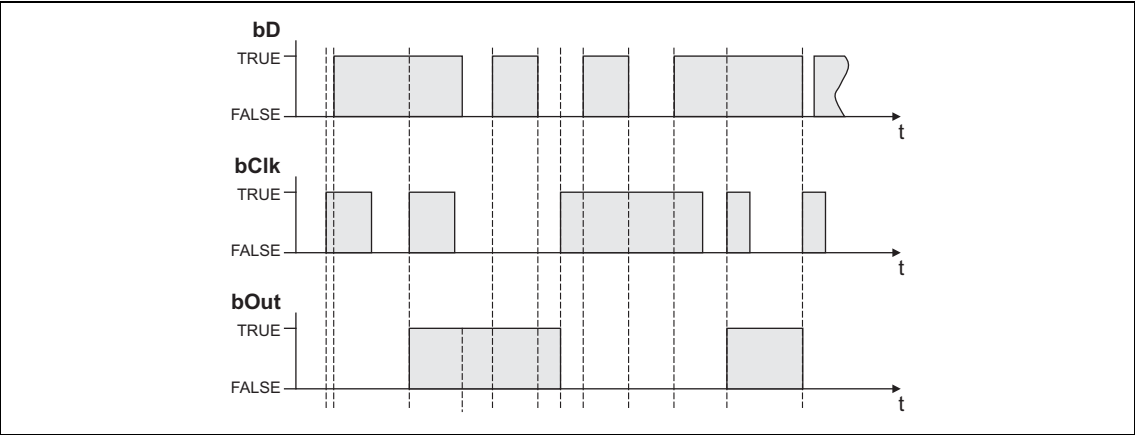
Identifier	Data type	Information/possible settings
bD	BOOL	Data input
bClk	BOOL	Clock input • Only FALSE/TRUE edges are evaluated
bClr	BOOL	Reset input
		TRUE • The <i>bOut</i> output is set to FALSE. • The <i>bNegOut</i> output is set to TRUE.

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal
bNegOut	BOOL	Output signal, inverted

Function

If the *bClr* input = FALSE, a signal edge at the *bClk* input switches the static input signal *bD* to the *bOut* output, where it is retained:

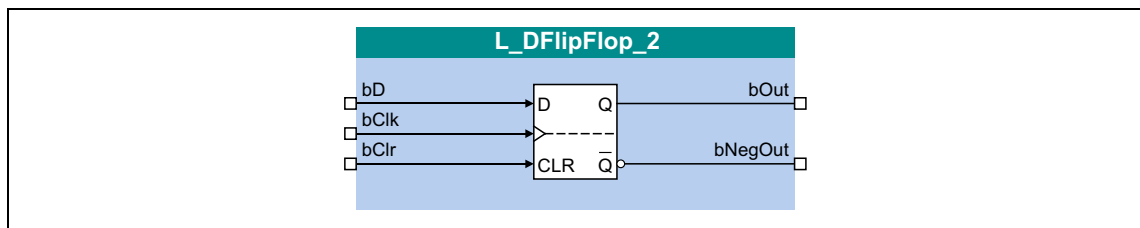


If the *bClr* input = TRUE:

- Due to the priority *bClr* > *bClk*, *bD* the *bOut* output signal can be set any time to the *FALSE* status by the *bClr* input signal = TRUE.
- The output signal is kept in this status independent of the other input signals.

19.1.75 L_DFlipFlop_2

The FB saves binary signals (DFlipFlop) in a clock-controlled way.



Inputs

Identifier	Data type	Information/possible settings
bD	BOOL	Data input
bClk	BOOL	Clock input • Only FALSE/TRUE edges are evaluated
bClr	BOOL	Reset input
		TRUE <ul style="list-style-type: none"> • The <i>bOut</i> output is set to FALSE. • The <i>bNegOut</i> output is set to TRUE.

Outputs

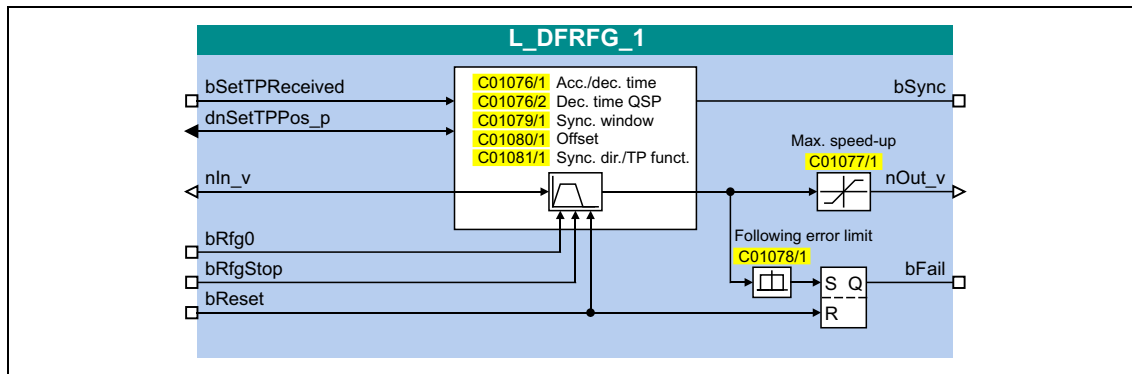
Identifier	Data type	Value/meaning
bOut	BOOL	Output signal
bNegOut	BOOL	Output signal, inverted



For a detailed functional description see [L_DFlipFlop_1](#).

19.1.76 L_DFRFG_1

This FB synchronises a drive (slave) to the master value of a master drive and then executes a angular synchronism with regard to the digital frequency.



Inputs

Identifier	Data type	Information/possible settings
bSetTPReceived	BOOL	Input for status signal "Touch probe detected"
		FALSE → TRUE Touch probe or zero pulse received.
dnSetTPPos_p	DINT	Input for accepting the position measured via touch probe
nIn_v	INT	Speed setpoint of the master • Scaling: 16384 ≙ 15000 rpm
bRfg0	BOOL	Ramp down ramp function generator to "0" (quick stop function) • This input can, for instance, be connected to the status signal "quick stop active".
		TRUE Ramp down the ramp function generator to "0" • The drive is brought to a standstill with the deceleration time set in C01076/2 .
bRfgStop	BOOL	Stop ramp function generator
		TRUE Stop ramp function generator • The last status is output to nOut_v. • The speed/angle setpoint nIn_v is saved. • After bStop is reset to FALSE, the setpoint angle is approached via the ramp function generator.
bReset	BOOL	Reset added angle setpoint
		TRUE The internally added angle setpoint is reset and the ramp function generator is activated. If the status signal bFail is set, it will also be reset.
		TRUE → FALSE Detect speed/angle setpoint.

Outputs

Identifier	Data type	Value/meaning
bSync	BOOL	Status signal "Drive is running synchronously"
		TRUE The drive is running synchronously, the speed input id directly applied to the speed output.
nOut_v	INT	Speed/angle setpoint • Scaling: 16384 \equiv 15000 rpm
bFail	BOOL	Status signal "Angular difference exceeded"
		TRUE The angular difference set in C01078/1 has been exceeded.

Parameter

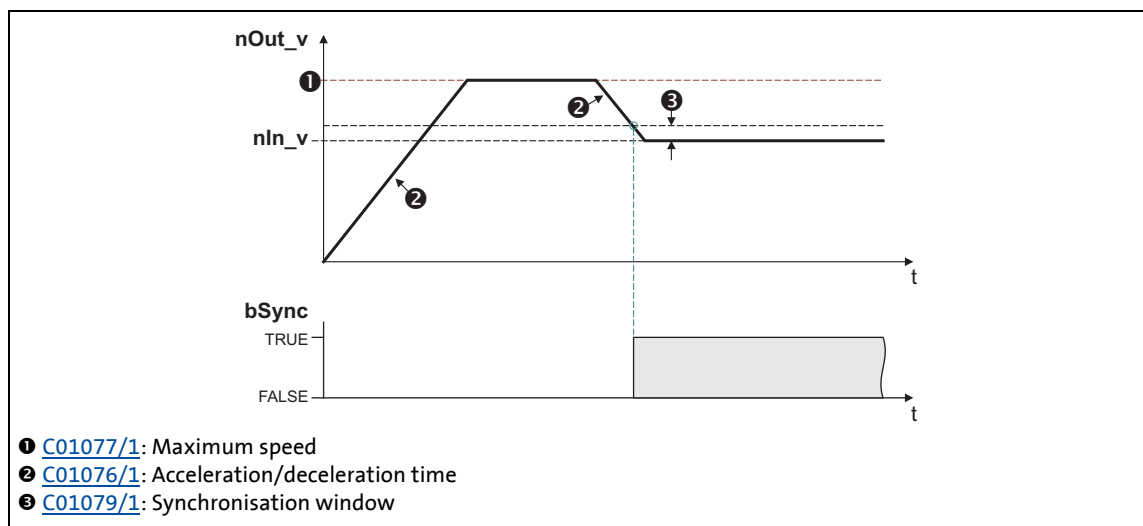
Parameter	Possible settings			Info
C01076/1	0.000	s	999.900	Acceleration and deceleration time • Relating to the reference speed (constant acceleration and deceleration) set in C00011 . • It is a maximum value which limits the acceleration of the ramp function generator. • Lenze setting: 1.000 s
C01076/2	0.000	s	999.900	Deceleration time for quick stop of the slave drive • Relating to the reference speed (constant acceleration and deceleration) set in C00011 . • It is a maximum value which limits the deceleration of the ramp function generator. • Lenze setting: 0.000 s
C01077/1	1	rpm	15000	Max. speed-up • Lenze setting: 3000 rpm
C01078/1	10	Incr.	2000000000	Following error limit • Scaling: A revolution is displayed with 65536 increments or steps. • Lenze setting: 2000000000 incr.
C01079/1	0	Incr.	65535	Synchronisation window (position) • If the difference between the master and the slave is lower than the synchronisation window, the <i>bSync</i> status signal is set to TRUE. • Lenze setting: 100 incr.
C01080/1	-2147483647	Incr.	2147483647	Offset • Angular offset for the internal actual position of the FB • Scaling: A revolution is displayed with 65536 increments or steps. • Lenze setting: 0 incr.

Parameter	Possible settings	Info
C01081/1		Sync. direction/TP function
	1 cw/ccw - without TP (Lenze setting)	• Selection of the direction of rotation for synchronising
	2 cw - without TP	• With high offset values and low input speed, the drive may change its direction of rotation. In order to prevent this, a direction of rotation can be permanently defined via this parameter.
	3 ccw - without TP	
	4 cw/ccw - with TP	
	5 cw - with TP	
	6 ccw - with TP	

19.1.76.1 Ramp function generator (profile generator)

The ramp function generator accelerates the slave drive to the input master speed.

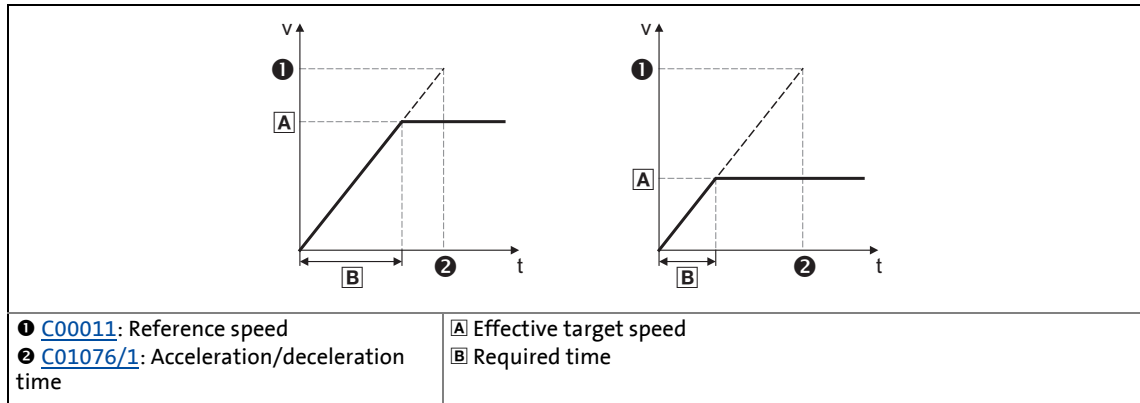
- Synchronising starts when the FB receives a touch probe edge from the master axis (e.g. a conveying belt) at the *bSetTPReceived* input.
- When the slave reaches the setpoint speed of the master and the made up path difference is lower than the synchronisation window set in [C01079/1](#), the *bSync* output is set to TRUE. At the same time, the FB switches the profile generator to inactive and outputs the *nIn_v* input speed to *nOut_v*.



[19-26] Example: Synchronisation

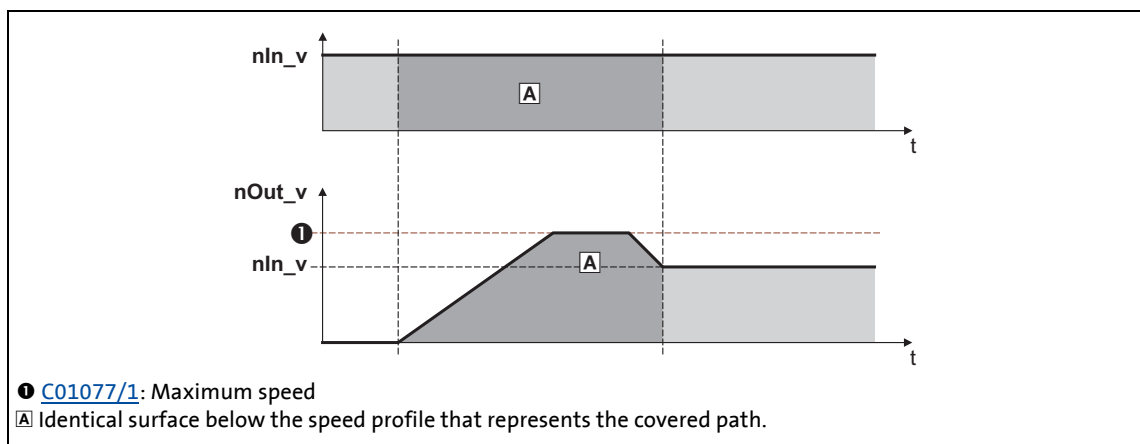
- [C01077/1](#) serves to set a maximum speed which limits the speed of the slave.

- The acceleration or deceleration in the synchronous point results from the acceleration/deceleration time set in [C01076/1](#).
 - Reference for the acceleration/deceleration time is the reference speed ([C00011](#)):



[19-27] Connection between acceleration time and acceleration

- Based on the input speed of the master axis, a setpoint angle is calculated from the starting time onwards which leads the actual angle of the slave.
- Dependent on the master speed and the settings for acceleration and offset, the FB may travel oversynchronously for reducing the angular difference, i.e. $nOut_v$ is higher than nIn_v :



[19-28] Speed/time diagram

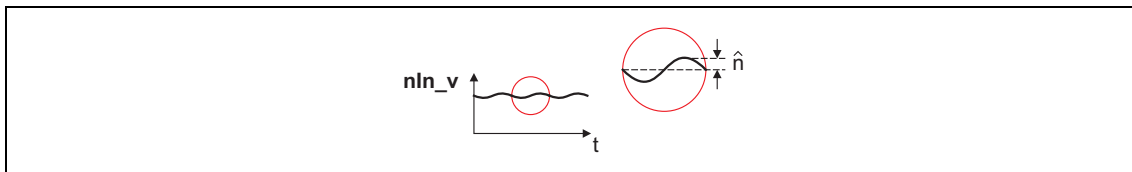


Note!

- Set the maximum speed in [C01077/1](#) higher than the master speed to be expected. The speed is selected on the motor side and is independent of the reference speed ([C00011](#)). The higher the difference between maximum speed and master speed, the less time to the synchronous time is required.
- In case of a heavily oscillating input speed it may occur that directly after setting the *bSync* status signal to TRUE the FB still executes slight angle corrections.
- Generally avoid acceleration or deceleration processes of the master axis while the slave axes are synchronising.

**Tip!**

Set the synchronisation window in [C01079/1](#) higher than the amplitude of beat available on the input signal:

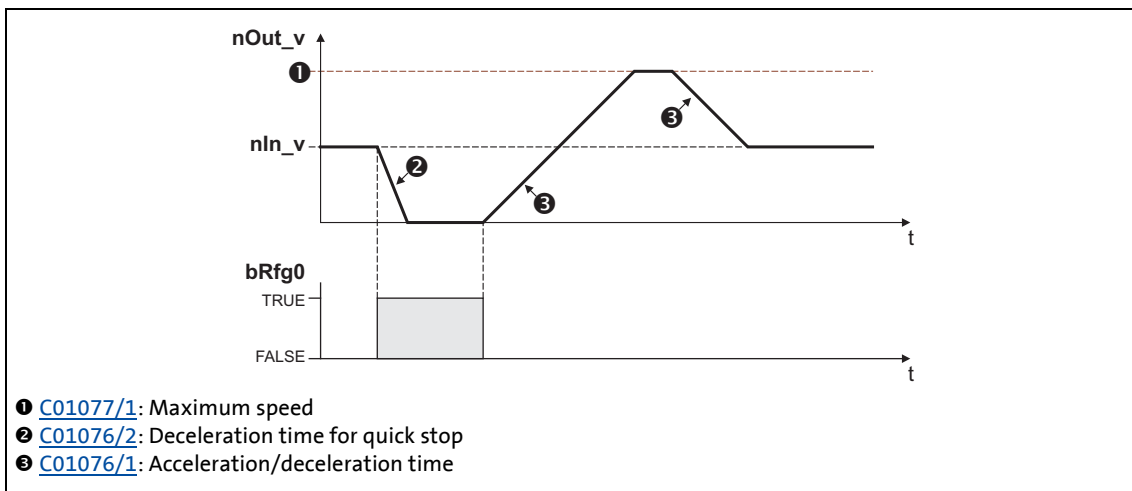


[19-29] Example: Beat on the input signal

19.1.76.2 Quick stop

The quick stop function removes the drive from the interconnection and leads it to standstill.

- Quick stop is activated by setting *bRfg0* to TRUE.
- [C01076/2](#) is used to set the delay time in [s] which refers as the acceleration/deceleration time to the reference speed ([C00011](#)).
- The angle setpoint created internally on the basis of the input signal *nln_v* is saved.
- After *bRfg0* is reset to FALSE, the angle setpoint is approached via the ramp function generator again.

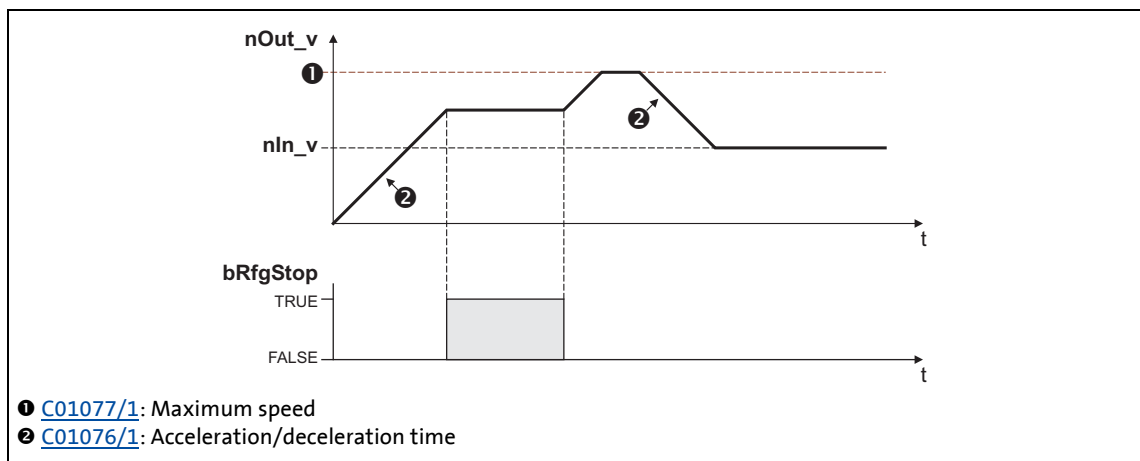


[19-30] Example: Quick stop function (QSP)

19.1.76.3 Ramp function generator stop

The stop function holds the status of the ramp function generator during operation.

- The stop function is activated by setting *bRfgStop* to TRUE.
- The last status is output to *nOut_v* (16384 \equiv 15000 rpm).
- The angle setpoint created internally on the basis of the input signal *nIn_v* is saved, thus the monitoring function of the angular difference between the created setpoint angle and actual angle cannot be activated.
- After *bRfgStop* is reset to FALSE, the angle setpoint is approached via the ramp function generator again.



[19-31] Example: Stop function

19.1.76.4 Reset angle setpoint

By setting *bReset* to TRUE, the internally created angle setpoint is set to "0" and the ramp function generator is activated.

19.1.76.5 Detecting the angular difference

In [C01078/1](#), a limit value for monitoring the angular difference between the created setpoint and actual angles can be set.

- Scaling: A revolution is displayed with 65536 increments or steps.
- The ramp function generator can accept a angular difference of up to ± 2140000000 increments (≈ 32000 revolutions).
- If monitoring responds, the status signal *bFail* is set to TRUE.
- If the internally added angle setpoint is reset by setting *bReset* to TRUE, the *bFail* status signal is reset to FALSE.

19.1.76.6 Offset setting

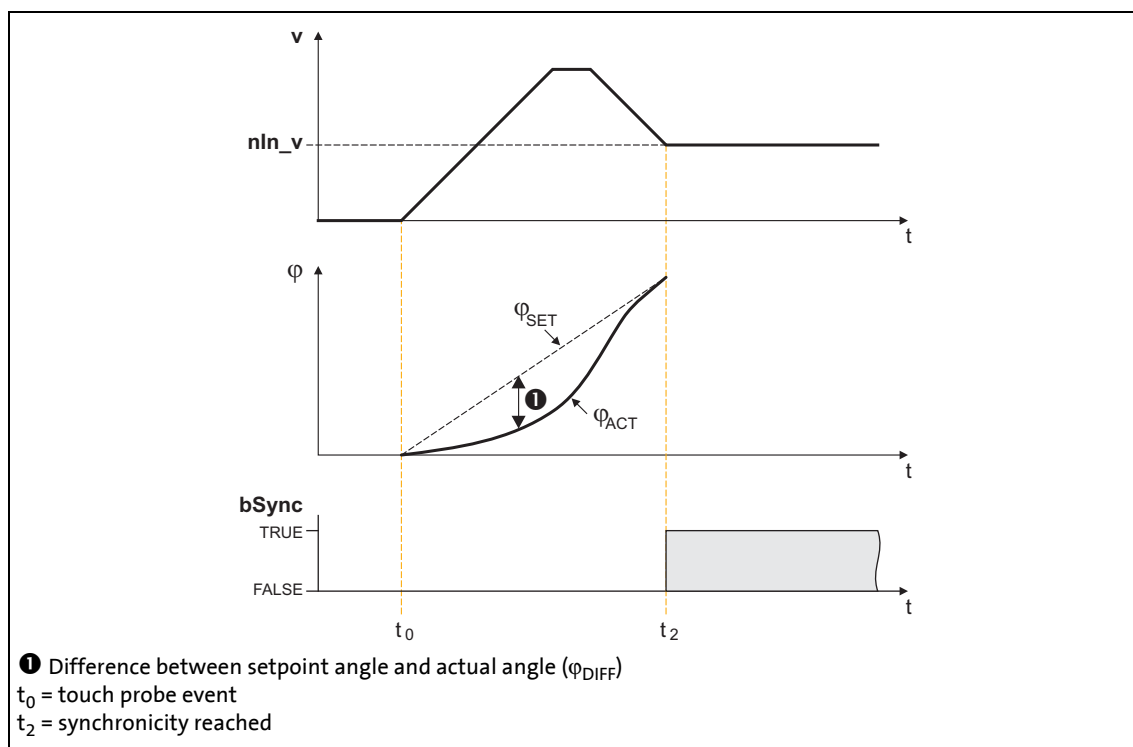
If the time to synchronicity is too long or the slave drive must not be operated oversynchronously, either the acceleration can be adapted or the touch probe initiator can be shifted. Since this is only possible to a limited extent due to construction conditions, in this case the better solution is selecting a virtual angular offset.

- In order to reach angle synchronicity, the difference between created setpoint and actual angle must be zero:

$$\varphi_{\text{DIFF}} = \varphi_{\text{SET}} - \varphi_{\text{ACT}} = 0$$

Behaviour without offset

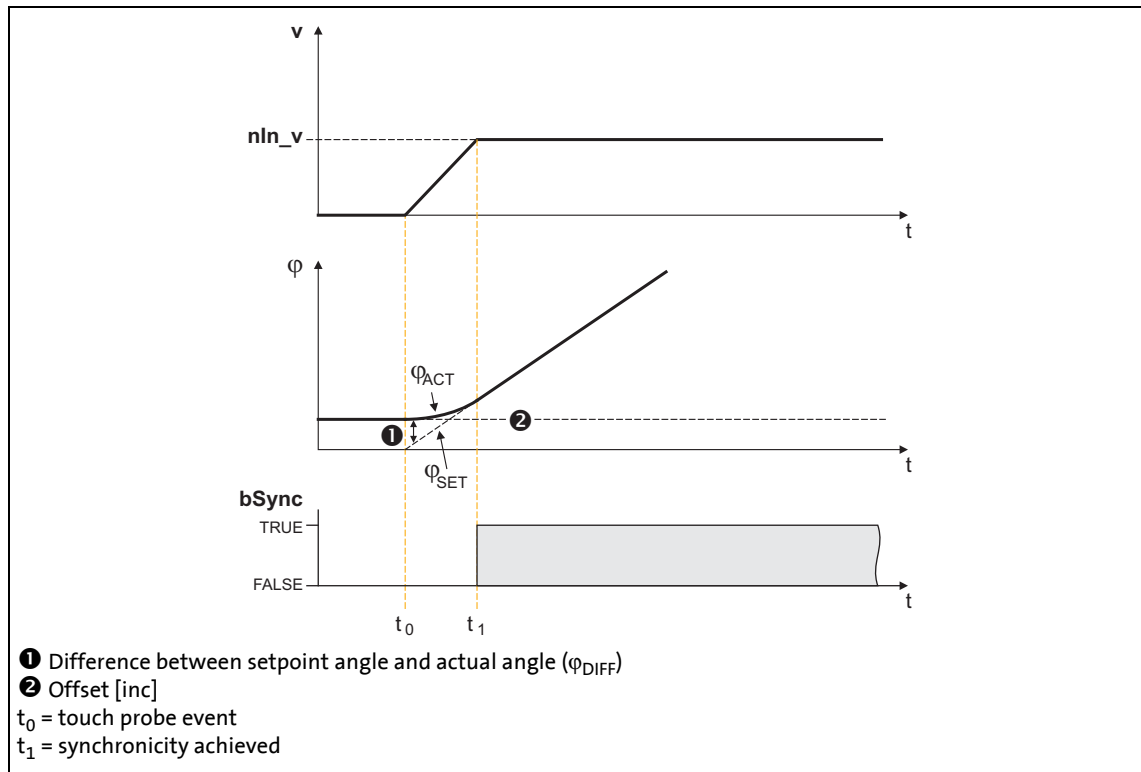
If the actual angle starts with an offset = 0, a higher difference between setpoint angle and actual angle develops:



[19-32] Example: Without offset selection (offset = 0)

Behaviour with offset

By selecting an offset, the actual position is preloaded with a non-zero value. This reduces the distance and the time to synchronicity.



[19-33] Example 1: With offset selection

- When a positive offset is selected, the sign of the distance between setpoint and actual value changes. This distance is reduced due to the acceleration of the slave from the input of the touch probe pulse. Thus, the time to synchronicity is shorter.
- The offset refers to the master value selection and is scaled with an encoder revolution ($\equiv 65536$ increments).
- The offset can be determined empirically, but it is sensible to calculate the required acceleration distance and select this value as offset:

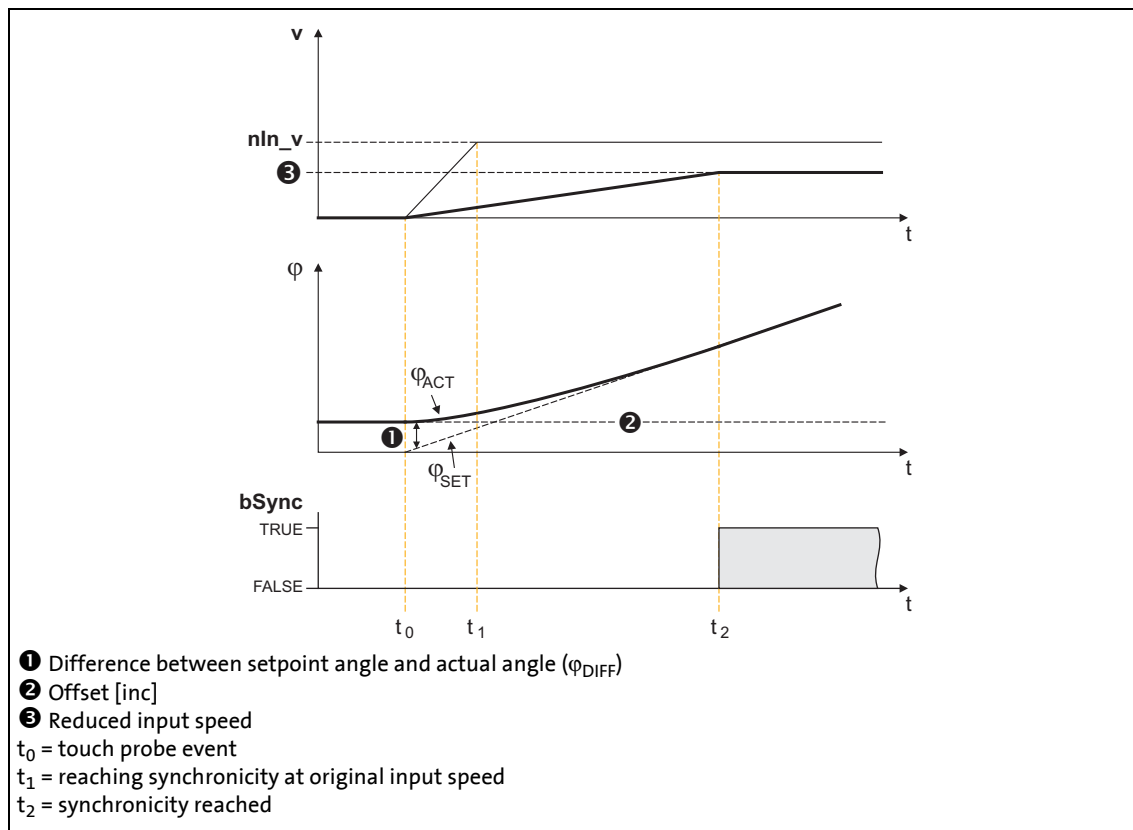
$$\Phi_{ACC} = \frac{1}{2} \cdot \frac{(V_{SET})^2}{C00011 [rpm]} \cdot C01076/1 [ms] \cdot \frac{16384 [incr./ms]}{15000 [rpm]}$$

 ϕ_{ACC} = acceleration distance in [increments] v_{SET} = setpoint speed in [rpm]

C00011 = reference speed of the motor in [rpm]

C01076/1 = acceleration/deceleration time of the ramp generator in [ms]

The acceleration calculated from the acceleration/deceleration time ([C01076/1](#)) is a maximum acceleration that will not be reached if the input speed is reduced and the FB has to reach its target with a too high offset.



[19-34] Example 2: With offset selection and reduced input speed



Note!

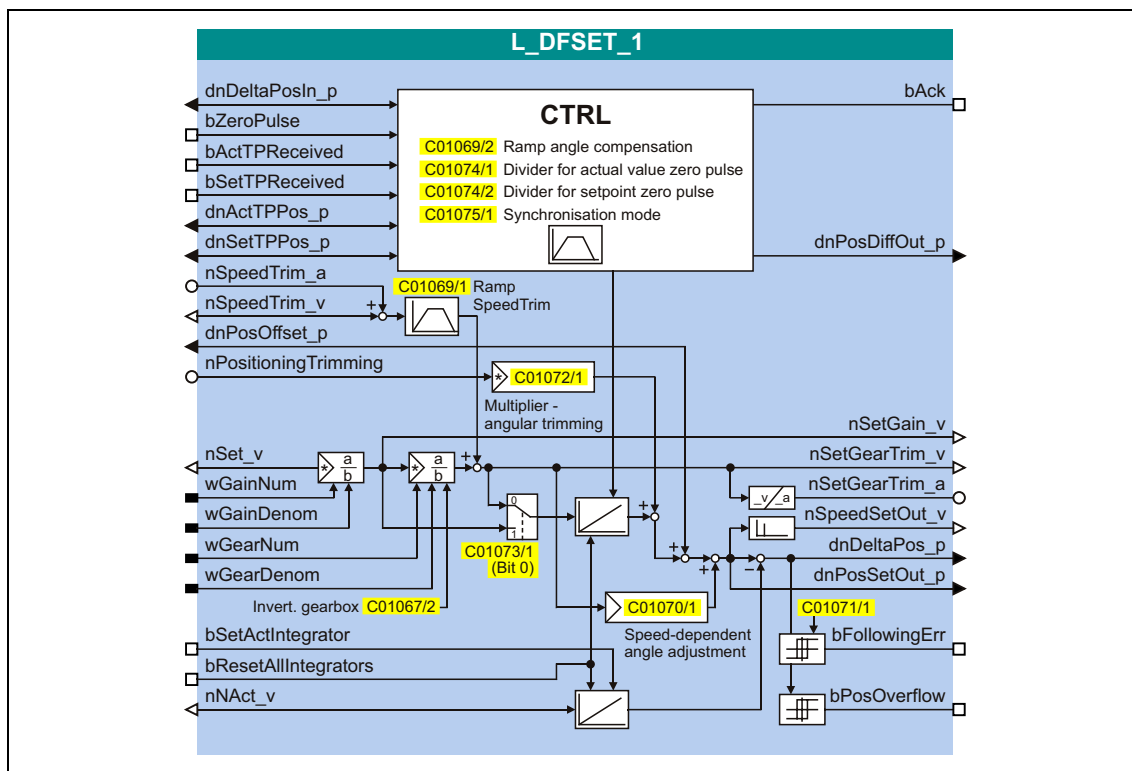
With a very low input speed, the acceleration can also get negative which causes the slave drive to change its direction of rotation.

In order to prevent a change of the direction of rotation, [C01069/1](#) serves to select a permanent direction of rotation.

19.1.77 L_DFSET_1

This FB prepares the master value for a slave drive. This FB enables the controller to follow the master drive true to speed and angle.

- You can select values for the stretch factor and gearbox factor of the slave.
- A speed trimming or angular trimming is possible.



Inputs

Identifier	Data type	Information/possible settings
dnDeltaPosIn_p	DINT	Input for considering a following error for the mark correction <ul style="list-style-type: none"> • The value of this input is used for the following error compensation if the <i>nNAct_v</i> input is not assigned.
bZeroPulse	BOOL	Enable of the zero pulse-/touch probe synchronisation for the modes 2, 10 ... 13 <ul style="list-style-type: none"> • The mode is selected in C01075/1.
		FALSE \nrightarrow TRUE Synchronisation enabled.
bActTPReceived	BOOL	Input for detecting an actual value touch probe or zero pulse
		FALSE \nrightarrow TRUE Actual value touch probe or zero pulse received.
bSetTPReceived	BOOL	Input for status signal "Touch probe detected"
		FALSE \nrightarrow TRUE Touch probe or zero pulse received.
dnActTPPos_p	DINT	Input for accepting the position measured via touch probe at <i>bActTPReceived</i>
dnSetTPPos_p	DINT	Input for accepting the position measured via touch probe at <i>bSetTPReceived</i>
nSpeedTrim_a	INT	Speed trimming in [%] <ul style="list-style-type: none"> • Scaling: $16384 \equiv 100\%$

Identifier	Data type	Information/possible settings
nSpeedTrim_v	INT	Speed trimming in [increments/ms] • Scaling: 16384 \equiv 15000 rpm • Speed trimming via this input is more precise.
dnPosOffset_p	DINT	Angular offset in [increments] • Scaling: A motor revolution is mapped with 65536 increments or steps.
nPositionTrimming	INT	Angular trimming in [increments] • Scaling: A motor revolution is mapped with 65536 increments or steps. • When analog values are selected: 100 % \equiv 1/4 revolution \equiv 16384 increments • The setting range can be extended via C01072/1 .
nSet_v	INT	Speed setpoint • Scaling: 16384 \equiv 15000 rpm
wGainNum	WORD	Stretch factor (numerator)
wGainDenom	WORD	Stretch factor (denominator)
wGearNum	WORD	Gearbox factor (numerator)
wGearDenom	WORD	Gearbox factor (denominator)
bSetActIntegrator	BOOL	Equalise angle integrators (current position = set position) • This input has a higher priority than the <i>bResetAllIntegrators</i> input.
		FALSE \rightarrow TRUE Set following error <i>dnDeltaPos_p</i> = 0.
		TRUE Equalise angle integrators.
bResetAllIntegrators	BOOL	Reset angle integrators
		TRUE Positional deviation, <i>dnPosSetOut_p</i> and <i>dnDeltaPos_p</i> are set to "0".
nNAct_v	INT	Actual value in [increments/ms] for calculating the actual position • Scaling: 16384 \equiv 15000 rpm • If this input is connected or assigned to an output, the following error created from integration of this input and difference with the set position is used for the following error compensation in case of mark correction.

Outputs

Identifier	Data type	Value/meaning
bAck	BOOL	Status signal of the internal angle correction (or control signal for external angle correction)
		TRUE Status signal "Synchronising is executed" • When the external angle correction is deactivated (C01073/1 - bit 2 = "0") and a ramp for the angle decompensation is set in C01069/2 .
		FALSE \rightarrow TRUE Control signal "Start external angle correction" • When the external angle correction is activated (C01073/1 - bit 2 = "1") and the angular offset is measured.
dnPosDiffOut_p	DINT	Angular offset in [increments] • Difference between two positions measured by means of touch probe.
nSetGain_v	INT	Speed setpoint in [increments/ms] evaluated with stretch factor • Scaling: 16384 \equiv 15000 rpm
nSetGearTrim_v	INT	Speed setpoint in [increments/ms] evaluated with stretch factor and gearbox factor • Scaling: 16384 \equiv 15000 rpm
nSetGearTrim_a	INT	Speed setpoint in [%] evaluated with stretch factor and gearbox factor • Scaling: 16384 \equiv 100 % reference speed (C00011)

Identifier	Data type	Value/meaning
nSpeedSetOut_v	INT	Speed setpoint in [increments/ms] <ul style="list-style-type: none">• Scaling: 16384 ≡ 15000 rpm• Derived from angle setpoint <i>dnPosSetOut_p</i>.• Can change abruptly if e.g. the angular offset changes abruptly.
dnDeltaPos_p	DINT	Following error between setpoint position and actual position in [increments] <ul style="list-style-type: none">• This output can be used for display purposes.
dnPosSetOut_p	DINT	Angle setpoint in [increments] <ul style="list-style-type: none">• Scaling: A revolution is displayed with 65536 increments or steps.
bFollowingErr	BOOL	Status signal "Following error"
		<div>TRUE<div>Following error occurred.<ul style="list-style-type: none">• The limit value set in C01071/1 has been exceeded.</div></div>
bPosOverflow	BOOL	Status signal "angle controller overflow" <ul style="list-style-type: none">• An angle controller overflow occurs from a limit value of 2130706432 increments.
		<div>TRUE<div>Angle controller overflow occurred.</div></div>

Parameter

Parameter	Possible settings			Info
C01067/2				Invert. gearbox nSet_v
	0	not inverted		
	1	inverted		
	2	Automatically from MCK		
C01069/1	0	Incr./ms	32767	Ramp SpeedTrim <ul style="list-style-type: none">• Lenze setting: 10 incr./ms• From version 12.00.00 onwards, this setting has a resolution increased by the factor 100: A value of 32767 is internally evaluated with 327.67. Hence, the unit is [incr./100 ms].
C01069/2	0	Incr./ms	32767	Ramp angle compensation <ul style="list-style-type: none">• The increments for the angle compensation in case of mark correction are specified in the Lenze setting with downstream 3rd-order polynomial.• Lenze setting: 100 incr./ms
C01070/1	-134217728	Incr.	134217728	Speed-dependent angle adjustment <ul style="list-style-type: none">• Scaling: A revolution is displayed with 65536 increments or steps.• Lenze setting: 0 incr.
C01071/1	10	Incr.	2147483647	Following error limit <ul style="list-style-type: none">• Scaling: A motor revolution is mapped with 65536 increments or steps.• Lenze setting: 32768 incr.
C01072/1	-20000		20000	Multiplier - angular trimming <ul style="list-style-type: none">• Lenze setting: 1

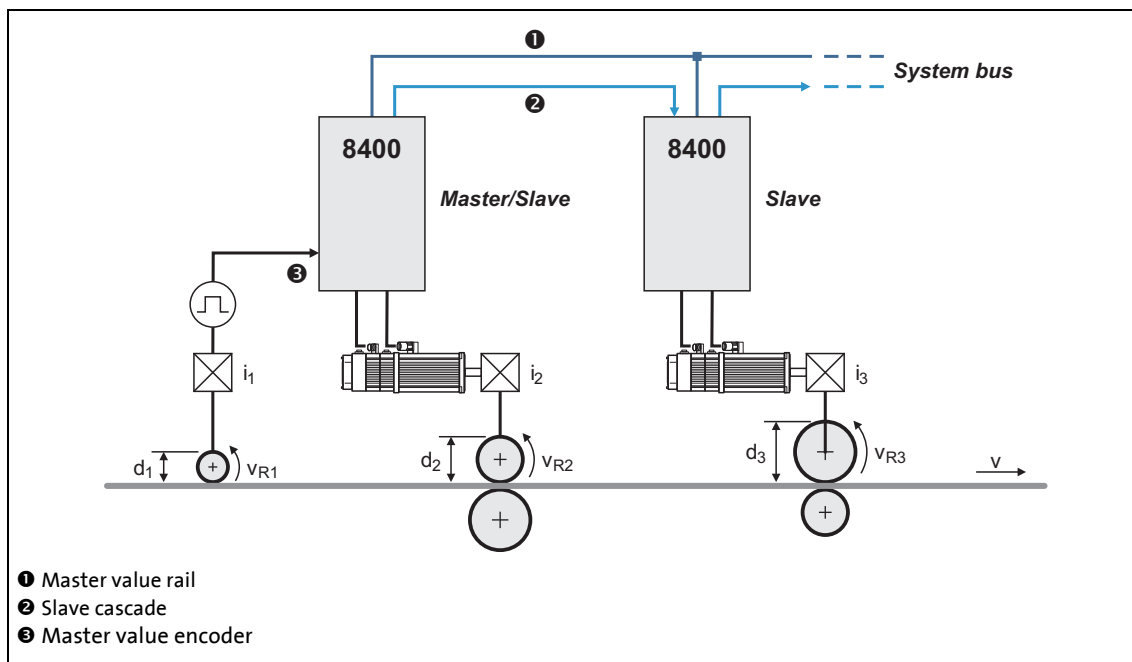
Parameter	Possible settings			Info
C01073/1	Setting is bit coded:			Setting <ul style="list-style-type: none">• Lenze setting: 0x02
	Bit 0	Setpoint angle without gearbox factor		0 = Evaluation of the setpoint angle with gearbox factor. 1 = Evaluation of the setpoint angle without gearbox factor.
	Bit 1	Angle correction with polynomial		0 = Angle correction without downstream polynomial. 1 = Angle correction with downstream polynomial.
	Bit 2	External angle correction		0 = Internal angle correction 1 = External angle correction <ul style="list-style-type: none">• From version 13.00.00
	Bit 3	Reserved		
	...			
	Bit 7			
C01074/1	0		16384	Divisor for actual value zero pulse <ul style="list-style-type: none">• Number of signals to be received at least until synchronisation gets active.• Initialisation: 0 (≡ 1)
	Note: The settings 0 and 1 are functionally identical. If 0 or 1 is set, at least one pulse is required in order that the synchronisation gets active.			
C01074/2	0		16384	Divisor for setpoint zero pulse <ul style="list-style-type: none">• Number of signals to be received at least until synchronisation gets active.• Initialisation: 0 (≡ 1)
	Note: The settings 0 and 1 are functionally identical. If 0 or 1 is set, at least one pulse is required in order that the synchronisation gets active.			

Parameter	Possible settings	Info
C01075/1		Synchronisation mode - mark correction
	0 Synchronisation inactive	Lenze setting
	1 Permanent synchronisation without enable via the <i>bZeroPulse</i> input • Correction is executed over the shortest possible path.	The synchronisation only takes place after 2 setpoint pulses have been received at the <i>bSetTPReceived</i> input. (required pulse order: set-actual-set)
	2 Permanent synchronisation only with enable via the <i>bZeroPulse</i> input • When <i>bZeroPulse</i> is set to TRUE, a permanent zero pulse/touch probe synchronisation is executed. • Correction is executed over the shortest possible path.	
	10 One-time synchronisation • An angular difference is compensated over the shortest possible path.	
	11 One-time synchronisation • An angle difference is compensated in CW direction.	
	12 One-time synchronisation • An angular difference is compensated in CCW direction.	
	13 One-time synchronisation • An angular difference is compensated over the shortest possible path.	Synchronisation takes place after the first setpoint pulse has been received at the <i>bSetTPReceived</i> input and/or actual value pulse at the <i>bActTPReceived</i> input. (Required clock sequence: Set/actual or actual/set)

19.1.77.1 Master value rail/slave cascade

If there is only one master speed that is transmitted to all slave drives involved, e.g. via system bus (CAN), it is called master value rail.

If a slave drive takes over the master value generation for the following slave, it is called slave cascade.



[19-35] Example: Master value rail/slave cascade

19.1.77.2 Setpoint conditioning with stretch factor and gearbox factor

Stretch factor

The stretch factor is required for the "speed synchronism via master value cascade" mode. It defines the ratio the slave drive is to be running with regard to its master value.

- The stretch factor evaluates the setpoint at the *nSet_v* input.
- The stretch factor must be selected via the *wGainNum* and *wGainDenom* inputs in the form of numerators and denominators.
- The result is provided at the *nSetGain_v* output.
 - Scaling: $16384 \equiv 15000 \text{ rpm}$

$$\text{nSetGain_v} = \text{nSet_v} \cdot \frac{\text{wGainNum}}{\text{wGainDenom}}$$

- If the stretch factor is 1 and the gearbox factors are selected correctly, the circumferential speeds of the rolls for master and slave 1 are identical in the example shown in the illustration [19-35].

Gearbox factor

The gearbox factor defines the gearbox ratio of the drive. Enter the ratio of the drive.

- The gearbox factor evaluates the setpoint at the $nSet_v$ input multiplied by the stretch factor.
- The gearbox factor has to be selected via the inputs $wGearNum$ and $wGearDenom$ in the form of numerators and denominators.
- The bit 0 in [C01073/1](#) serves to simply deactivate the evaluation with the gearbox factor (does not apply to the speed outputs $nSetGain_v$, $nSetGearTrim_v$ and $nSetGearTrim_a$).
- The result is provided at the outputs $nSetGearTrim_v$ and $nSetGearTrim_a$.
 - Scaling $nSetGearTrim_v$: 16384 \equiv 15000 rpm
 - Scaling $nSetGearTrim_a$: 16384 \equiv 100 % reference speed ([C00011](#))

$$nSetGearTrim_v = nSet_v \cdot \text{Stretch factor} \cdot \frac{wGearNum}{wGearDenom}$$

$$nSetGearTrim_v = nSet_v \cdot \frac{wGainNum}{wGainDenom} \cdot \frac{wGearNum}{wGearDenom}$$

$$nSetGearTrim_a = nSet_v \cdot \frac{C00011}{15000} \cdot \frac{wGainNum}{wGainDenom} \cdot \frac{wGearNum}{wGearDenom}$$

**Note!**

The intermediate results and the result of the evaluation are limited to ± 32767 increments (16 bits).

19.1.77.3 Processing correction values**Speed trimming**

Speed trimming enables the connection of correction values, e.g. from a higher-level control loop. This permits an acceleration or deceleration of the drive.

The correction value can either be transmitted as an analog value via the $nSpeedTrim_a$ input or for exact speed trimming as a speed value via the $nSpeedTrim_v$ input.

- Scaling $nSpeedTrim_a$: 16384 \equiv 100 % reference speed ([C00011](#))
- Scaling $nSpeedTrim_v$: 16384 \equiv 15000 rpm

Speed variations of the trimming values are specified via the SpeedTrim ramp ([C01069/1](#)).

Angular trimming

Angular trimming enables the rotor position to be put forward or back with regard to the setpoint (the drive is leading or lagging).

The correction value must have to be defined in [increments] via the *nPositionTrimming* input. It is internally added to the angle setpoint.

- Scaling: A motor revolution is mapped with 65536 increments or steps.
- The maximum angular trimming amounts to $\pm\frac{1}{2}$ motor revolution (± 32767 increments).
- When analog values are selected: 100 % $\equiv \frac{1}{4}$ motor revolution $\equiv 16384$ increments.
- The setting range can be extended with the multiplier to be set in [C01072/1](#).

Angular offset

The *dnPosOffset_p* input serves to define a permanent angular offset for the setpoint of the drive.

- An adjustment takes place via the following error (*dnDeltaPos_p*) output and via the speed change at the *nSpeedSetOut_v* output.
- Example: A angular offset of 90° is to be set on the load side with a gearbox ratio of 3.8147:

$$\text{dnPosOffset_p} = \frac{90^\circ}{360^\circ} \cdot 65536 \left[\frac{\text{Increments}}{\text{Motor revolution}} \right] \cdot 3.8147 = 62500 \text{ [increments]}$$



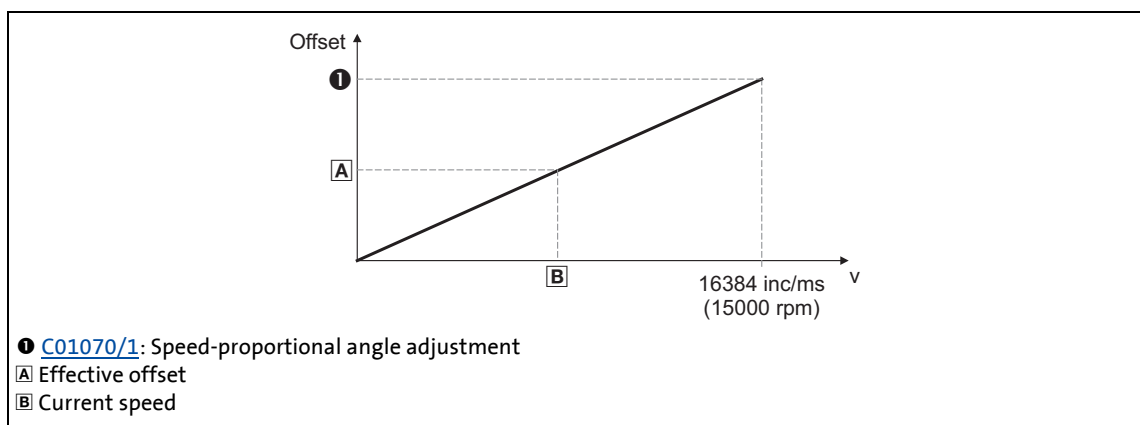
Stop!

Change the angular offset only step by step as the FB does not contain a ram generator for preventing torque impulses.

Speed-proportional angle adjustment

The speed-proportional angle adjustment enables a leading or lagging of the angle with increasing speed and serves to compensate dead times and transmission times.

The correction value selected in [C01070/1](#). in [increments] refers to a speed of 15000 rpm (linear relationship):



[19-36] Connection between offset/speed

19.1.77.4 Synchronising slave drive to master drive

If an angular synchronism of the drives is required (e.g. in printing units), the slave drives must be positioned to the master position since the FB **L_DFSET** as a master value can only receive and process one relative signal. The FB **L_DFSET** receives the master value via a real-time capable MotionBus as the system bus (CAN).



Tip!

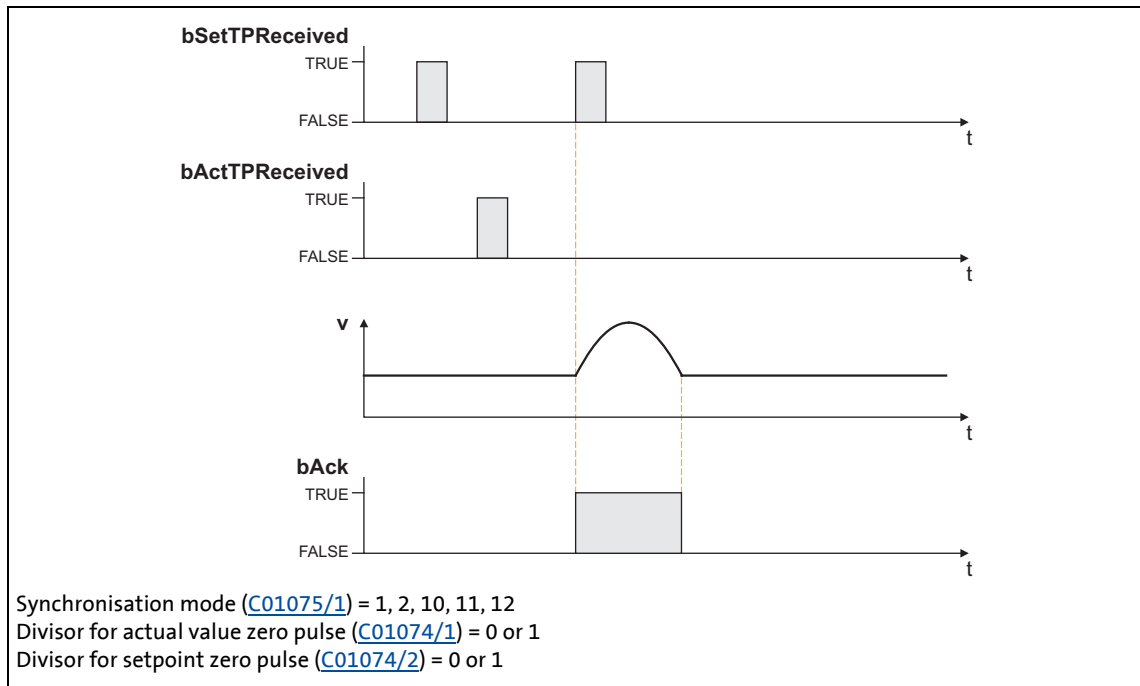
The 8400 TopLine serves to realise very easily a master value cascade via the cross communication with the [Axis bus](#) of the drives.

For synchronisation purposes, the slave drive is informed cyclically or once about its drive position by a pulse generated by the master drive. This pulse is either the zero pulse of the master feedback or the edge of a touch probe sensor. Moreover, a pulse must be generated by the slave drive. Only if the FB **L_DFSET** receives both signals, it can execute a synchronisation.

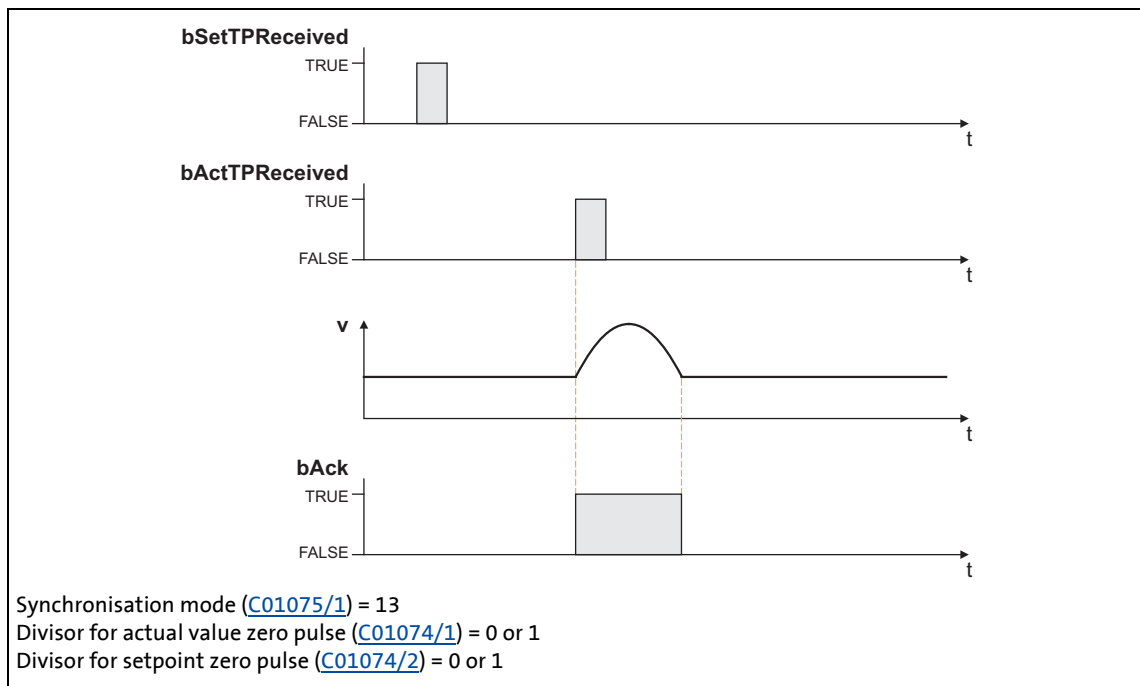
Synchronisation mode - mark correction

For synchronisation, the following modes are available in [C01075/1](#) :

Mode	Info
0 Synchronisation inactive	Lenze setting
1 Permanent synchronisation without enable via the <i>bZeroPulse</i> input <ul style="list-style-type: none"> Correction is executed over the shortest possible path. 	The synchronisation only takes place after 2 setpoint pulses have been received at the <i>bSetTPReceived</i> input. (required pulse order: set-actual-set) • See illustration [19-37] . (1507)
2 Permanent synchronisation only with enable via the <i>bZeroPulse</i> input <ul style="list-style-type: none"> When <i>bZeroPulse</i> is set to TRUE, a permanent zero pulse/touch probe synchronisation is executed. Correction is executed over the shortest possible path. 	
10 One-time synchronisation only with enable via the <i>bZeroPulse</i> input <ul style="list-style-type: none"> An angular difference is compensated over the shortest possible path. 	
11 One-time synchronisation only with enable via the <i>bZeroPulse</i> input <ul style="list-style-type: none"> An angle difference is compensated in CW direction. 	
12 One-time synchronisation only with enable via the <i>bZeroPulse</i> input <ul style="list-style-type: none"> An angular difference is compensated in CCW direction. 	Synchronisation takes place after the first setpoint pulse has been received at the <i>bSetTPReceived</i> input and/or actual value pulse at the <i>bActTPReceived</i> input. (Required clock sequence: Set/actual or actual/set) • See illustration [19-38] . (1507)
13 One-time synchronisation only with enable via the <i>bZeroPulse</i> input <ul style="list-style-type: none"> An angular difference is compensated over the shortest possible path. 	



[19-37] Synchronisation process in the modes 1, 2, 10, 11, 12



[19-38] Synchronisation process in mode 13

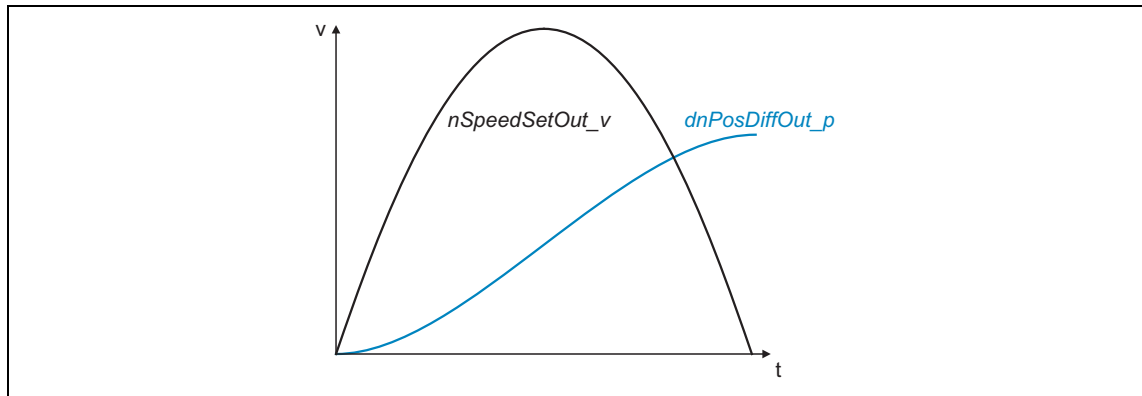
Compensation process

At the input of the second set or actual touch probe pulse, the difference between master and slave position is detected which is then provided via the *nSpeedSetOut_v* speed output and equivalently as position at .

In [C01073/1](#), the following bit coded settings can be made for the compensation procedure:

Setting	Info
Bit 1 Angle correction with polynomial	<p>If this bit is set (Lenze setting), the compensating movement is rounded by polynomial.</p> <ul style="list-style-type: none"> The angle error to be compensated is limited to ± 1073741823 increments due to the system. This applies in general when the L_DFSET_1 carries out the compensation. The maximum compensating speed can be set in C1069/2. When "0" is set in C1069/2 if activated in C01075/1, the angle error is measured and output to <i>dnPosDiffOut_p</i>.
Bit 2 External angle correction <small>From version 13.00.00</small>	<p>If this bit is set, the FB L_DFSET_1 does not compensate any angle errors.</p> <ul style="list-style-type: none"> Every time the angle errors have been measured, the angular difference is output to <i>dnPosDiffOut_p</i>. In addition, a FALSE/TRUE edge is output to <i>bAck</i>. This signal serves to trigger an external profile generator which compensates the angular offset via a speed profile additionally.

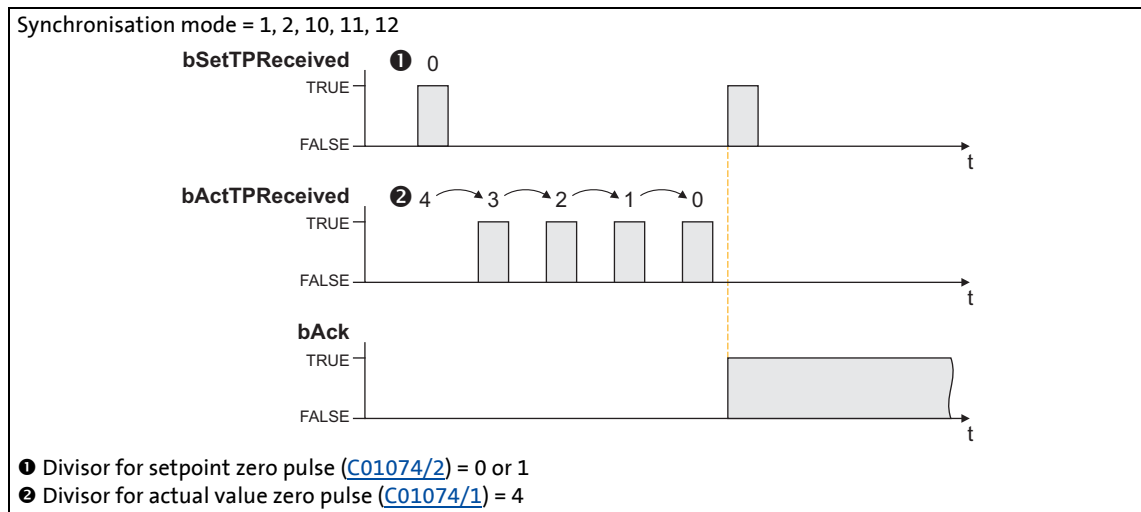
The following illustration shows a compensating process after the marks have been detected. The speed is added here as a parabola to the line speed. (The scaling in this diagram does not correspond to reality)



[19-39] Example: Compensation process

19.1.77.5 Masking out touch probe signals

When passing-through material is used, e.g. printed foil, touch probe initiators may respond several times per cycle. For suppressing such "interference pulses", count values can be selected in [C01074/1](#) and [C01074/2](#) that are decremented when the touch probe pulse has been received. Only when the counter content is "0", the synchronisation will be enabled. Please note that the settings 0 and 1 are functionally identical. If 0 or 1 is set, at least one pulse is required to activate the synchronisation.



[19-40] Synchronisation process in the modes 1, 2, 10, 11, 12 with a masking out of the touch probe pulses

19.1.77.6 Process monitoring functions

Following error

The *bFollowingErr* status output is set to TRUE if the drive cannot follow its setpoint angle.

- Possible causes:
 - The centrifugal mass is too high for the set acceleration or deceleration time.
 - The torque limit has been reached (load torque > drive torque).
- Remedy: Unload drive or increase torque limit at the servo controller (if the power limits of the controller have not yet been reached).

The following error is derived from the angular difference of the setpoint angle integrator minus the actual angle integrator. The comparison value (following error limit) can be set in [C01071/1](#).

Angle controller overflow (*bPosOverflow* = TRUE)

The *bPosOverflow* status output is set to TRUE if the angular difference that can be displayed device-internally has been exceeded. Home positions get lost here.



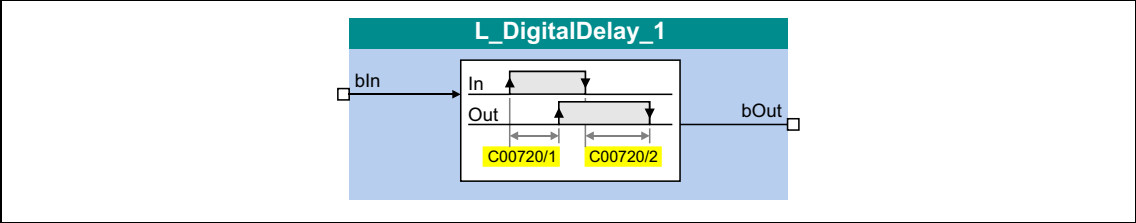
Tip!

If an error response is to be triggered in case of a following error and/or angle controller overflow, connect the corresponding status output with a free *bSetError* input of the SB [LS_SetError_2](#) and parameterise the requested error response for this input in [C00581](#).

19.1.78 L_DigitalDelay_1

This FB delays binary signals.

- ON and OFF-deceleration can be parameterised separately.



Inputs

Identifier	Data type	Information/possible settings
bIn	BOOL	Input signal

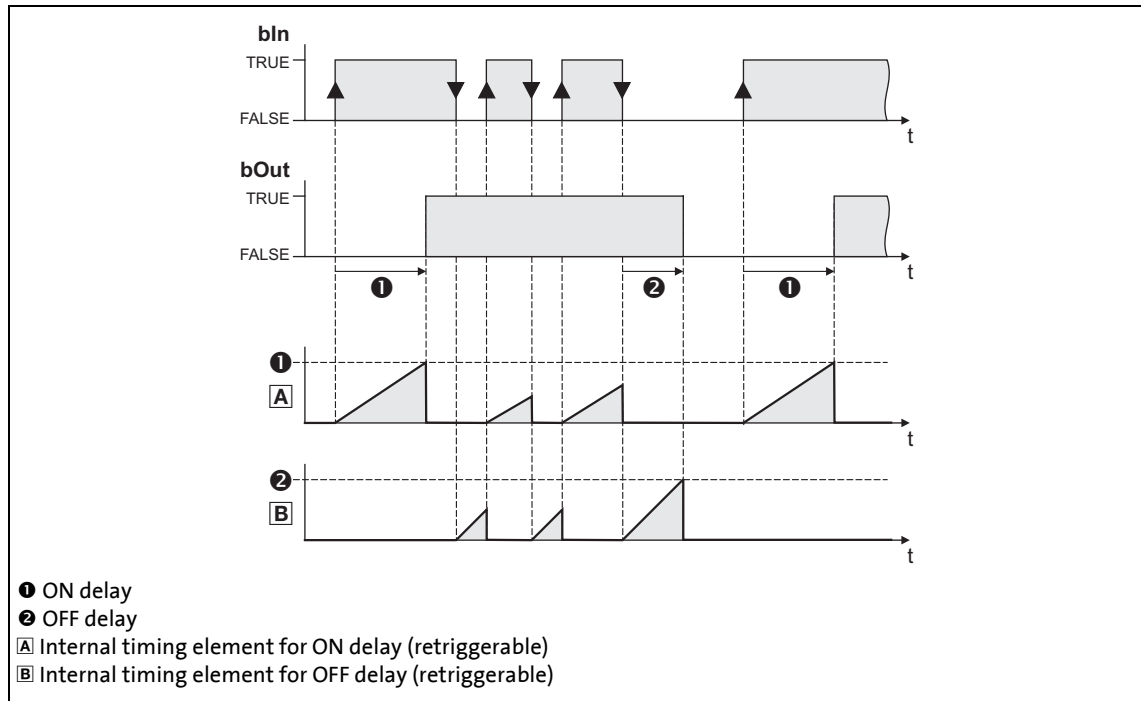
Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal (time-delayed input signal)

Parameter

Parameter	Possible settings			Info
C00720/1	0.000	s	3600.000	ON-deceleration • Lenze setting: 0.000 s
C00720/2	0.000	s	3600.000	OFF-deceleration • Lenze setting: 0.000 s

Function

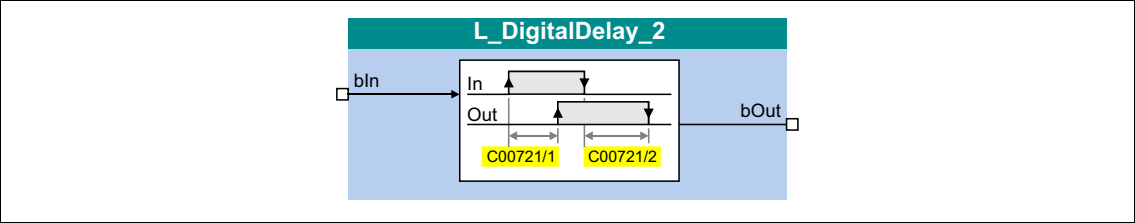


1. A FALSE-TRUE edge at bIn starts the internal timing element for the ON delay.
2. After the defined ON delay, the input signal bIn is output at $bOut$.
3. A TRUE-FALSE edge at bIn starts the internal timing element for the OFF delay.
4. After the defined OFF delay, the input signal bIn is output at $bOut$.

19.1.79 L_DigitalDelay_2

This FB delays binary signals.

- ON and OFF-deceleration can be parameterised separately.



Inputs

Identifier	Data type	Information/possible settings
bIn	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal (time-delayed input signal)

Parameter

Parameter	Possible settings			Info
C00721/1	0.000	s	3600.000	ON-deceleration • Lenze setting: 0.000 s
C00721/2	0.000	s	3600.000	OFF-deceleration • Lenze setting: 0.000 s

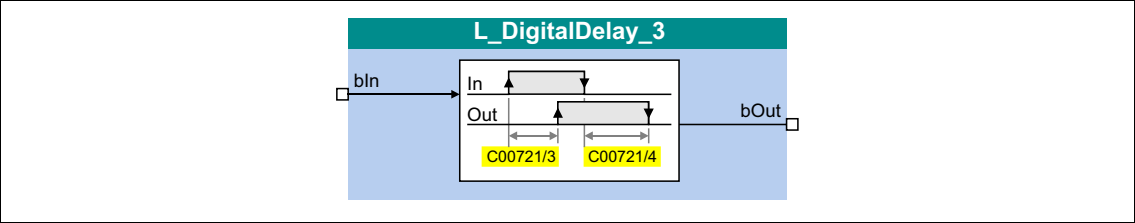


For a detailed functional description see [L_DigitalDelay_1](#).

19.1.80 L_DigitalDelay_3

This FB delays binary signals.

- ON and OFF-deceleration can be parameterised separately.



Inputs

Identifier	Data type	Information/possible settings
bIn	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal (time-delayed input signal)

Parameter

Parameter	Possible settings			Info
C00721/3	0.000	s	3600.000	ON-deceleration • Lenze setting: 0.000 s
C00721/4	0.000	s	3600.000	OFF-deceleration • Lenze setting: 0.000 s

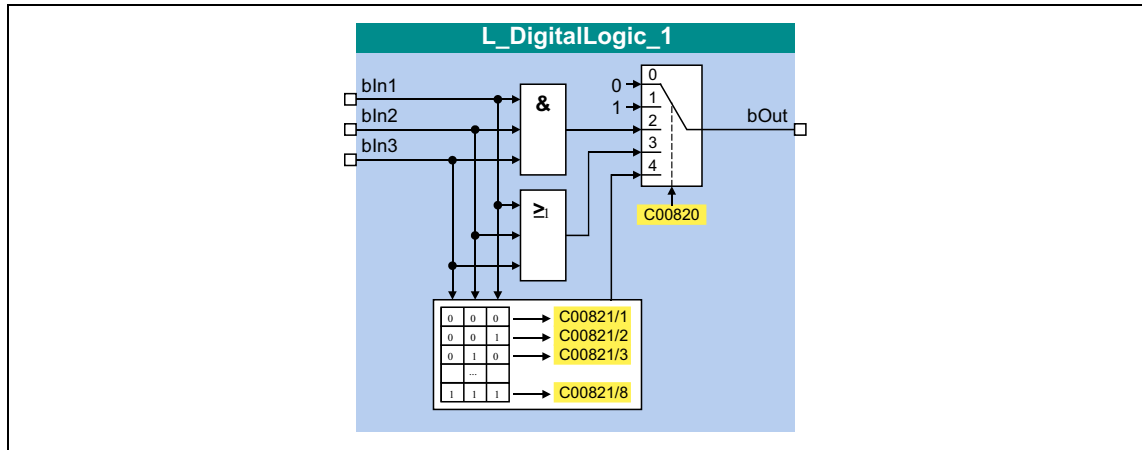


For a detailed functional description see [L_DigitalDelay_1](#).

19.1.81 L_DigitalLogic_1

This FB provides a binary output signal created by a logic operation of the input signals. Optionally, one of the constant binary values independent from the input signals can be output.

- Output of a constant binary value
- AND operation of the inputs
- OR operation of the inputs
- Output depending on the combination of the input signals



Inputs

Identifier	Data type	Information/possible settings
bIn1	BOOL	Input signal 1
bIn2	BOOL	Input signal 2
bIn3	BOOL	Input signal 3

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal

Parameter

Parameter	Possible settings	Info
C00820		Function selection
	0 "0"	Constant value "FALSE"
	1 "1"	Constant value "TRUE"
	2 $bOut = bIn1 \wedge bIn2 \wedge bIn3$	AND operation
	3 $bOut = bIn1 \vee bIn2 \vee bIn3$	OR operation
	4 $bOut = f(\text{truth table})$	The output value depends on the truth table parameterised in C00821/1...8

Parameter	Possible settings	Info
C00821/1...8		Truth table for function "4: bOut = f (truth table)" <ul style="list-style-type: none"> • Each of the eight possible input combinations can be assigned to the output value FALSE or TRUE. • For an application example see the following section.
	0 FALSE	
	1 TRUE	

Function "4: bOut = f (Truth table)"

When the function "4: bOut = f (truth table)" is selected in [C00820](#), the output value *bOut* depends on the truth table parameterised in [C00821/1...8](#).

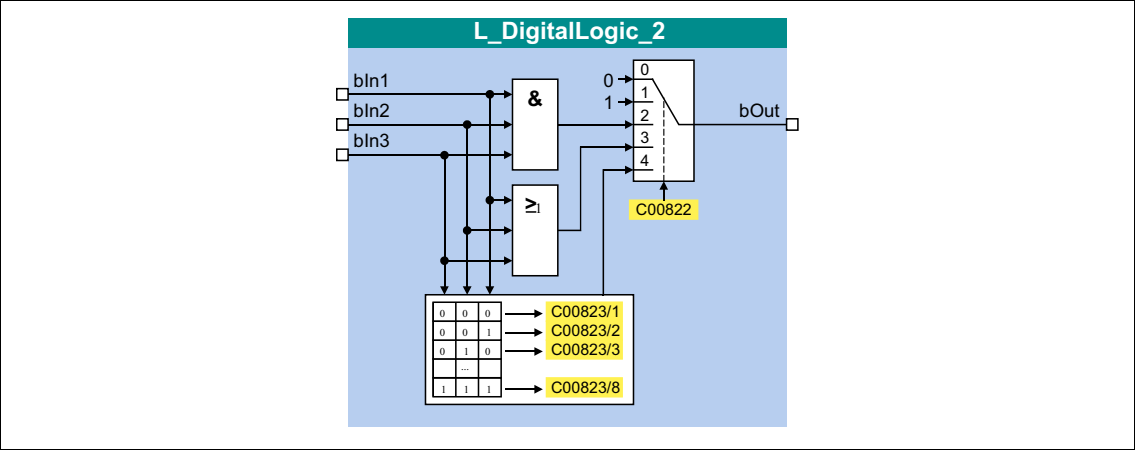
The following table shows which setting may be required in [C00821/1...8](#) to realise the logic operations NAND, NOR, XOR and XNOR:

Input signals			Output <i>bOut</i>	Parameter setting for logic operation:			
<i>bIn3</i>	<i>bIn2</i>	<i>bIn1</i>		NAND	NOR	XOR	XNOR
0	0	0	C00821/1 =	1	1	0	1
0	0	1	C00821/2 =	1	0	1	0
0	1	0	C00821/3 =	1	0	1	0
0	1	1	C00821/4 =	1	0	0	1
1	0	0	C00821/5 =	1	0	1	0
1	0	1	C00821/6 =	1	0	0	1
1	1	0	C00821/7 =	1	0	0	1
1	1	1	C00821/8 =	0	0	0	1

19.1.82 L_DigitalLogic_2

This FB provides a binary output signal created by a logic operation of the input signals. Optionally, one of the constant binary values independent from the input signals can be output.

- Output of a constant binary value
- AND operation of the inputs
- OR operation of the inputs
- Output depending on the combination of the input signals



Inputs

Identifier	Data type	Information/possible settings
bIn1	BOOL	Input signal 1
bIn2	BOOL	Input signal 2
bIn3	BOOL	Input signal 3

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal

Parameter

Parameter	Possible settings	Info
C00822		Function selection
	0 "0"	Constant value "FALSE"
	1 "1"	Constant value "TRUE"
	2 $bOut = bIn1 \wedge bIn2 \wedge bIn3$	AND operation
	3 $bOut = bIn1 \vee bIn2 \vee bIn3$	OR operation
	4 $bOut = f(\text{truth table})$	The output value depends on the truth table parameterised in C00823/1...8

Parameter	Possible settings	Info
C00823/1...8		Truth table for function "4: bOut = f (truth table)" <ul style="list-style-type: none"> • Each of the eight possible input combinations can be assigned to the output value FALSE or TRUE. • For an application example see the following section.
	0 FALSE	
	1 TRUE	

Function "4: bOut = f (Truth table)"

When the function "4: bOut = f (truth table)" is selected in [C00822](#), the output value *bOut* depends on the truth table parameterised in [C00823/1...8](#).

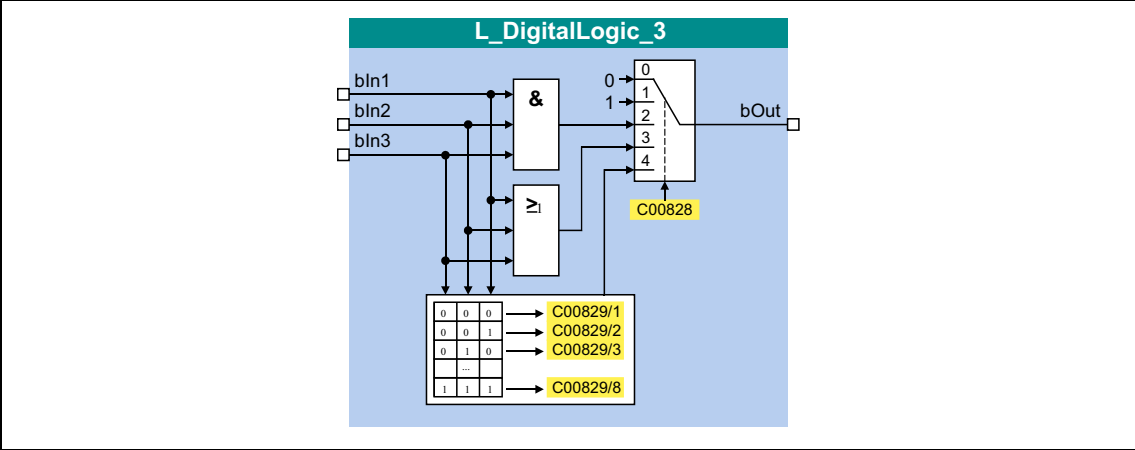
The following table shows which setting may be required in [C00823/1...8](#) to realise the logic operations NAND, NOR, XOR and XNOR:

Input signals			Output <i>bOut</i>	Parameter setting for logic operation:			
<i>bIn3</i>	<i>bIn2</i>	<i>bIn1</i>		NAND	NOR	XOR	XNOR
0	0	0	C00823/1 =	1	1	0	1
0	0	1	C00823/2 =	1	0	1	0
0	1	0	C00823/3 =	1	0	1	0
0	1	1	C00823/4 =	1	0	0	1
1	0	0	C00823/5 =	1	0	1	0
1	0	1	C00823/6 =	1	0	0	1
1	1	0	C00823/7 =	1	0	0	1
1	1	1	C00823/8 =	0	0	0	1

19.1.83 L_DigitalLogic_3

This FB provides a binary output signal created by a logic operation of the input signals. Optionally, one of the constant binary values independent from the input signals can be output.

- Output of a constant binary value
- AND operation of the inputs
- OR operation of the inputs
- Output depending on the combination of the input signals



Inputs

Identifier	Data type	Information/possible settings
bIn1	BOOL	Input signal 1
bIn2	BOOL	Input signal 2
bIn3	BOOL	Input signal 3

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal

Parameter

Parameter	Possible settings	Info
C00828		Function selection
	0 "0"	Constant value "FALSE"
	1 "1"	Constant value "TRUE"
	2 $bOut = bIn1 \wedge bIn2 \wedge bIn3$	AND operation
	3 $bOut = bIn1 \vee bIn2 \vee bIn3$	OR operation
	4 $bOut = f(\text{truth table})$	The output value depends on the truth table parameterised in C00829/1...8

Parameter	Possible settings	Info
C00829/1...8		Truth table for function "4: bOut = f (truth table)" <ul style="list-style-type: none"> • Each of the eight possible input combinations can be assigned to the output value FALSE or TRUE. • For an application example see the following section.
	0 FALSE	
	1 TRUE	

Function "4: bOut = f (Truth table)"

When the function "4: bOut = f (truth table)" is selected in [C00828](#), the output value *bOut* depends on the truth table parameterised in [C00829/1...8](#).

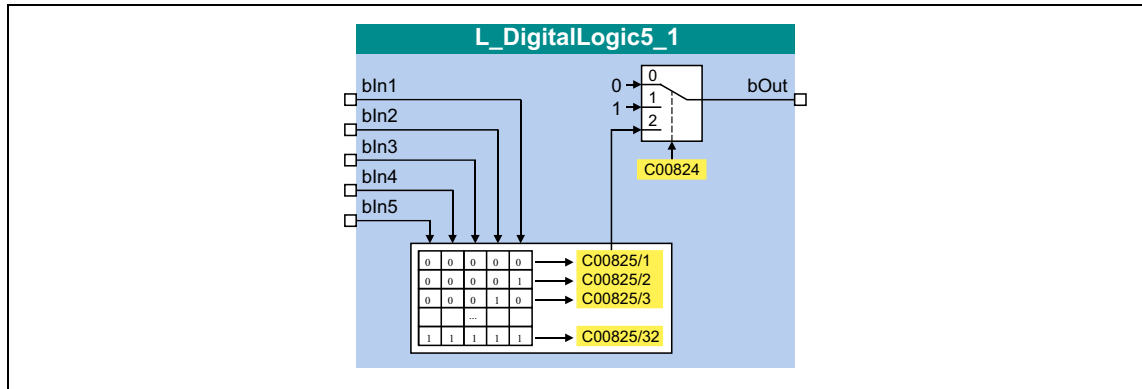
The following table shows which setting may be required in [C00829/1...8](#) to realise the logic operations NAND, NOR, XOR and XNOR:

Input signals			Output <i>bOut</i>	Parameter setting for logic operation:			
<i>bIn3</i>	<i>bIn2</i>	<i>bIn1</i>		NAND	NOR	XOR	XNOR
0	0	0	C00829/1 =	1	1	0	1
0	0	1	C00829/2 =	1	0	1	0
0	1	0	C00829/3 =	1	0	1	0
0	1	1	C00829/4 =	1	0	0	1
1	0	0	C00829/5 =	1	0	1	0
1	0	1	C00829/6 =	1	0	0	1
1	1	0	C00829/7 =	1	0	0	1
1	1	1	C00829/8 =	0	0	0	1

19.1.84 L_DigitalLogic5_1

This FB provides a binary output signal created by a logic operation of the input signals. Optionally, one of the constant binary values independent from the input signals can be output.

- Output of a constant binary value
- Output depending on the combination of the input signals



Inputs

Identifier	Data type	Information/possible settings
bln1 ... bln5	BOOL	Input signal 1 ... 5

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal

Parameter

Parameter	Possible settings	Info
C00824		Function selection
	0 "0"	Constant value "FALSE"
	1 "1"	Constant value "TRUE"
	2 bOut = f (truth table)	The output value depends on the parameterised truth table
C00825	see truth table	Truth table Each of the 32 possible input combinations can be assigned to the output value FALSE or TRUE.

Truth table for C00824 = 4

bln5	bln4	bln3	bln2	bln1	Output signal bOut
FALSE	FALSE	FALSE	FALSE	FALSE	C00825/1 (FALSE or TRUE)
FALSE	FALSE	FALSE	FALSE	TRUE	C00825/2 (FALSE or TRUE)

bIn5	bIn4	bIn3	bIn2	bIn1	Output signal bOut
FALSE	FALSE	FALSE	TRUE	FALSE	C00825/3 (FALSE or TRUE)
...					C00825/... (FALSE or TRUE)
TRUE	TRUE	TRUE	FALSE	TRUE	C00825/30 (FALSE or TRUE)
TRUE	TRUE	TRUE	TRUE	FALSE	C00825/31 (FALSE or TRUE)
TRUE	TRUE	TRUE	TRUE	TRUE	C00825/32 (FALSE or TRUE)

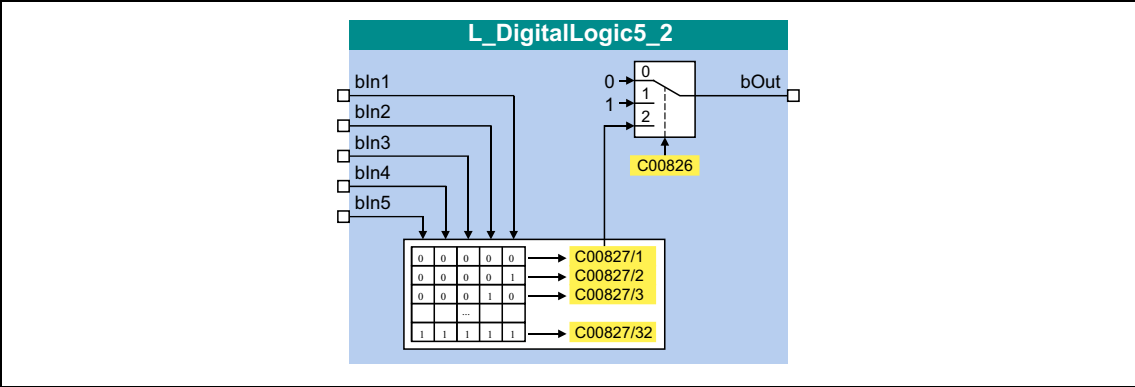
Example: If in case of the signal combination *bIn1* = TRUE, *bIn2* = FALSE, *bIn3* = TRUE, *bIn4* = TRUE and *bIn5* = TRUE, the output signal *bOut* is to be = TRUE, [C00825/30](#) must be set to "TRUE":

bIn5	bIn4	bIn3	bIn2	bIn1	Output signal bOut
TRUE	TRUE	TRUE	FALSE	TRUE	C00825/30 (TRUE)

19.1.85 L_DigitalLogic5_2

This FB provides a binary output signal created by a logic operation of the input signals. Optionally, one of the constant binary values independent from the input signals can be output.

- Output of a constant binary value
- Output depending on the combination of the input signals



Inputs

Identifier	Data type	Information/possible settings
bln1 ... bln5	BOOL	Input signal 1 ... 5

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal

Parameter

Parameter	Possible settings	Info
C00826		Function selection
	0 "0"	Constant value "FALSE"
	1 "1"	Constant value "TRUE"
	2 bOut = f (truth table)	The output value depends on the parameterised truth table
C00827	see truth table	Truth table Each of the 32 possible input combinations can be assigned to the output value FALSE or TRUE.

Truth table for C00826 = 4

bln5	bln4	bln3	bln2	bln1	Output signal bOut
FALSE	FALSE	FALSE	FALSE	FALSE	C00827/1 (FALSE or TRUE)
FALSE	FALSE	FALSE	FALSE	TRUE	C00827/2 (FALSE or TRUE)

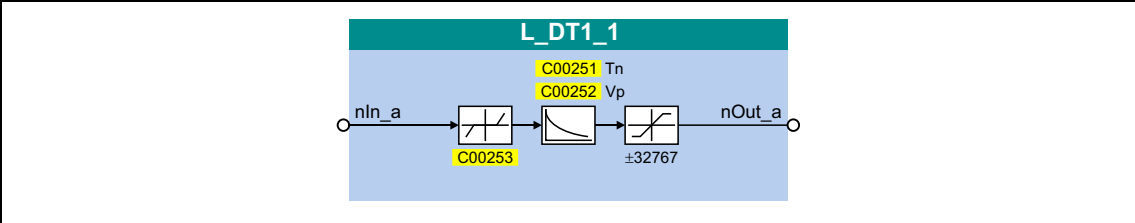
bIn5	bIn4	bIn3	bIn2	bIn1	Output signal bOut
FALSE	FALSE	FALSE	TRUE	FALSE	C00827/3 (FALSE or TRUE)
...					C00827/... (FALSE or TRUE)
TRUE	TRUE	TRUE	FALSE	TRUE	C00827/30 (FALSE or TRUE)
TRUE	TRUE	TRUE	TRUE	FALSE	C00827/31 (FALSE or TRUE)
TRUE	TRUE	TRUE	TRUE	TRUE	C00827/32 (FALSE or TRUE)

Example: If in case of the signal combination *bIn1* = TRUE, *bIn2* = FALSE, *bIn3* = TRUE, *bIn4* = TRUE and *bIn5* = TRUE, the output signal *bOut* is to be = TRUE, [C00827/30](#) must be set to "TRUE":

bIn5	bIn4	bIn3	bIn2	bIn1	Output signal bOut
TRUE	TRUE	TRUE	FALSE	TRUE	C00827/30 (TRUE)

19.1.86 L_DT1_1

This FB differentiates signals. The function block can, for instance, be used to apply an acceleration (dv/dt).



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal

Outputs

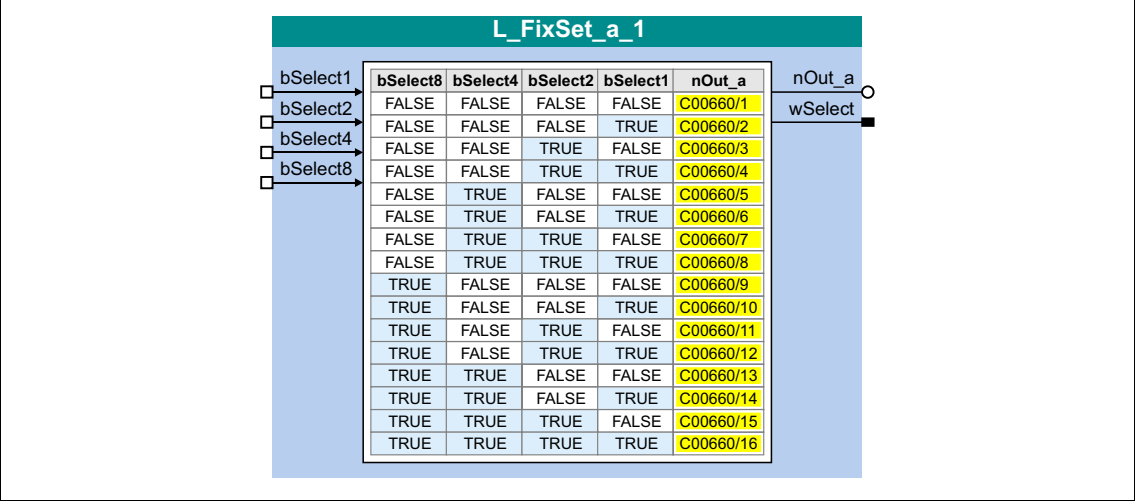
Identifier	Data type	Value/meaning
nOut_a	INT	Output signal

Parameter

Parameter	Possible settings			Info
C00251	10	ms	5000	Time constant Tn • Lenze setting: 1000 ms
C00252	-320.00		320.00	Gain factor Vp • Lenze setting: 1.00
C00253	Note: The most significant bit determines the sign of the value, the remaining bits determine the numerical value.			Selection of sensitivity • Depending on the selection, the number of indicated higher-order bits is evaluated. • Lenze setting: 15 bit
	1	15 bits		Bit 0 ... bit 14 are evaluated
	2	14 bits		Bit 0 ... bit 13 are evaluated
	3	13 bits		Bit 0 ... bit 12 are evaluated
	4	12 bits		Bit 0 ... bit 11 are evaluated
	5	11 Bit		Bit 0 ... bit 10 are evaluated
	6	10 Bit		Bit 0 ... bit 9 are evaluated
	7	9 Bit		Bit 0 ... bit 8 are evaluated

19.1.87 L_FixSet_a_1

This FB outputs one of 16 parameterisable analog signals. Binary coded selection of the "fixed value" to be output via the four selection inputs.



Inputs

Identifier	Data type	Information/possible settings
bSelect1 ... bSelect8	BOOL	Binary coded selection of the fixed value to be output • See truth table displayed in the FB above.

Outputs

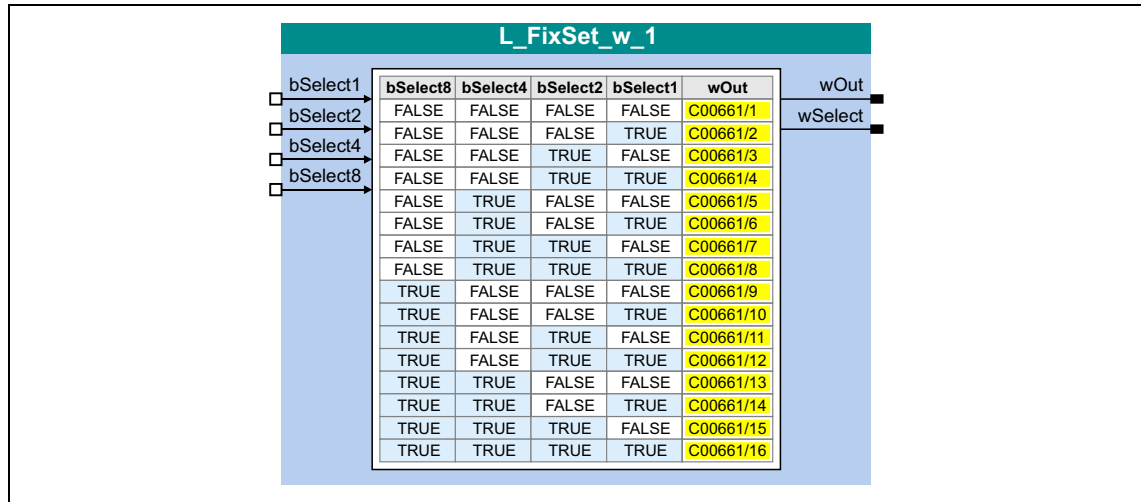
Identifier	Data type	Value/meaning
nOut_a	INT	Output of the selected fixed value
wSelect	WORD	Current selection (0 ... 15)

Parameter

Parameter	Possible settings	Info
C00660/1...16	-199.99 % 199.99	Fixed value 0 ... 15 • Lenze setting: 0.00 %

19.1.88 L_FixSet_w_1

This FB outputs one of 16 parameterisable data words. Binary coded selection of the "fixed value" to be output via the four selection inputs.



Inputs

Identifier	Data type	Information/possible settings
bSelect1 ... bSelect8	BOOL	Binary coded selection of the fixed value to be output • See truth table displayed in the FB above.

Outputs

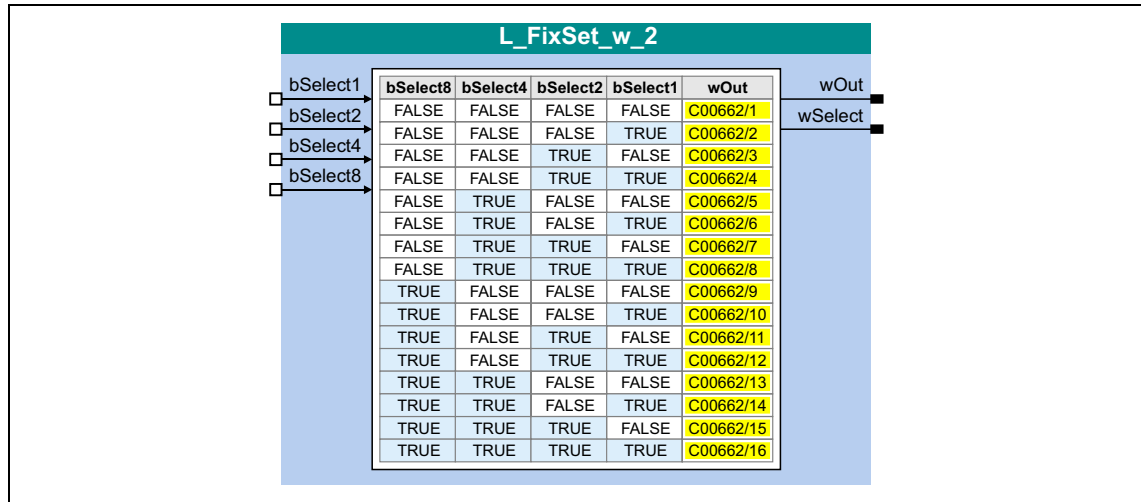
Identifier	Data type	Value/meaning
wOut	WORD	Output of the selected fixed value
wSelect	WORD	Current selection (0 ... 15)

Parameter

Parameter	Possible settings	Info
C00661/1...16	0	65535 Fixed values 0 ... 15 • Lenze setting: 0

19.1.89 L_FixSet_w_2

This FB outputs one of 16 parameterisable data words. Binary coded selection of the "fixed value" to be output via the four selection inputs.



Inputs

Identifier	Data type	Information/possible settings
bSelect1 ... bSelect8	BOOL	Binary coded selection of the fixed value to be output • See truth table displayed in the FB above.

Outputs

Identifier	Data type	Value/meaning
wOut	WORD	Output of the selected fixed value
wSelect	WORD	Current selection (0 ... 15)

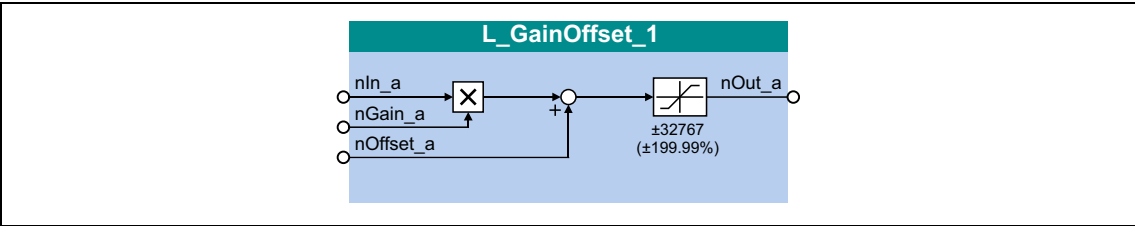
Parameter

Parameter	Possible settings	Info
C00662/1...16	0	65535 Fixed values 0 ... 15 • Lenze setting: 0

19.1.90 L_GainOffset_1

This FB can amplify an analog input signal and then add an offset to it. Preferably to be interconnected directly after the analog input terminals.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Gain and offset are selected via FB inputs.
- The value provided at the *nOut_a* output is internally limited to $\pm 199.99\%$.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal <ul style="list-style-type: none">• Scaling: 16384 \equiv 100 %
nGain_a	INT	Gain factor <ul style="list-style-type: none">• Scaling: 16384 \equiv 100 %• 199.99 % \approx 2
nOffset_a	INT	Offset <ul style="list-style-type: none">• Scaling: 16384 \equiv 100 %

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal <ul style="list-style-type: none">• Internal limitation to $\pm 199.99\%$

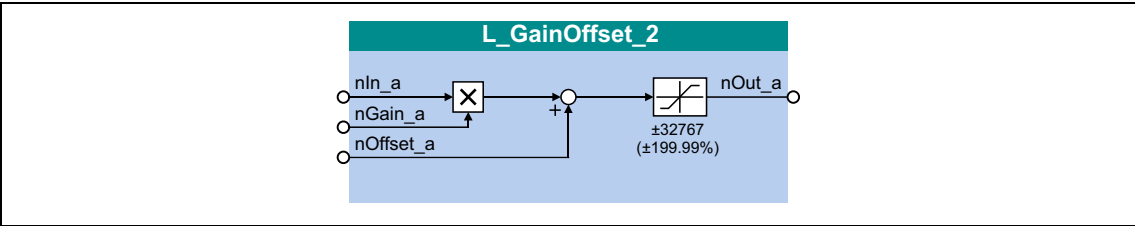
Function

$$nOut_a = (nIn_a \cdot \text{Gain factor}) + \text{Offset}$$

19.1.91 L_GainOffset_2

This FB can amplify an analog input signal and then add an offset to it. Preferably to be interconnected directly after the analog input terminals.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Gain and offset are selected via FB inputs.
- The value provided at the *nOut_a* output is internally limited to $\pm 199.99\%$.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal <ul style="list-style-type: none">• Scaling: 16384 \equiv 100 %
nGain_a	INT	Gain factor <ul style="list-style-type: none">• Scaling: 16384 \equiv 100 %• 199.99 % \approx 2
nOffset_a	INT	Offset <ul style="list-style-type: none">• Scaling: 16384 \equiv 100 %

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal <ul style="list-style-type: none">• Internal limitation to $\pm 199.99\%$

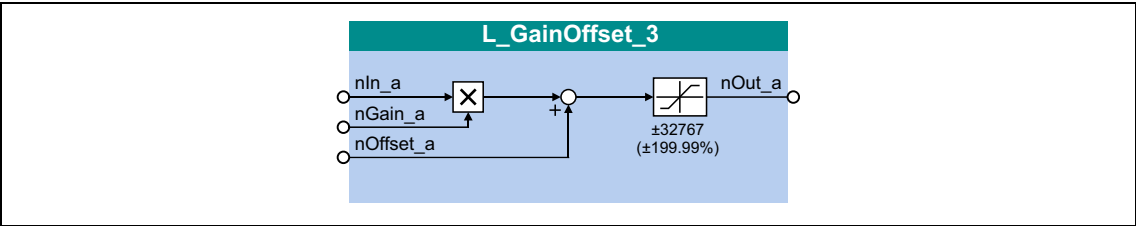
Function

$$nOut_a = (nIn_a \cdot \text{Gain factor}) + \text{Offset}$$

19.1.92 L_GainOffset_3

This FB can amplify an analog input signal and then add an offset to it. Preferably to be interconnected directly after the analog input terminals.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Gain and offset are selected via FB inputs.
- The value provided at the *nOut_a* output is internally limited to $\pm 199.99\%$.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal <ul style="list-style-type: none">• Scaling: 16384 \equiv 100 %
nGain_a	INT	Gain factor <ul style="list-style-type: none">• Scaling: 16384 \equiv 100 %• 199.99 % \approx 2
nOffset_a	INT	Offset <ul style="list-style-type: none">• Scaling: 16384 \equiv 100 %

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal <ul style="list-style-type: none">• Internal limitation to $\pm 199.99\%$

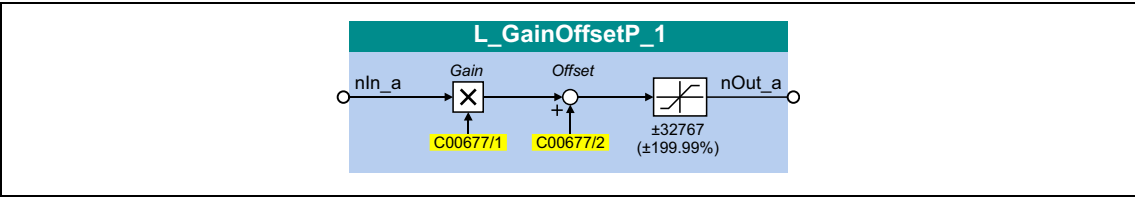
Function

$$nOut_a = (nIn_a \cdot \text{Gain factor}) + \text{Offset}$$

19.1.93 L_GainOffsetP_1

This FB can amplify an analog input signal and then add an offset to it. Preferably to be interconnected directly after the analog input terminals.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Gain and offset are selected via parameters.
- The value provided at the *nOut_a* output is internally limited to ±199.99 %.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal <ul style="list-style-type: none">• Scaling: 16384 ≙ 100 %

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal <ul style="list-style-type: none">• Internal limitation to ±199.99 %

Parameter

Parameter	Possible settings			Info
C00677/1	-199.99	%	199.99	Gain factor <ul style="list-style-type: none">• Lenze setting: 100.00 %• 199.99 % ≈ 2
C00677/2	-199.99	%	199.99	Offset <ul style="list-style-type: none">• Lenze setting: 0.00 %

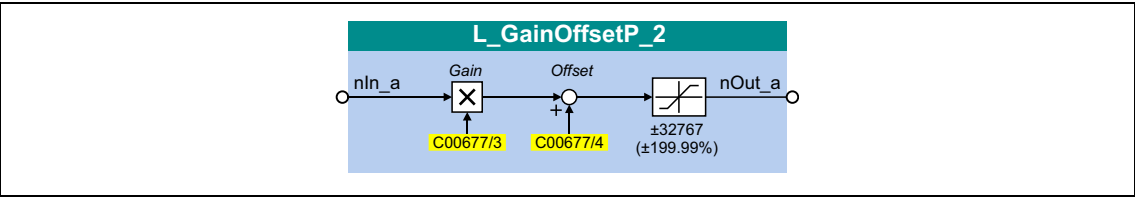
Function

$$nOut_a = (nIn_a \cdot \text{Gain factor}) + \text{Offset}$$

19.1.94 L_GainOffsetP_2

This FB can amplify an analog input signal and then add an offset to it. Preferably to be interconnected directly after the analog input terminals.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Gain and offset are selected via parameters.
- The value provided at the *nOut_a* output is internally limited to ±199.99 %.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal <ul style="list-style-type: none">• Scaling: 16384 ≙ 100 %

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal <ul style="list-style-type: none">• Internal limitation to ±199.99 %

Parameter

Parameter	Possible settings			Info
C00677/3	-199.99	%	199.99	Gain factor <ul style="list-style-type: none">• Lenze setting: 100.00 %• 199.99 % ≈ 2
C00677/4	-199.99	%	199.99	Offset <ul style="list-style-type: none">• Lenze setting: 0.00 %

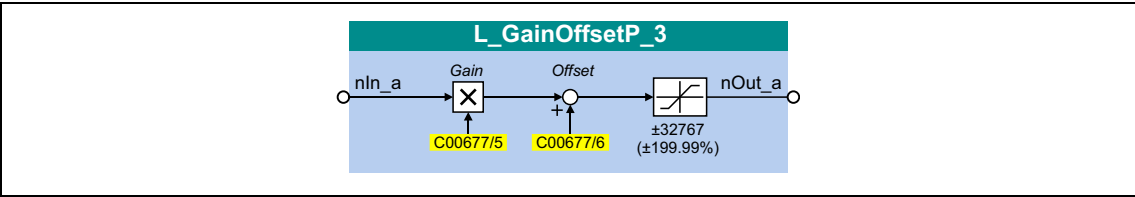
Function

$$nOut_a = (nIn_a \cdot \text{Gain factor}) + \text{Offset}$$

19.1.95 L_GainOffsetP_3

This FB can amplify an analog input signal and then add an offset to it. Preferably to be interconnected directly after the analog input terminals.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Gain and offset are selected via parameters.
- The value provided at the *nOut_a* output is internally limited to ±199.99 %.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal <ul style="list-style-type: none">• Scaling: 16384 ≡ 100 %

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal <ul style="list-style-type: none">• Internal limitation to ±199.99 %

Parameter

Parameter	Possible settings			Info
C00677/5	-199.99	%	199.99	Gain factor <ul style="list-style-type: none">• Lenze setting: 100.00 %• 199.99 % ≈ 2
C00677/6	-199.99	%	199.99	Offset <ul style="list-style-type: none">• Lenze setting: 0.00 %

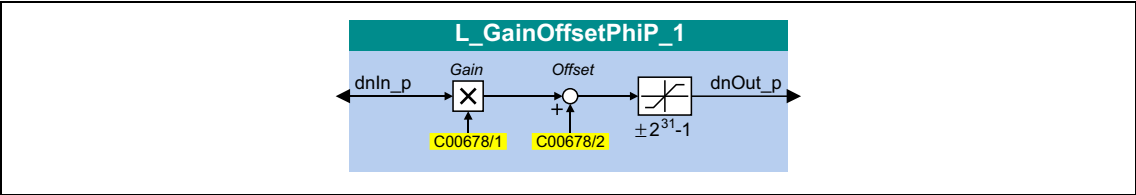
Function

$$nOut_a = (nIn_a \cdot \text{Gain factor}) + \text{Offset}$$

19.1.96 L_GainOffsetPhiP_1

This FB can amplify an angle signal and add an offset to it afterwards.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Gain and offset are selected via parameters.
- The value provided at the *dnOut_p* output is internally limited to $\pm 2^{31}-1$.



Inputs

Identifier	Data type	Information/possible settings
dnIn_p	DINT	Input signal

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal • Internal limitation to $\pm 2^{31}-1$ (± 2147483647)

Parameter

Parameter	Possible settings			Info
C00678/1	-2147483647	Incr.	2147483647	Offset • Lenze setting: 0 incr.
C00678/2	-2147483647		2147483647	Gain factor • Lenze setting: 65536

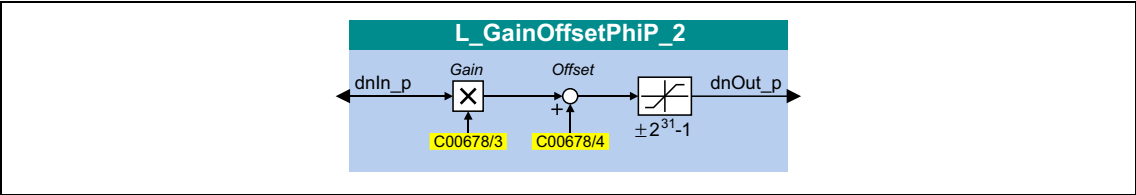
Function

$$dnOut_p = (dnIn_p \cdot \text{Gain factor}) + \text{Offset}$$

19.1.97 L_GainOffsetPhiP_2

This FB can amplify an angle signal and add an offset to it afterwards.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Gain and offset are selected via parameters.
- The value provided at the *dnOut_p* output is internally limited to $\pm 2^{31}-1$.



Inputs

Identifier	Data type	Information/possible settings
dnIn_p	DINT	Input signal

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal • Internal limitation to $\pm 2^{31}-1$ (± 2147483647)

Parameter

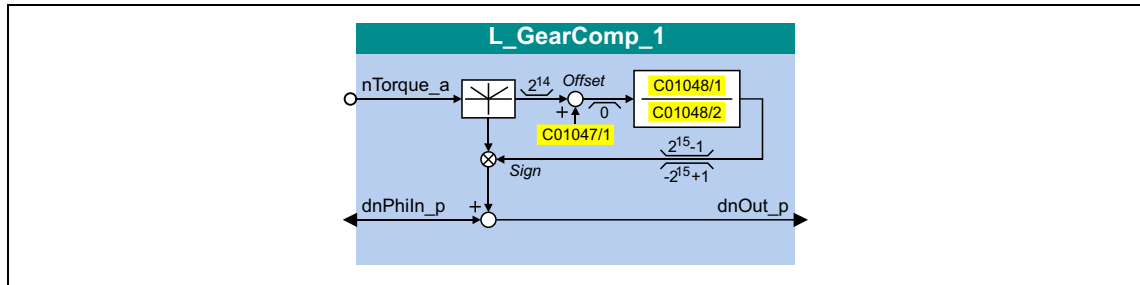
Parameter	Possible settings			Info
C00678/3	-2147483647	Incr.	2147483647	Offset • Lenze setting: 0 incr.
C00678/4	-2147483647		2147483647	Gain factor • Lenze setting: 65536

Function

$$dnOut_p = (dnIn_p \cdot \text{Gain factor}) + \text{Offset}$$

19.1.98 L_GearComp_1

This FB is used for dynamic compensation of elasticities in the drive train that arise, e.g. by elastic coupling of speed reduction gearboxes or long transmission shafts.



Inputs

Identifier	Data type	Information/possible settings
nTorque_a	INT	Torque demand • 16384 \equiv 100 %
dnPhiIn_p	DINT	Angle setpoint • 65536 increments \equiv 1 motor revolution

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Corrected angle setpoint • 65536 increments \equiv 1 motor revolution

Parameter

Parameter	Possible settings	Info
C01047/1	-16383	Offset • Static torque offset • Lenze setting: 0
C01048/1	-32767	Counter • Elastic constant • Lenze setting: 1
C01048/2	1	Denominator • Elastic constant • Lenze setting: 1

Function

Elasticity is a measure of how far the load have moved from the ideal setpoint position at motor standstill due to mechanical force effect.

- Example: "Hoist":
Due to elasticity of the mechanical transmission elements, the real position of the "hook" varies in loaded and unloaded status.
- In order to compensate errors caused by elasticity, the actual torque at the *nTorque_a* input is applied. This torque is a measure for the current load.
- The multiplication by an elasticity factor results in an angle compensation value which is added to the setpoint angle correctly signed depending on the direction of the torque. This serves to correct the false position of the load.
- The elasticity factor is selected in the form of numerator and denominator via [C01048/1](#) and [C01048/2](#).
- [C01047/1](#) serves to select a static correction value (offset).

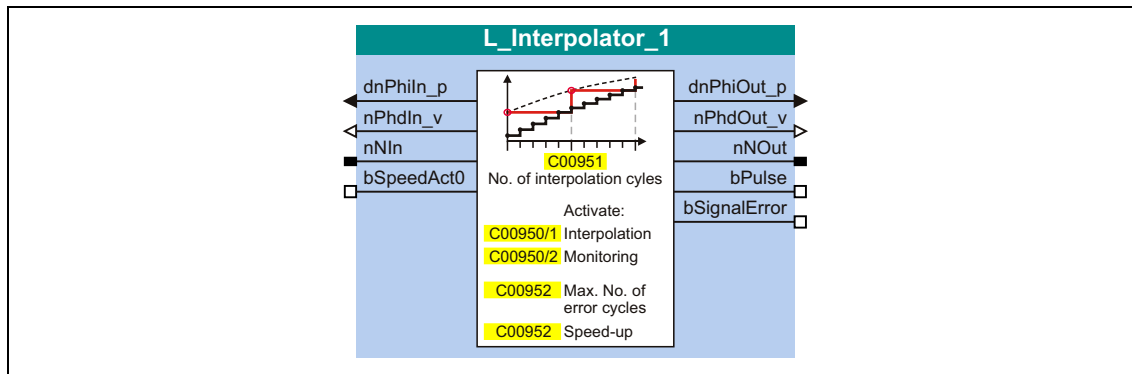


Note!

Please note that the compensation may be reversed in case of a signed numerator/denominator selection of the elasticity factor!

19.1.99 L_Interpolator_1

This FB interpolates a position setpoint and/or an analog value e.g. to compensate for larger bus transmission cycles or to continue signal characteristics if data telegrams are missing.



Inputs

Identifier	Data type	Information/possible settings
dnPhiIn_p	DINT	Position setpoint <ul style="list-style-type: none"> Is interpolated and completed when signal interpolation is activated.
nPhdIn_v	INT	Angular velocity <ul style="list-style-type: none"> Is only passed through to the <i>nPhdOut_v</i> output.
nNIn	INT	Analog value <ul style="list-style-type: none"> Is interpolated when signal interpolation is activated.
bSpeedAct0	BOOL	Input for detecting the "Current speed is zero" status <ul style="list-style-type: none"> This status signal needs to be transmitted by the setpoint source to ensure trouble-free operation.
		TRUE The current speed is zero. The interpolator in the follow-up controller is kept to the <i>dnPhiIn_p</i> input. <ul style="list-style-type: none"> This function is for instance required for referencing the axis. Since in this case, the axis can move independently of the master position, the follow-up controller is not allowed to intervene.

Outputs

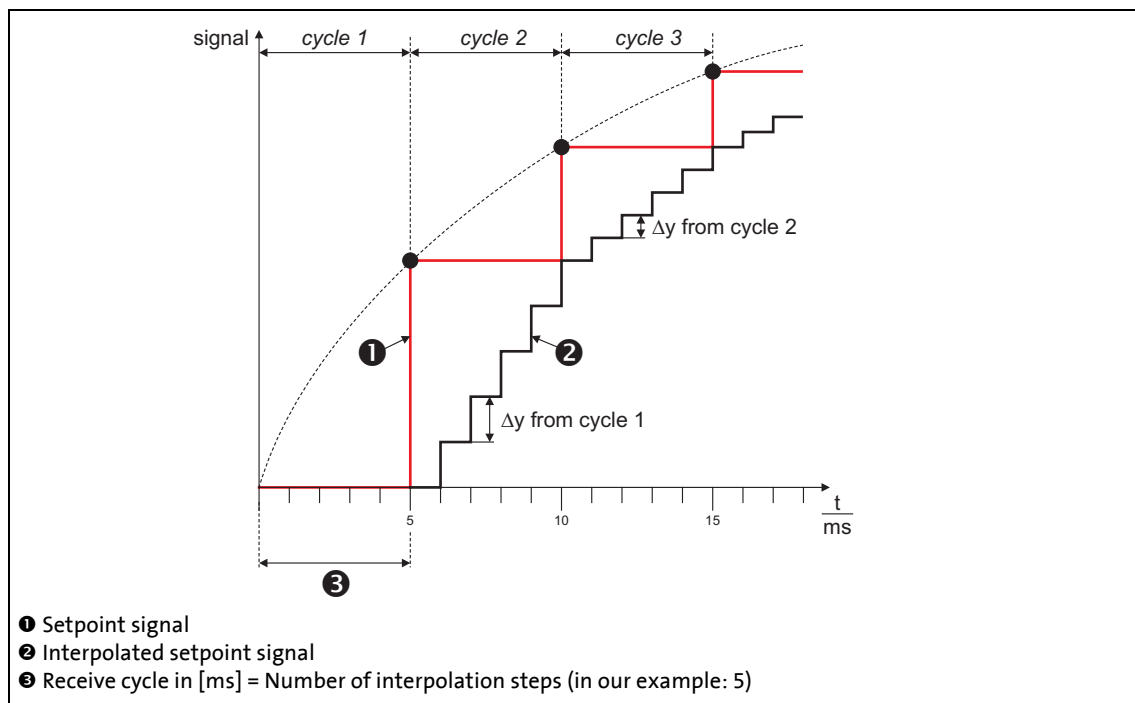
Identifier	Data type	Value/meaning
dnPhiOut_p	DINT	Output of the <i>dnPhiIn_p</i> position setpoint which, if applicable, has been interpolated and completed
nPhdOut_v	INT	Output of the <i>nPhdIn_v</i> angular velocity
nNOut	INT	Output of the <i>nNIn</i> analog value which, if applicable, has been interpolated
bPulse	BOOL	"Input values have been accepted" status signal
		TRUE The input values have been accepted during this cycle.
bSignalError	BOOL	"Signal error" status signal <ul style="list-style-type: none"> Only if signal monitoring is active (<i>C00950/2</i> = "1: On").
		TRUE The number of missing data telegrams has exceeded the limit value parameterised in <i>C00952</i> .

Parameter

Parameter	Possible settings			Info
C00950/1				Signal interpolation of the <i>dnPhIn_p</i> and <i>nNIn</i> input signals <ul style="list-style-type: none">• Lenze setting: Off ▶ Signal interpolation (📘 1539)
	0	Off		
	1	On		
C00950/2				Signal monitoring of the <i>dnPhIn_p</i> input signal <ul style="list-style-type: none">• Lenze setting: Off ▶ Signal monitoring (📘 1540)
	0	Off		
	1	On		
C00951	1		65535	Number of interpolation steps <ul style="list-style-type: none">• Corresponds to the receive cycle of the data telegrams in [ms].• Lenze setting: 1
C00952	0		65535	Limit value for missing data telegrams <ul style="list-style-type: none">• Lenze setting: 5 ▶ Signal monitoring (📘 1540)
C00953	0		100	Speed-up <ul style="list-style-type: none">• Limitation of the amount of correction increments per cycle• Scaling: 1 increment/ms ≡ 0.9155 min⁻¹

19.1.99.1 Signal interpolation

If signal interpolation is active ([C00950/1](#) = 1), the output signal will not reach the level of the corresponding input signal until all interpolation steps parameterised in [C00951](#) have been performed:



[19-41] Signal characteristic

**Note!**

Do not change the number of interpolation steps during operation. Otherwise the interpolation becomes inaccurate.

19.1.99.2 Signal monitoring

If signal monitoring is active ([C00950/2](#) = 1), the signal characteristic of the *dnPhIn_p* input signal is continued even if the data telegram is missing (setpoint selection via CAN).

Monitoring is performed on the basis of the *dnPhIn_p* position setpoint and the *bSpeedAct0* status signal:

- If the *dnPhIn_p* position setpoint remains the same in the next device cycle, it is either because the speed is zero or because no data telegram has been received.
- The evaluation of the *bSpeedAct0* status signal gives information about which reason applies. This status signal needs to be transmitted by the setpoint source to ensure trouble-free operation:
 - *bSpeedAct0* = FALSE means that the speed is not zero, so an error is assumed: The signal characteristic of the *dnPhIn_p* input signal is completed (the current slope is retained).
 - *bSpeedAct0* = TRUE means that the speed is zero, so the unchanged position setpoint is not treated as an error.
- If the number of missing data telegrams exceeds the limit value parameterised in [C00952](#), the *bSignalError* output is set to TRUE.
 - The *bSignalError* output is automatically reset to FALSE if correct signals are detected at *dnPhIn_p* and *bSpeedAct0* again.

**Note!**

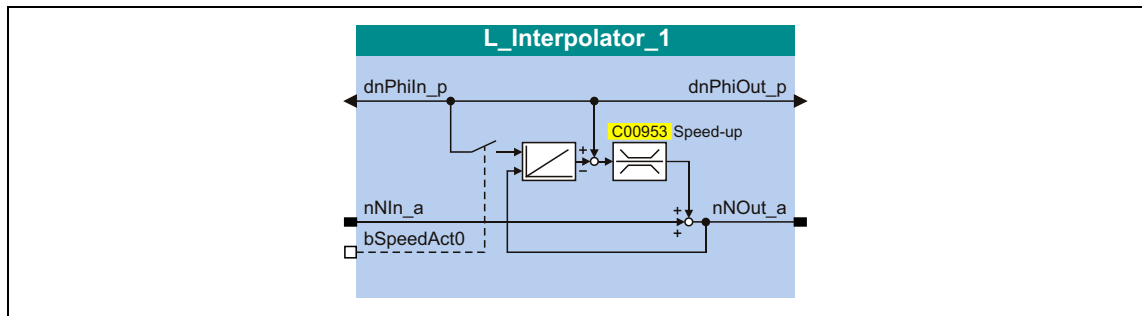
The analog value *nNIn* is not monitored!

19.1.99.3 Angle correction in case of transmission errors

If an angular offset between master and slave is caused due to transmission errors (missing data telegrams), it will be corrected by a catch-up function in the FB. For this purpose, the following connections and parameter settings are required for the slave at the FB **L_Interpolator_1**:

1. The master angle of the master is connected to the *dnPhiln_p* input.
2. The speed signal of the master is connected to the *nNIn* input.
3. The *nNOut* output is connected to the *nSet_v* input of the FB **L_DFSET_1**.

The following illustration shows the principle of the catch-up function in the FB **L_Interpolator_1**:



[19-42] Principle of the catch-up function

The speed signal at *nNIn* is provided almost 1:1 at the *nNOut* output. In case of a telegram error, a correction value can be added to the signal. This correction value results from the subtraction of the integrated speed signal from the position value applied at *dnPhiln_p*.

If for instance a data telegram fails, the input values for a program cycle remain constant. In the following cycle, the correct position and speed are pending again.

"Holding" the position at *dnPhiln_p* results in a difference between the position values at *dnPhiln_p* and at the output of the integrator. This difference is added to the *nNOut_a* output signal.

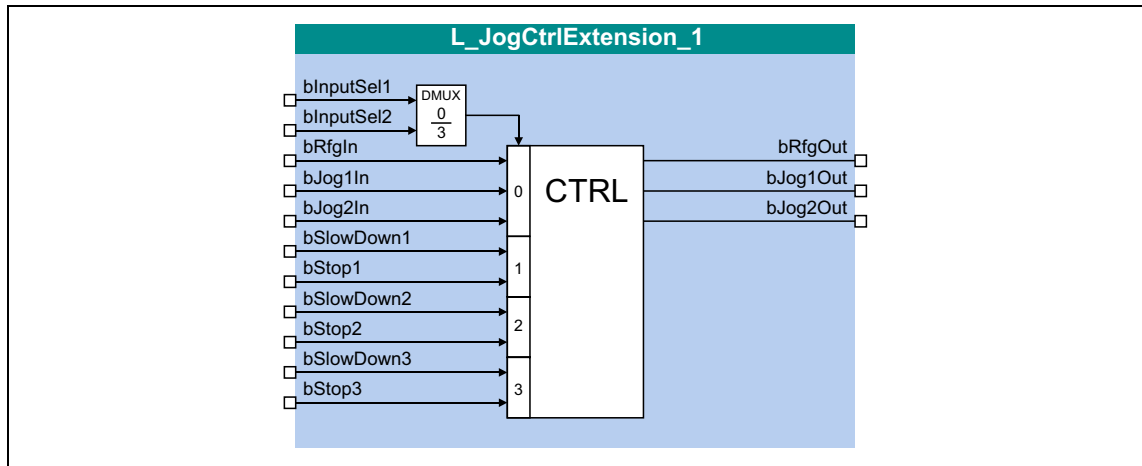
In order that this angle correction does not lead to a strong jerk in the master value, the amount of correction increments is limited per cycle (catch-up cycle) using **C00953**. A typical correction value is for instance 10 increments/ms.

When the controller is inhibited, the integrator is to be loaded with the position value pending at *dnPhiln_p* by setting the *bSpeedAct0* input to TRUE. When the controller is enabled, the *nNOut* speed signal is integrated.

19.1.100 L_JogCtrlExtension_1

This FB can be connected upstream to the [L_NSet](#) ramp function generator/setpoint generator to implement a switch-off positioning at limit switch.

- Detailed information on this operating mode can be found in the description of the "Switch-off positioning" TA.



Inputs

Identifier	Data type	Information/possible settings
bInputSel1 bInputSel2	BOOL	Activation of the <i>bSlowDown1/bStop1</i> , <i>bSlowDown2/bStop2</i> and <i>bSlowDown3/bStop3</i> signal pairs according to the Truth table
bRfgIn	BOOL	Ramping down of the setpoint generator in the downstream L_NSet FB according to the Truth table
bJog1In bJog2In	BOOL	Selection inputs for setting fixed speeds in the setpoint generator <ul style="list-style-type: none"> If the pre-switch off is inactive (<i>bInputSel1</i> and <i>bInputSel2</i> are both set to FALSE), the two control signals are output one-to-one at the <i>bJog1Out</i> and <i>bJog2Out</i> outputs. To achieve the desired behaviour (starting at high speed, pre-switch off at low speed), both inputs must be set to TRUE. Fixed setpoint 2 must be less than fixed setpoint 3! Otherwise, the drive will start at a low speed and accelerate after the pre-switch off. If, in addition to the <i>bJog1In</i> and <i>bJog2In</i> inputs, other jog signals are set at the L_NSet FB, new fixed setpoints are reached, and the drive traverses at speeds that differ from the selection via <i>bJog1In</i> and <i>bJog2In</i>.
bSlowDown1 bSlowDown2 bSlowDown3	BOOL	Activation of fixed setpoint 2 in the downstream L_NSet FB <ul style="list-style-type: none"> These inputs only fulfil a function if they have been activated via <i>bInputSel1</i> and <i>bInputSel2</i> previously (see Truth table).
bStop1 bStop2 bStop3	BOOL	Ramping down of the ramp function generator in the downstream L_NSet FB <ul style="list-style-type: none"> These inputs only fulfil a function if they have been activated via <i>bInputSel1</i> and <i>bInputSel2</i> previously (see Truth table).

Outputs

Identifier	Data type	Value/meaning
bRfgOut	BOOL	Control signal for ramping down the setpoint generator <ul style="list-style-type: none"> Connect this output to the <i>bRfg0</i> input of the L_NSet FB.
bJog1Out	BOOL	Control signal for setting fixed speeds in the setpoint generator <ul style="list-style-type: none"> Connect this output to the <i>bJog1</i> input of the L_NSet FB.
bJog2Out	BOOL	Control signal for setting fixed speeds in the setpoint generator <ul style="list-style-type: none"> Connect this output to the <i>bJog2</i> input of the L_NSet FB.

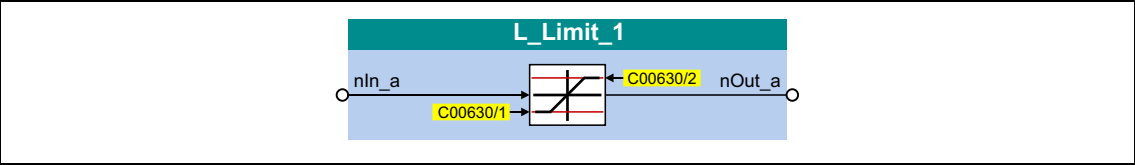
Truth table

Input		Function	Response in the L_NSet FB
bInputSel1	bInputSel2		
FALSE	FALSE	Pre-switch off inactive	No response <ul style="list-style-type: none"> The <i>bRfgIn</i> input signal is directly provided at the <i>bRfgOut</i> output. The <i>bJogIn1</i> and <i>bJogIn2</i> input signals are directly output at the <i>bJog1Out</i> and <i>bJog2Out</i> outputs.
TRUE	FALSE	The <i>bSlowDown1</i> and <i>bStop1</i> inputs are evaluated.	Pre-switch off can be activated <ul style="list-style-type: none"> If the SlowDown function is activated via the selected <i>bSlowDown</i> input, fixed setpoint 2 in the setpoint generator is activated via the <i>bJog1Out</i> and <i>bJog2Out</i> outputs. If the Stop function is activated via the selected <i>bStop</i> input, the <i>bRfgOut</i> output is set to TRUE and hence the setpoint generator is deactivated.
FALSE	TRUE	The <i>bSlowDown2</i> and <i>bStop2</i> inputs are evaluated.	
TRUE	TRUE	The <i>bSlowDown3</i> and <i>bStop3</i> inputs are evaluated.	

[19-1] Truth table for activating the pre-switch off

19.1.101 L_Limit_1

This FB limits an analog input signal to a value range whose upper and lower limit can be set via parameters.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal • Scaling: 16384 ≙ 100 %

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal • Scaling: 16384 ≙ 100 %

Parameter

Parameter	Possible settings			Info
C00630/1	-199.99	%	199.99	Lower limit • Lenze setting: -100.00 %
C00630/2	-199.99	%	199.99	Upper limit • Lenze setting: 100.00 %

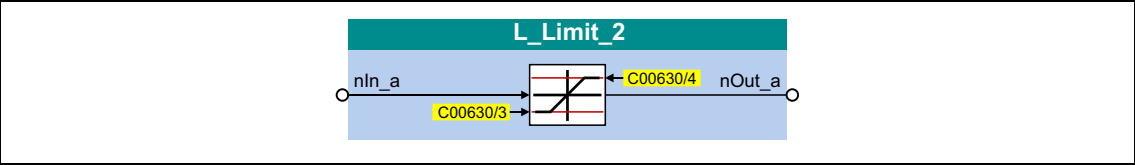


Tip!

Always set the lower limit lower than the upper limit, otherwise value "0" is provided at the *nOut_a* output.

19.1.102 L_Limit_2

This FB limits an analog input signal to a value range whose upper and lower limit can be set via parameters.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal • Scaling: 16384 ≙ 100 %

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal • Scaling: 16384 ≙ 100 %

Parameter

Parameter	Possible settings			Info
C00630/3	-199.99	%	199.99	Lower limit • Lenze setting: -100.00 %
C00630/4	-199.99	%	199.99	Upper limit • Lenze setting: 100.00 %

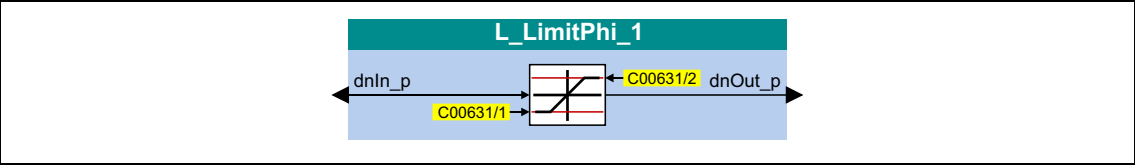


Tip!

Always set the lower limit lower than the upper limit, otherwise value "0" is provided at the *nOut_a* output.

19.1.103 L_LimitPhi_1

This FB limits an angle signal to a value range whose upper and lower value range can be set via parameters.



Inputs

Identifier	Data type	Information/possible settings
dnIn_p	INT	Input signal

Outputs

Identifier	Data type	Value/meaning
dnOut_p	INT	Output signal

Parameter

Parameter	Possible settings			Info
C00631/1	-2147483647	Incr.	2147483647	Lower limit • Lenze setting: -2147483647 incr.
C00631/2	-2147483647	Incr.	2147483647	Upper limit • Lenze setting: 2147483647 incr.

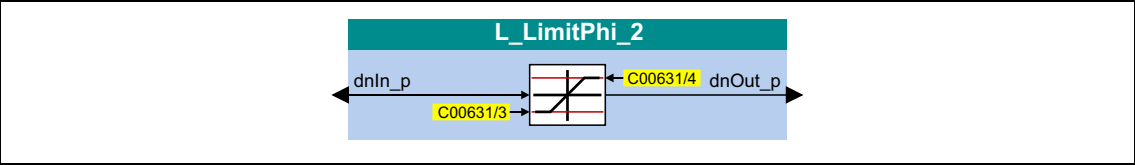


Tip!

Always set the lower limit lower than the upper limit, otherwise value "0" is provided at the *dnOut_p* output.

19.1.104 L_LimitPhi_2

This FB limits an angle signal to a value range whose upper and lower value range can be set via parameters.



Inputs

Identifier	Data type	Information/possible settings
dnIn_p	INT	Input signal

Outputs

Identifier	Data type	Value/meaning
dnOut_p	INT	Output signal

Parameter

Parameter	Possible settings			Info
C00631/3	-2147483647	Incr.	2147483647	Lower limit • Lenze setting: -2147483647 incr.
C00631/4	-2147483647	Incr.	2147483647	Upper limit • Lenze setting: 2147483647 incr.

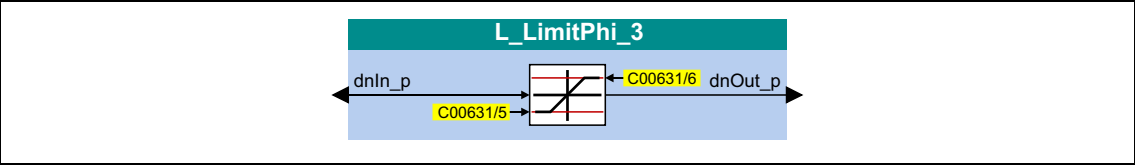


Tip!

Always set the lower limit lower than the upper limit, otherwise value "0" is provided at the *dnOut_p* output.

19.1.105 L_LimitPhi_3

This FB limits an angle signal to a value range whose upper and lower value range can be set via parameters.



Inputs

Identifier	Data type	Information/possible settings
dnIn_p	INT	Input signal

Outputs

Identifier	Data type	Value/meaning
dnOut_p	INT	Output signal

Parameter

Parameter	Possible settings			Info
C00631/5	-2147483647	Incr.	2147483647	Lower limit • Lenze setting: -2147483647 incr.
C00631/6	-2147483647	Incr.	2147483647	Upper limit • Lenze setting: 2147483647 incr.



Tip!

Always set the lower limit lower than the upper limit, otherwise value "0" is provided at the *dnOut_p* output.

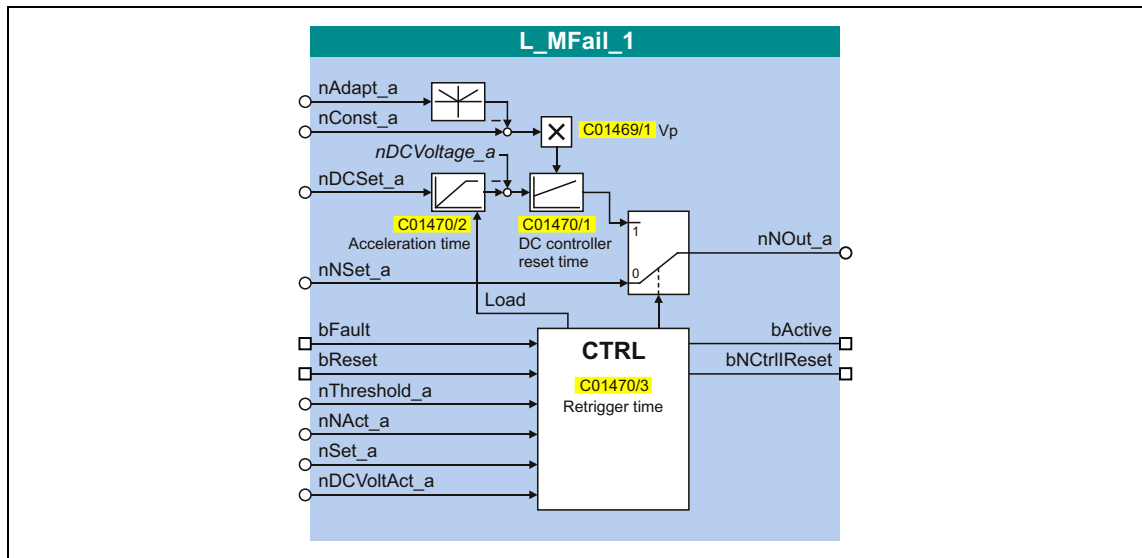
19.1.106 L_MFail_1

In case the supply voltage fails, this FB serves to stop (brake) the drive or drive system in a controlled way via L1, L2, L3 or +UG, -UG to prevent coasting.

**Stop!**

For drive systems that are coupled via digital frequency (a master drive and one or several slave drives) the following applies:

- The mains failure detection and control may only be activated for the master drive.
- All controllers must be operated via the terminals +UG, -UG in the DC bus connection.

**Inputs**

Identifier	Data type	Information/possible settings
nAdapt_a	INT	Dynamic adaptation of the proportional gain of the DC-bus voltage controller <ul style="list-style-type: none">• The resulting proportional gain results from:$V_p = C01469/1 \cdot \frac{nConst_a [\%] - nAdapt_a [\%] }{100 \%}$• Scaling: 16384 ≡ 100 %
nConst_a	INT	
nDCSet_a	INT	Voltage setpoint on which the DC-bus voltage is to be kept. <ul style="list-style-type: none">• Scaling: 16384 ≡ 1000 V
nNset_a	INT	Speed setpoint in [%] <ul style="list-style-type: none">• Scaling: 16384 ≡ 100 % reference speed (C00011)
bFault	BOOL	Activating the mains failure control
		<table><tr><td>TRUE</td><td>Activate mains failure control.</td></tr></table>
TRUE	Activate mains failure control.	
bReset	BOOL	Reset mains failure control <ul style="list-style-type: none">• A reset is always required when the restart protection is active or the restart protection is used and the supply (mains or DC supply) has been switched on.
		<table><tr><td>TRUE</td><td>Reset mains failure control.</td></tr></table>
TRUE	Reset mains failure control.	
nThreshold_a	INT	Restart threshold in [%] <ul style="list-style-type: none">• Scaling: 16384 ≡ 100 % reference speed (C00011)

Identifier	Data type	Information/possible settings
nNAct_a	INT	Comparison value for the restart threshold in [%] • Scaling: 16384 \equiv 100 % reference speed (C00011)
nSet_a	INT	Speed starting point for the deceleration in [%] • Scaling: 16384 \equiv 100 % reference speed (C00011)
nDCVoltAct_a	INT	Actual DC-bus voltage • Scaling: 16384 \equiv 1000 V

Outputs

Identifier	Data type	Value/meaning
nNOut_a	INT	Speed setpoint in [%] • Scaling: 16384 \equiv 100 % reference speed (C00011)
bActive	BOOL	Status signal "Mains failure control active" TRUE The mains failure control is active.
bNCtrlReset	BOOL	Control signal for resetting the I component of the speed controller in the motor control • Connect this output with the <i>bSpeedCtrlOn</i> input of the SB LS_MotionControlKernel (if this is connected upstream to the motor control). TRUE Reset I component of the speed controller of the motor control.

Parameter

Parameter	Possible settings	Info
C01469/1	0.001 31.000	Vp • Lenze setting: 1.000
C01470/1	1 ms 60000 Note: The set value is internally limited to 20 ... 2000 ms! From version 14.00.00 onwards, the limited value is written back to the code if the setting is outside the limits.	Vdc-bus controller reset time • Lenze setting: 20 ms
C01470/2	1 ms 60000 Note: The set value is internally set to 1 ... 16000 ms! From version 14.00.00 onwards, the limited value is written back to the code if the setting is outside the limits.	Acceleration time • Lenze setting: 20 ms
C01470/3	1 ms 60000	Retrigger time • Lenze setting: 20 ms

19.1.106.1 Procedure of the mains failure control

A failure of the voltage supply of the power section can be detected by

- an evaluation of the DC-bus voltage and/or
- an external monitoring system (e.g. voltage measuring relay).

The type of mains failure control to be used depends on the used drive system.



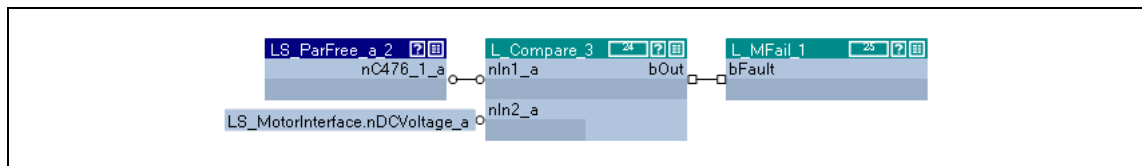
Note!

The following interconnection examples are not functional yet. For an error-free function, connect the FB **L_MFail_1** with further signals!

Evaluation of the DC-bus voltage

This proceeding is used for single drives or multi-axis drives which do not use an external monitoring system.

- For evaluating the DC-bus voltage, you can use a comparator (e.g. FB **L_Compare_3**) as shown in the following interconnection example 1.
- In order that the mains failure control will be activated if the DC-bus voltage falls below a certain operating threshold, set the comparison function "2: In1 > In2" has to be set for the FB **L_Compare_3** in [C00690](#).
- For specifying the operating threshold, the SB **LS_ParFree_a_2** is used. This system block can output 16 parameterisable analog signals. In the shown example, the operating threshold has to be set in the "free parameter" [C00476/1](#).

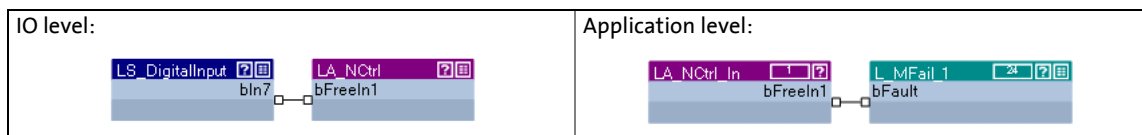


[19-43] Interconnection example 1: Evaluation of the DC-bus voltage with a comparator (cutout)

Use of an external monitoring system

In this proceeding, the digital status signal of an external monitoring system is connected to the FB **L_MFail_1** via a digital input of the controller.

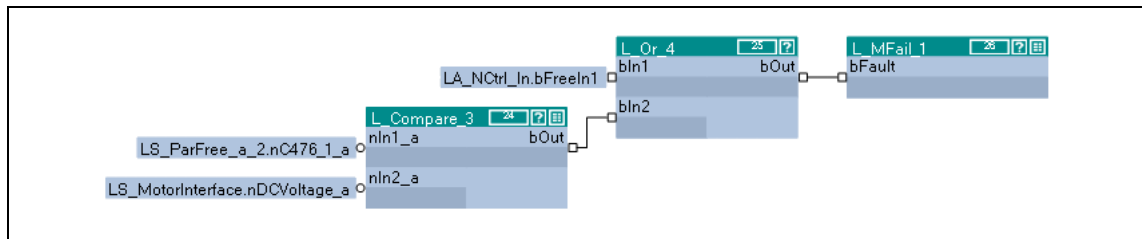
- In the following example, the digital input DI7 is used.
 - The active level (HIGH or LOW active) for DI7 has to be parameterised in [C00114](#) in such a way that *bFault* becomes TRUE when the monitoring system is tripped.
 - A free input of the application block can be used to transfer the digital input signal from I/O level to application level.



[19-44] Interconnection example 2: Use of the digital status signal of an external monitoring system

Combination of the above shown proceedings

The combination of the proceedings can be simply realised via an OR operation:



[19-45] Interconnection example 3: Mains failure control of different sources

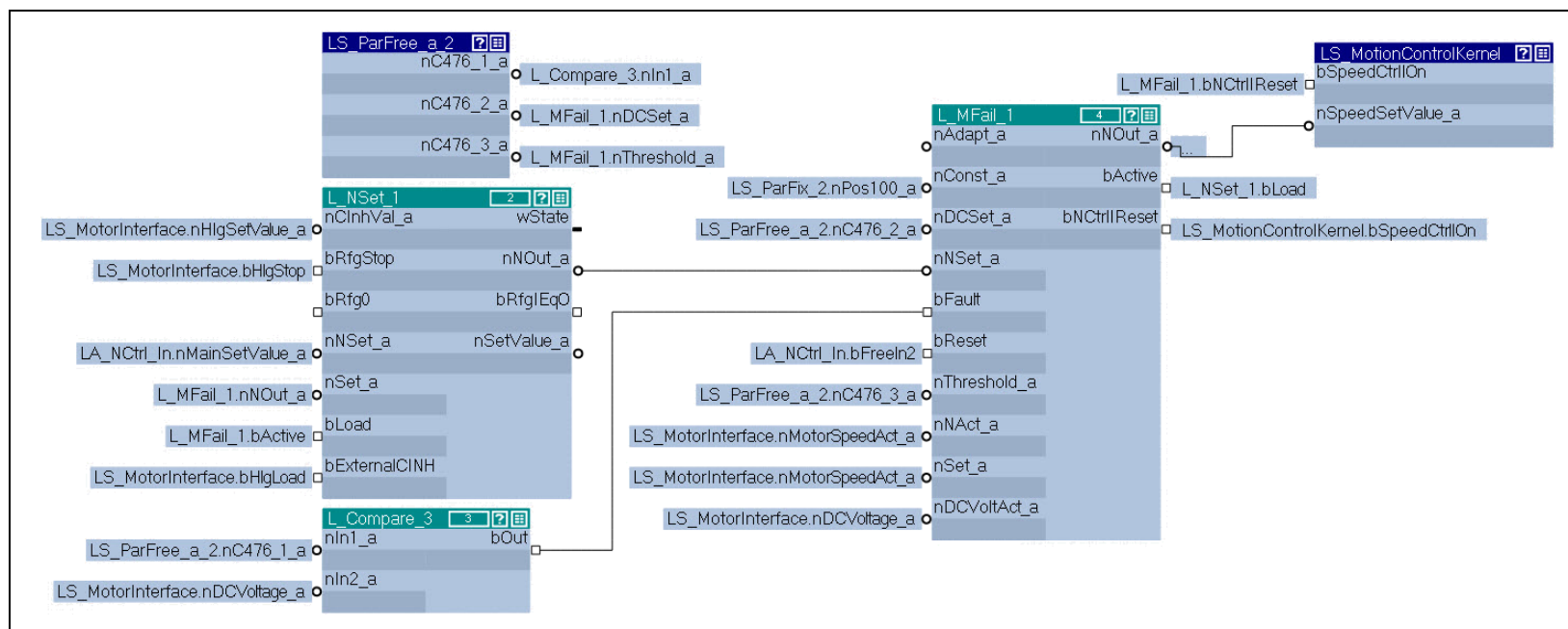
19.1.106.2 Signal flow for mains failure control

The following illustration shows the basic signal flow (cutout) for a mains failure control.



Note!

The following interconnection example is not functional yet. For an error-free function, connect e.g. the FB **L NSet 1** with further signals!



[19-46] Signal flow (detail)

L_MFail inputs	Function
nAdapt_a	Dynamic adaptation of the proportional gain of the DC-bus voltage controller. <ul style="list-style-type: none"> Input not interconnected → Adaptation = 0 %.
nConst_a	Proportional gain of the DC-bus voltage controller <ul style="list-style-type: none"> Input with <i>nPos100_a</i> constant interconnected → proportional gain = 100 %.
nDCSet_a	Voltage setpoint on which the DC-bus voltage is to be kept. <ul style="list-style-type: none"> The voltage setpoint has to be set in the "free parameter" C00476/2.
nNset_a	Speed setpoint path (output: nNOut_a)
bFault	Activating the mains failure control <ul style="list-style-type: none"> ► Procedure of the mains failure control (1551)
bReset	Reset mains failure control <ul style="list-style-type: none"> The free <i>bFreeIn2</i> input of the application block used in the example can be e.g. connected to a digital input on I/O level.
nThreshold_a	Restart threshold <ul style="list-style-type: none"> The restart threshold (at first approx 2 %) has to be set in the "free parameter" C00476/3.
nNAct_a	Comparison value for the restart threshold <ul style="list-style-type: none"> Comparison value is the actual speed value
nSet_a	Speed starting point for the deceleration <ul style="list-style-type: none"> Speed starting point is the actual speed value
nDCVoltAct_a	Actual DC-bus voltage

19.1.106.3 Activating the mains failure control

The mains failure control is activated by setting *bFault* to TRUE. The controller now generates the required operational energy from the rotational energy of the drive. The drive is braked via the power loss of the controller and the motor. Thus, the speed deceleration ramp is shorter than for an uncontrolled system (coasting drive).

After activating the mains failure control:

1. The acceleration time set in [C01470/2](#) is used to control the DC-bus voltage to the value at *nDCSet_a*.
2. At *nNOut_a*, an internally generated speed setpoint is output which serves to brake the drive to a speed close to "0" (via the speed setpoint).
 - Starting value for the controlled deceleration is the value at *nSet_a*. This input is appropriately connected to the actual speed value *nMotorSpeedAct_a* of the SB [LS_MotorInterface](#).
 - The speed deceleration ramp (and hence the braking torque) results from the moment of inertia of the load machine(s), the power loss of the drive (system) and the set parameter setting.



Stop!

If a connected braking unit responds, the drive is braked with a max. possible torque (I_{\max}). In this case, adapt the parameter setting if required (see the following chapter).

If the power section is not supplied, the drive cannot create a standstill torque (important for active loads as e.g. hoists).

Stopping/cancelling the mains failure control

When *bFault* is reset to FALSE, an internal timing element is triggered. After the time set in [C01470/3](#) has elapsed, the mains failure control is stopped/cancelled.

- When the restart protection is active, the drive is continued to be braked to standstill. ▶ [Restart protection](#) ([□ 1559](#))
 - When the restart protection is active, the drive can only be reset by setting the *bReset* input to TRUE.
- When the restart protection not active, the drive is accelerated to the speed setpoint. ▶ [Quick mains recovery \(KU\)](#) ([□ 1559](#))

19.1.106.4 Parameterising the mains failure control

The parameters to be set before initial commissioning strongly depend on the used motor, the moment of inertia of the drive and the drive configuration (single drive, drive system, master/slave operation etc.) and must hence be adapted to the corresponding application case.



Note!

The following data refers to the chapter "[Procedure of the mains failure control](#)". (1551)

- Measure the DC-bus voltage with an oscilloscope (channel 1).
Option 1: With a corresponding voltage divider at the terminals +UG, -UG.
Option 2: At the analog output terminals X3/O1U and X3/GA
 - For this purpose, adapt the signal flow in order that the DC-bus voltage is provided via the analog output 1: Go to the application level and connect the *nDCVoltage_a* signal of the SB [LS_MotorInterface](#) to a free output of the application block (e.g. *wFreeOut1*). Then connect this output in the IO level to the *nOut1V_a* input of the SB [LS_AnalogOutput](#).
- Measure the speed with an oscilloscope (channel 2) at the analog output terminals X3/O2U and X3/GA.
 - For this purpose, adapt the signal flow in order that the speed is provided via the analog output 2: Go to the application level and connect the *nMotorSpeedAct_a* signal of the SB [LS_MotorInterface](#) to a free output of the application block (e.g. *wFreeOut2*). Then connect this output in the IO level to the *nOut2V_a* input of the SB [LS_AnalogOutput](#).
- Set the operating threshold for the mains failure control in [C00476/1](#).
 - Scaling: 100 % \equiv 1000 V
 - Recommended setting: approx. 50 V above the reset threshold for undervoltage in the DC bus (LU_{off}).
 - The operating thresholds for undervoltage (LU) and overvoltage (OU) depend on the setting in [C00173](#):

Mains voltage		Undervoltage (LU)		Overvoltage (OU)	
1-phase	C00173	Operating threshold LU_{on}	Reset threshold LU_{off}	Operating threshold OU_{on}	Reset threshold OU_{off}
230V _{AC}	0, 1, 2, 3	180 V _{DC}	240 V _{DC}	400 V _{DC}	390 V _{DC}

Mains voltage		Undervoltage (LU)		Overvoltage (OU)	
3-phase	C00173	Operating threshold LU_{on}	Reset threshold LU_{off}	Operating threshold OU_{on}	Reset threshold OU_{off}
400V _{AC}	0	285 V _{DC}	430 V _{DC}	800 V _{DC}	790 V _{DC}
440V _{AC}	1	400 V _{DC}	430 V _{DC}		
480V _{AC}	2	490 V _{DC}	535 V _{DC}		
500V _{AC}	3	540 V _{DC}	585 V _{DC}		

- Set the voltage setpoint in [C00476/2](#) the DC-bus voltage is to be controlled to.
 - Scaling: 100 % \equiv 1000 V
 - Recommended setting: approx. 700 V \rightarrow [C00476/2](#) = 70 %



Stop!

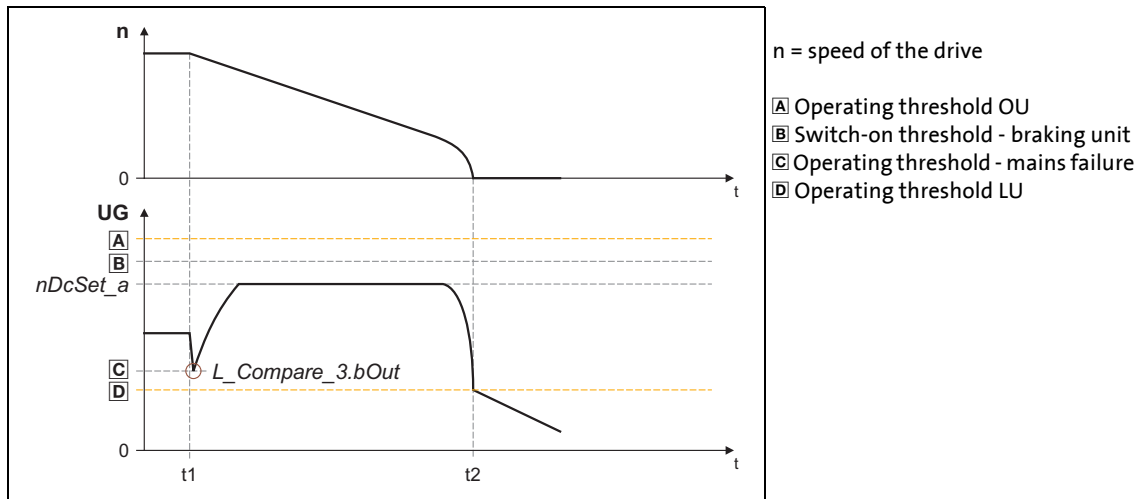
The voltage setpoint must be below the operating threshold of a braking unit if connected. If a connected braking unit responds, the drive with max. possible torque (I_{\max}) will be braked. The desired operational performance gets lost.

19.1.106.5 Commissioning the mains failure control

Commissioning should be executed with motors without load.

1. Start the drive.
2. Set the acceleration time:
 - Set the speed setpoint to 100 %, operate the controller with max. speed.
 - Set controller inhibit and measure deceleration time up to standstill.
 - Set approx. 1/10 of the measured deceleration time in [C01470/2](#).
3. Set retrigger time:
 - In case of mains failure control via detection of the DC-bus voltage level:
Set the deceleration time measured under point 2 in [C01470/3](#).
 - In case of mains failure control via an external system:
Set the time in which the drive is to be continued to be brought to a standstill under control at short-term mains recovery in [C01470/3](#).
4. Switch off the supply voltage (mains or DC bus).

The following profile is to be shown on the oscilloscope:



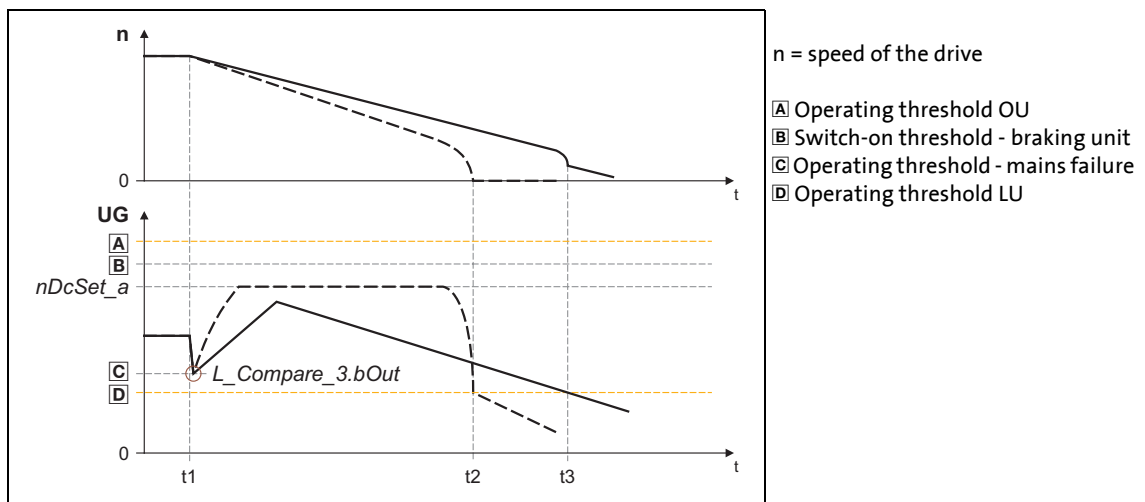
[19-47] Schematic diagram with activated mains failure control (ideal profile)

Point in time	Info
$t = t1$	Mains failure
$t = t2$	Speed "0" reached.

19.1.106.6 Fine adjustment of the mains failure control

For the fine adjustment, repeat the following points several times:

1. A final speed as low as possible has to be reached before the controller reaches the operating threshold for undervoltage (LU):
 - Increase proportional gain V_p in [C01469/1](#).
 - Reduce Vdc-bus controller reset time in [C01470/1](#).
2. The responding of the braking unit or the reaching of the operating threshold for overvoltage (OU) has to be prevented:
 - Increase Vdc controller reset time in [C01470/1](#) until the ideal profile shown in [\[19-47\]](#) will be almost reached.
 - If required, reduce the $nDcSet_a$ voltage setpoint to which the DC-bus voltage is to be controlled (in the interconnection example via the free parameter [C00476/2](#)).
3. Increasing the deceleration time or reducing the braking torque is only possible to a limited extent:
 - Increasing the acceleration time in [C01470/2](#) reduces the initial braking torque and simultaneously increases the deceleration time.
 - Increasing the Vdc controller reset time in [C01470/1](#) reduces the braking torque and simultaneously increases the deceleration time. If the reset times are too high, the controller reaches the operating threshold for undervoltage (LU) before standstill is reached. Hence, the drive is not controlled anymore.



[19-48] Schematic diagram with different braking torques

Point in time	Info
$t = t_1$	Mains failure
$t = t_2$	Speed "0" with higher braking torque reached (short reset time).
$t = t_3$	With a lower braking torque (higher reset time), the drive reaches the operating threshold for undervoltage (LU) without reaching speed "0".
$t > t_3$	Drive is not controlled anymore (is braked by friction).

19.1.106.7 Reset mains failure control

The mains failure control is reset by setting *bReset* to TRUE.

- A reset via *bReset* is always required when the restart protection is active or the restart protection is used and the supply (mains or DC supply) has been switched on.
- The *bReset* input can, for instance, be connected to a digital input.

19.1.106.8 Restart protection

The integrated restart protection is to prevent a restart in the lower speed range when the supply voltage was only interrupted briefly (mains recovery before drive stands still).

- The *nThreshold_a* input serves to specify the restart threshold in [%] with regard to the reference speed ([C00011](#)) below which no start has to take place after mains recovery.
 - If in case of mains recovery the speed is below the restart threshold, the drive is continued to be braked in a controlled way. This function is only stopped by setting *bReset* to TRUE.
 - If the speed is above the restart threshold after mains recovery, the drive changes to its setpoint *nNSet_a*.
 - The function is switched inactive when *nThreshold_a* = 0 %.
- A reset takes place by setting *bReset* to TRUE and is required after every mains switching.
 - In this case, the *bActive* output is set to TRUE when the *bFault* input is set to FALSE.

19.1.106.9 Quick mains recovery (KU)

The quick mains recovery causes a restart of the controller if the restart protection is not active anymore.

- In case, the drive reaches its setpoint.
- If this behaviour is not desired, you can delay the restart by setting a retrigger time in [C01470/3](#) or prevent it by using the restart protection.
- Dependent on the system, the mains recovery is reported through the mains failure control via the level of the DC-bus voltage. ▶ [Procedure of the mains failure control](#) ([1551](#))

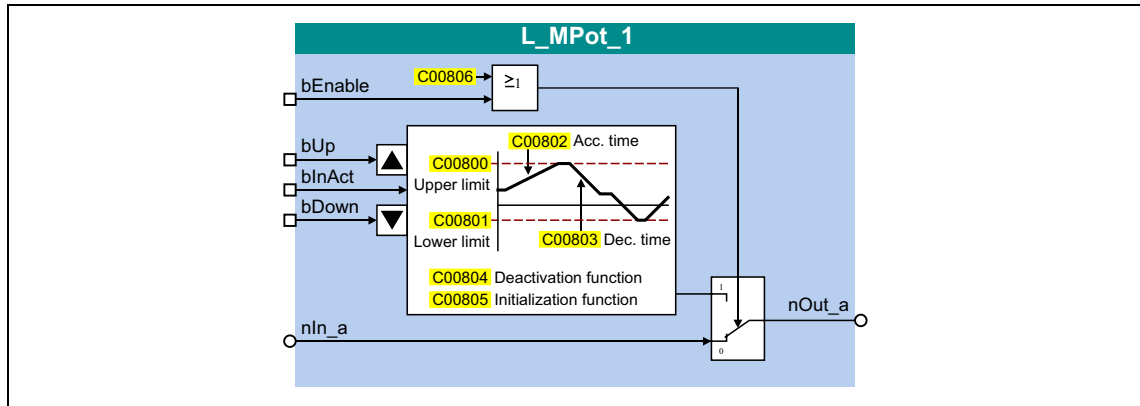
A quick mains recovery is caused by a "quick interruption" of the energy supply company (e.g. thunderstorm) and by faulty components in the supply cables (e.g. collector rings).

- Then, set the retrigger time in [C01470/3](#) higher than the measured deceleration time reached in braking operation.

19.1.107 L_MPot_1

This FB replaces a hardware motor potentiometer and can be used as an alternative setpoint source which is controlled via two inputs.

- The signal is output via a ramp function generator with linear ramps.
- The acceleration and deceleration times are set via parameters.
- Constant ramping even with speed limit values changed online.
- The motor potentiometer function can be switched on/off online.



Inputs

Identifier	Data type	Information/possible settings
bEnable	BOOL	Switch over motor potentiometer function <i>bEnable</i> input and C00806 code are ORed.
		TRUE Motor potentiometer function is active, setpoint can be changed via <i>bUp</i> and <i>bDown</i> . • With switching to TRUE, the value applied to <i>nIn_a</i> is automatically transferred to the motor potentiometer.
		FALSE The value applied to <i>nIn_a</i> is output at <i>nOut_a</i> .
nIn_a	INT	When bEnable = FALSE, the analog nIn_ is input signal switched to the nOut_a output.
bUp	BOOL	Approaching of the upper speed limit value set in C00800 .
		TRUE The <i>nOut_a</i> output signal runs to its upper limit value (<i>nHighLimit</i>). • If the <i>bDown</i> input is simultaneously set to TRUE, the <i>nOut_a</i> output signal is not changed.
bDown	BOOL	Approaching of the lower speed limit value set in C00801 .
		TRUE The <i>nOut_a</i> output signal runs to its lower limit value (<i>nLowLimit</i>). • If the <i>bUp</i> input is simultaneously set to TRUE, the <i>nOut_a</i> output signal is not changed.
bInAct	BOOL	Deactivate motor potentiometer function • This input has the highest priority. • When the motor potentiometer is deactivated, the <i>nOut_a</i> output signal follows the function set with code C00804 .
		TRUE Motor potentiometer function is deactivated.

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal

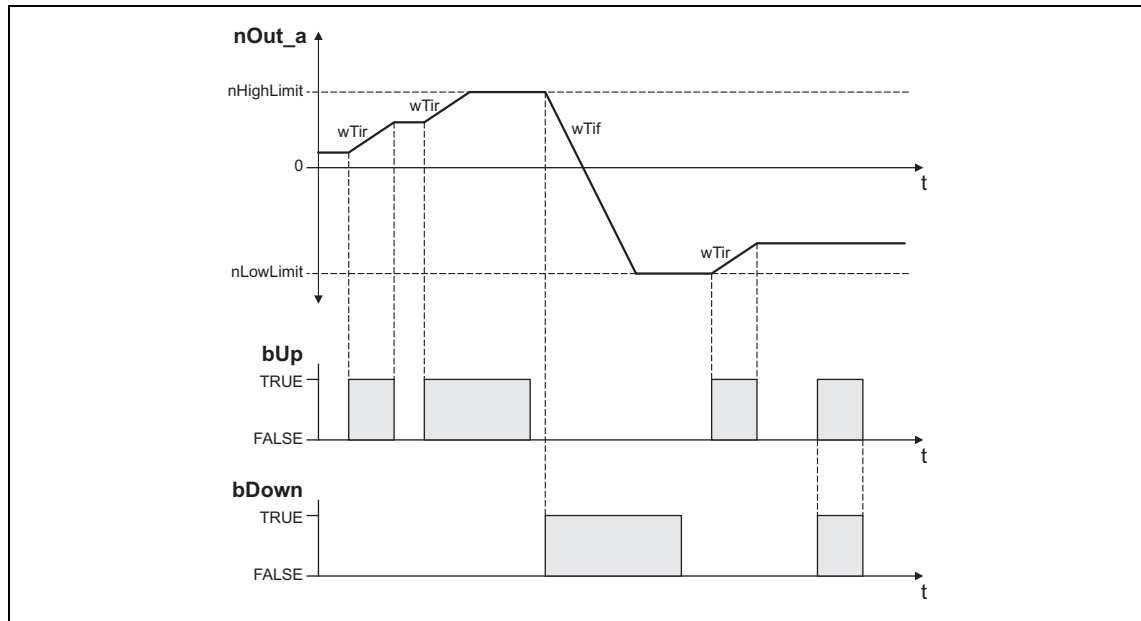
Parameter

Parameter	Possible settings			Info
C00800	-199.99	%	199.99	Upper limit • Lenze setting: 100.00 %
C00801	-199.99	%	199.99	Lower limit • Lenze setting: -100.00 %
C00802	0.1	s	6000.0	Acceleration time • Lenze setting: 10.0 s
C00803	0.1	s	6000.0	Deceleration time • Lenze setting: 10.0 s
C00804				Inactive function • Selection of response when deactivating the motor potentiometer via the input <i>blnAct</i> . • Lenze setting: 0
	0	No further action; <i>nOut_a</i> retains its value.		
	1	The motor potentiometer returns to 0 % within the deceleration time T_{if}		
	2	The motor potentiometer runs to the lower limit value (C00801) within the deceleration time T_{if}		
	3	The motor potentiometer output immediately changes to 0 %		Important for the emergency stop function
	4	The motor potentiometer output immediately changes to the lower limit value (C00801)		
	5	The motor potentiometer runs to the upper limit value (C00800) within the acceleration time T_{ir}		
C00805				Init function • Selection of response when switching on the device. • Lenze setting: 0
	0	The output value being output during mains power-off is saved non-volatily in the internal memory of the controller. It will be reloaded during mains power-on.		
	1	The lower limit value (C00801) is loaded during mains power-on.		
	2	An output value = 0 % is loaded during mains power-on.		
C00806				Use of the motor potentiometer • When switching to 1: YES, the value applied to <i>nIn_a</i> is automatically transferred to the motor potentiometer. • Lenze setting: 0
	0	No		
	1	Yes		

19.1.107.1 Activate & control motor potentiometer

When *blnAct* is set to FALSE, the motor potentiometer is activated.

- The currently active function depends on the current output signal *nOut_a*, the limit values set and the control signals at *bUp* and *bDown*.
- When the *nOut_a* output signal is outside the limits set, the output signal runs to the next limit with the *Ti* times set. This process is independent of the control signals at *bUp* and *bDown*.
- When the *nOut_a* output signal is inside the limits set, the output signal changes according to the control signals at *bUp* and *bDown*.

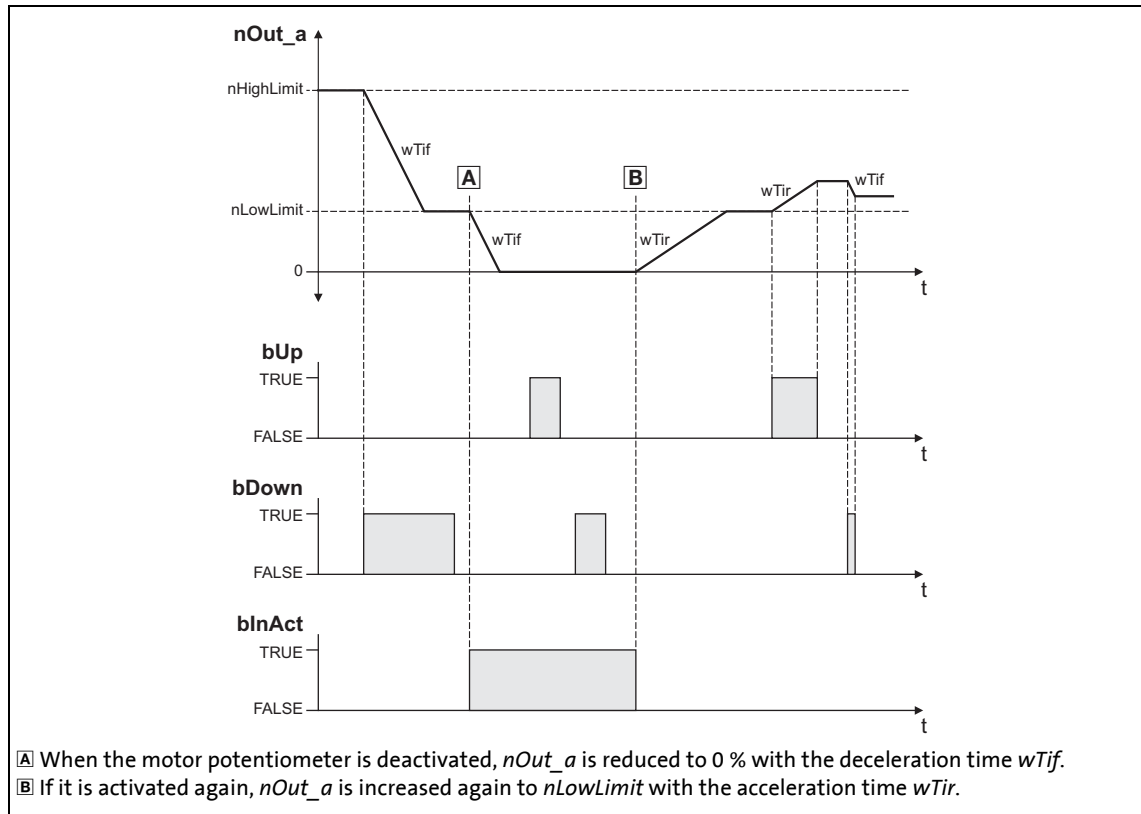


[19-49] Example: Control of the motor potentiometer

<i>bUp</i>	<i>bDown</i>	<i>blnact</i>	Function
FALSE	FALSE	FALSE	The <i>nOut_a</i> output signal remains unchanged.
TRUE	FALSE		The <i>nOut_a</i> output signal runs to its upper limit value (<i>nHighLimit</i>).
FALSE	TRUE		The <i>nOut_a</i> output signal runs to its lower limit value (<i>nLowLimit</i>).
TRUE	TRUE		The <i>nOut_a</i> output signal remains unchanged.
-	-	TRUE	The motor potentiometer function is deactivated. The <i>nOut_a</i> output signal responds according to the function selected via <i>Function</i> .

19.1.107.2 Deactivate motor potentiometer

When the motor potentiometer is deactivated by setting *blnAct* to TRUE, the *nOut_a* output signal responds according to the function selected via *Function*.

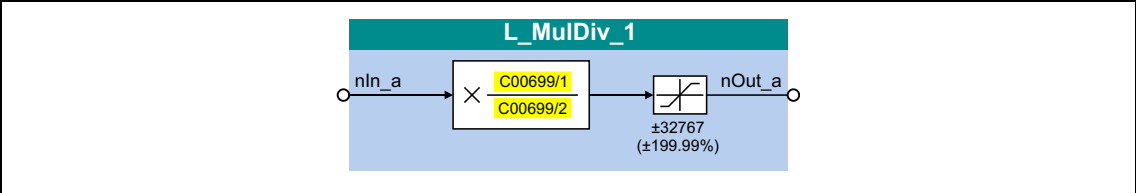


[19-50] Example: Deactivation of the motor potentiometer when the *Function* = 1 has been selected

19.1.108 L_MulDiv_1

This FB multiplies the analog input signal with a parameterisable factor.

- The value of the factor is determined by a quotient consisting of numerator and denominator .
- The value output at *nOut_a* is limited to ±199.99 %.
- Division is not remainder considered.



Inputs

Identifier	Data type	Information/possible settings
nIn1	INT	Input signal

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Product value (result of the multiplication) <ul style="list-style-type: none">• Internal limitation to ± 32767

Parameter

Parameter	Possible settings			Info
C00699/1	-32767		32767	Counter
C00699/2	-32767		32767	Denominator

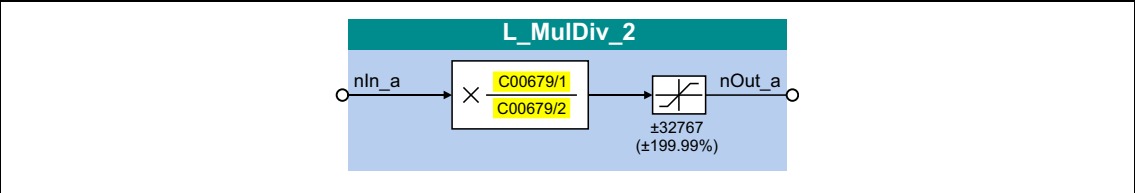
Function

$$nOut_a = nIn_a \times \frac{C00699/1}{C00699/2}$$

19.1.109 L_MulDiv_2

This FB multiplies the analog input signal with a parameterisable factor.

- The value of the factor is determined by a quotient consisting of numerator and denominator .
- The value output at *nOut_a* is limited to ±199.99 %.
- Division is not remainder considered.



Inputs

Identifier	Data type	Information/possible settings
nIn1	INT	Input signal

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Product value (result of the multiplication) <ul style="list-style-type: none">• Internal limitation to ± 32767

Parameter

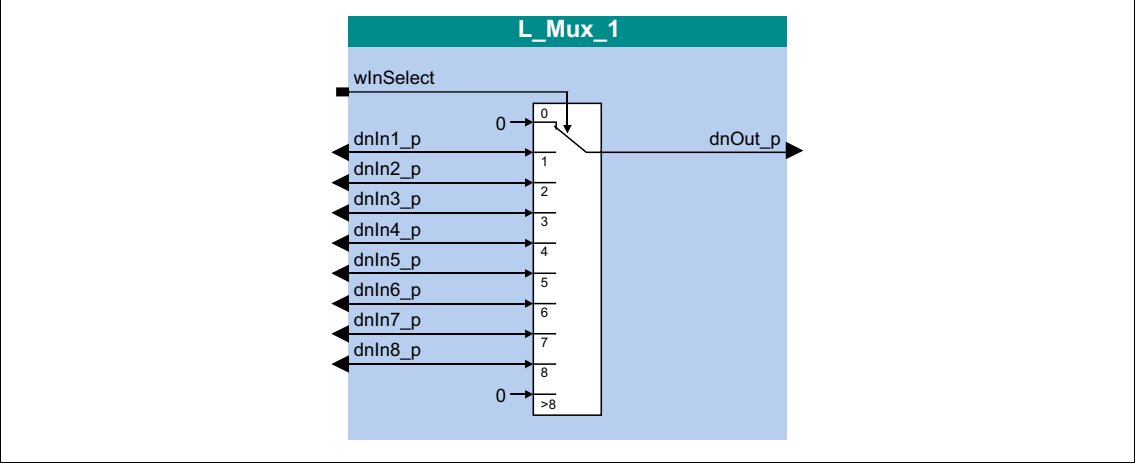
Parameter	Possible settings			Info
C00679/1	-32767		32767	Counter
C00679/2	-32767		32767	Denominator

Function

$$nOut_a = nIn_a \times \frac{C00679/1}{C00679/2}$$

19.1.110 L_Mux_1

This FB provides one of the eight input signals *dnIn1_p* ... *dnIn8_p* at the output *dnOut_p*. The selection is made by means of the signal at the input *wInSelect*.



Inputs

Identifier	Data type	Information/possible settings
wInSelect	WORD	Input signal
		1 ... 8 <ul style="list-style-type: none">• The values "1" ... "8" select the input signal to be applied to the output.• Values from "1" ... "8" set the <i>dnOut_p</i> output to "0".
dnIn1_p	DINT	Input signal
...		
dnIn8_p	DINT	

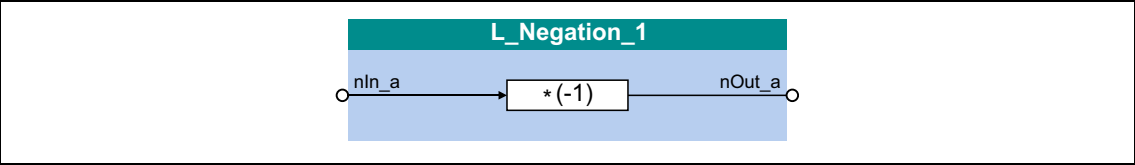
Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal

19.1.111 L_Negation_1

This FB converts the sign of the input signal, i.e. the input signal is multiplied by the value -1 and is then output.

- With the value - 32768 at the *nIn_a* input, the value + 32767 is provided at the *nOut_a* output.



Inputs

Identifier	Data type	Value/meaning
nIn_a	INT	Input signal

Outputs

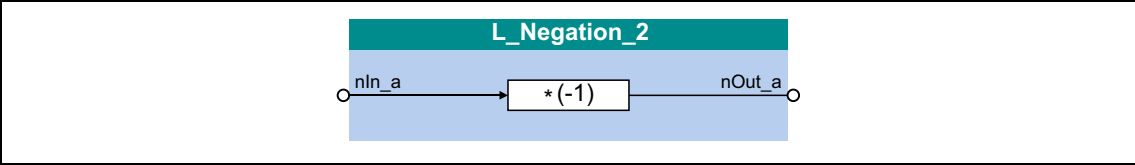
Identifier	Data type	Value/meaning
nOut_a	INT	Output signal

19.1.112

L_Negation_2

This FB converts the sign of the input signal, i.e. the input signal is multiplied by the value -1 and is then output.

- With the value - 32768 at the *nIn_a* input, the value + 32767 is provided at the *nOut_a* output.



Inputs

Identifier	Data type	Value/meaning
nIn_a	INT	Input signal

Outputs

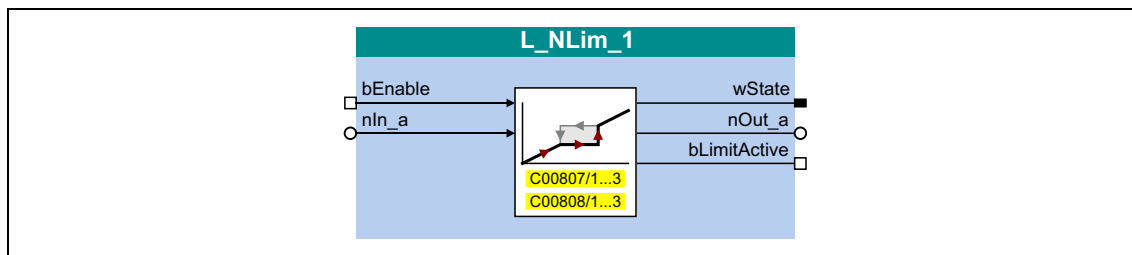
Identifier	Data type	Value/meaning
nOut_a	INT	Output signal

19.1.113 L_NLim_1

This FB can mask out up to three parameterisable blocking zones within a continuous signal characteristic.

**Note!**

A value of "0" cannot be masked out if the *nIn_a* input signal changes signs.

**Inputs**

Identifier	Data type	Information/possible settings
bEnable	BOOL	Activate zone masking
		FALSE The FB has been deactivated. • The input signal is output one-to-one at the <i>nOut_a</i> output.
		TRUE The FB has been activated. • Zone masking of the input signal is carried out according to the parameterised blocking zones.
nIn_a	INT	Input signal

Outputs

Identifier/data type	Value/meaning
wState	WORD
	Bit-coded status word • Bits that are not listed are reserved for future extensions.
	Bit 0 No blocking zone active
	Bit 1 Blocking zone 1 active
	Bit 2 Blocking zone 2 active
nOut_a	INT
	Output signal • If the FB has been activated, the output signal is outside the blocking zones.
bLimitActive	BOOL
	"Limitation active" status signal TRUE The input signal is inside a blocking zones and is limited to the respective boundary value of the blocking zone.

Parameter

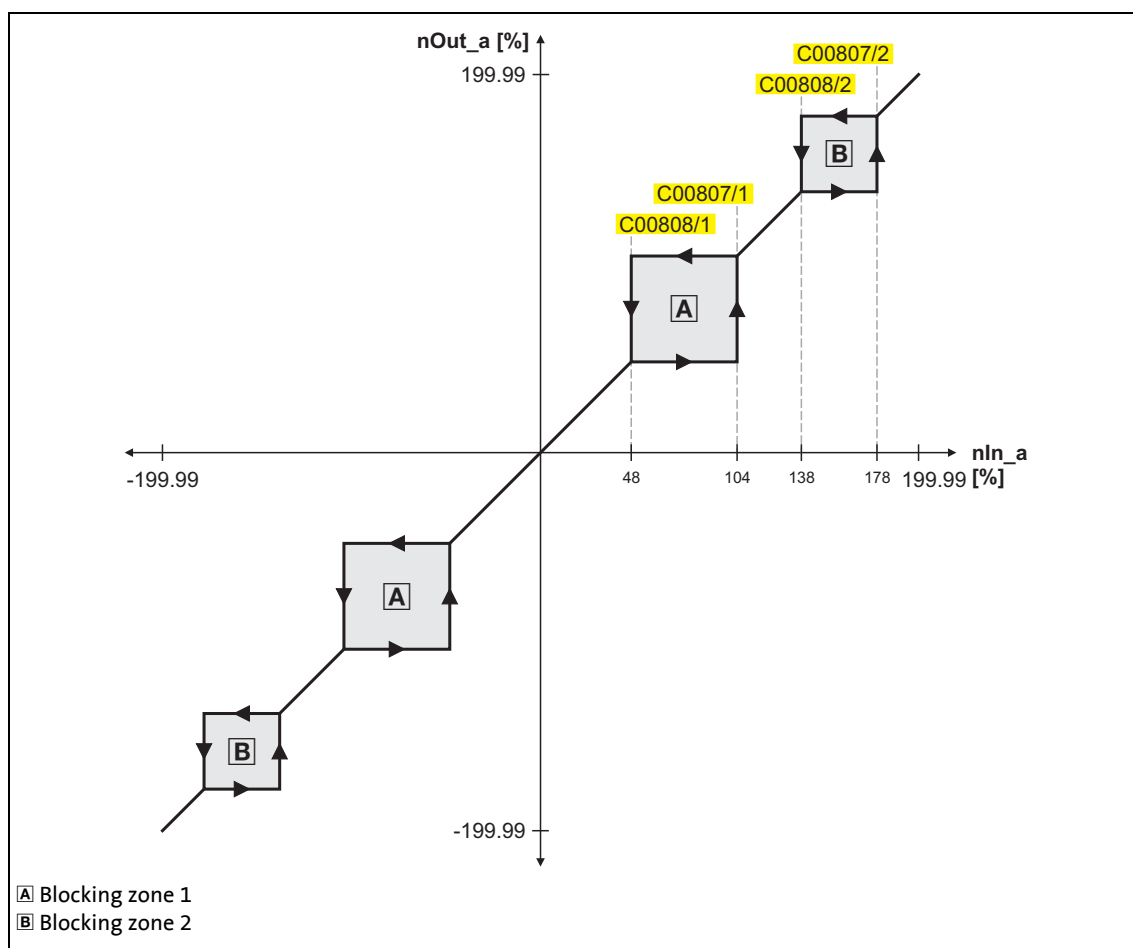
Parameter	Possible settings			Info
C00807/1...3	0.00	%	199.99	Max. skip frequency 1 ... 3 • Lenze setting: 0.00 %
C00808/1...3	0.00	%	199.99	Min. skip frequency 1 ... 3 • Lenze setting: 0.00 %

Definition of the blocking zones

Up to three zones can be parameterised which are to be skipped by the *nOut_a* output signal.

The example below shows the parameter setting of two blocking zones for the **L_NLim_1** FB:

Parameter	Blocking zone 1		Blocking zone 2		Blocking zone 3	
Minimum limit value	C00808/1:	48 %	C00808/2:	138 %	C00808/3:	0 %
Maximum limit value	C00807/1:	104 %	C00807/2:	178 %	C00807/3:	0 %



[19-51] Zone masking by means of parameterisable blocking zones (in our example: **L_NLim_1**)

- The parameterised blocking zones have the same effect on negative input signals.
- A blocking zone is deactivated by entering identical limit values (in our example: blocking zone 3).

Overlapping of blocking zones

If blocking zones overlap, the lowest and highest value of the overlapping zones form a new zone. In this case, the status display (*wState* output) will also just display one zone (the lower one of the two original zones).

Abutting blocking zones

If two blocking zones abut (e.g. 20 ... 30 % and 30 ... 40 %), the limit value between the two zones (in this example 30 %) is also passed through.

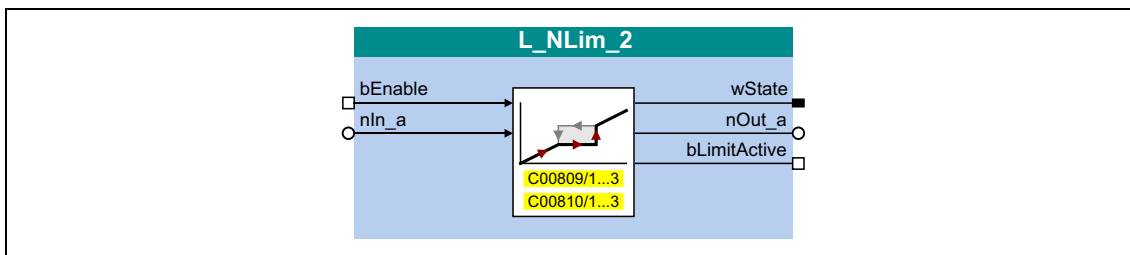
The same applies to a limit range of 0 ... xx %. At the zero crossing of the *nIn_a* input signal, a value of "0" is also output at the *nOut_a* output. Value "0" cannot be excluded. If the *nIn_a* input signal drops back to "0", the *nOut_a* output will retain the upper limit value.

19.1.114 L_NLim_2

This FB can mask out up to three parameterisable blocking zones within a continuous signal characteristic.

**Note!**

A value of "0" cannot be masked out if the *nIn_a* input signal changes signs.

**Inputs**

Identifier	Data type	Information/possible settings
bEnable	BOOL	Activate zone masking
		FALSE The FB has been deactivated. • The input signal is output one-to-one at the <i>nOut_a</i> output.
		TRUE The FB has been activated. • Zone masking of the input signal is carried out according to the parameterised blocking zones.
nIn_a	INT	Input signal

Outputs

Identifier/data type	Value/meaning
wState	WORD
	Bit-coded status word • Bits that are not listed are reserved for future extensions.
	Bit 0 No blocking zone active
	Bit 1 Blocking zone 1 active
	Bit 2 Blocking zone 2 active
nOut_a	INT
	Output signal • If the FB has been activated, the output signal is outside the blocking zones.
bLimitActive	BOOL
	"Limitation active" status signal TRUE The input signal is inside a blocking zones and is limited to the respective boundary value of the blocking zone.

Parameter

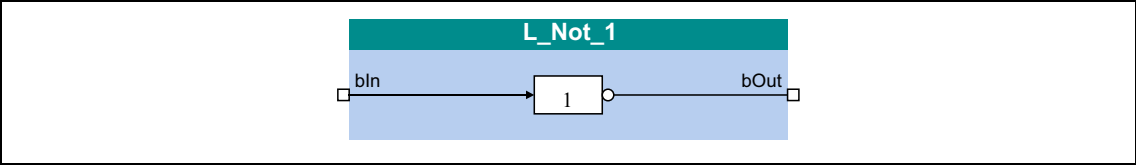
Parameter	Possible settings			Info
C00809/1...3	0.00	%	199.99	Max. skip frequency 1 ... 3 • Lenze setting: 0.00 %
C00810/1...3	0.00	%	199.99	Min. skip frequency 1 ... 3 • Lenze setting: 0.00 %



For a detailed functional description see [L_NLim 1](#).

19.1.115 L_Not_1

This FB negates a signal of BOOL data type.



Inputs

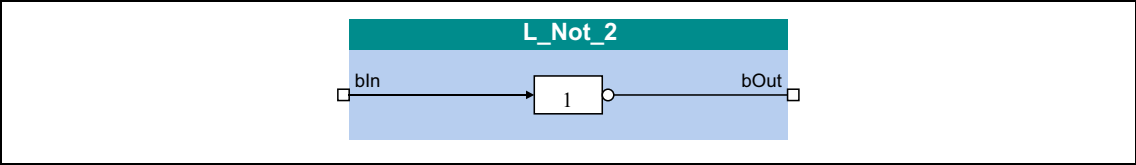
Identifier	Data type	Value/meaning
bIn	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Result of the NOT operation (negated input signal)

19.1.116 L_Not_2

This FB negates a signal of BOOL data type.



Inputs

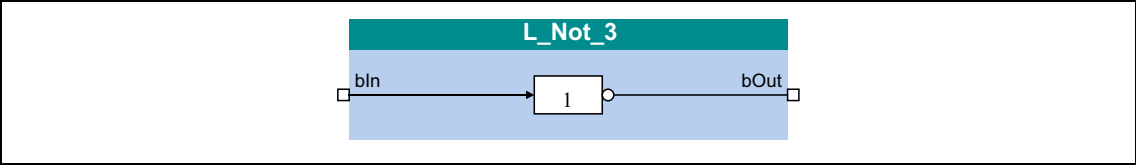
Identifier	Data type	Value/meaning
bIn	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Result of the NOT operation (negated input signal)

19.1.117 L_Not_3

This FB negates a signal of BOOL data type.



Inputs

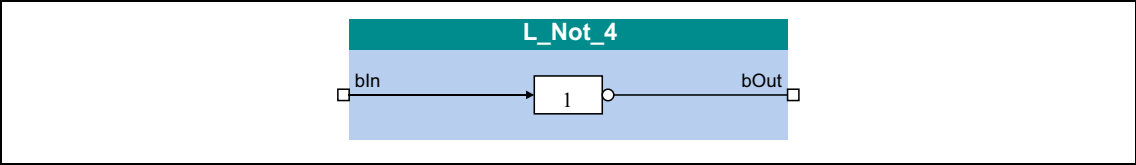
Identifier	Data type	Value/meaning
bIn	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Result of the NOT operation (negated input signal)

19.1.118 L_Not_4

This FB negates a signal of BOOL data type.



Inputs

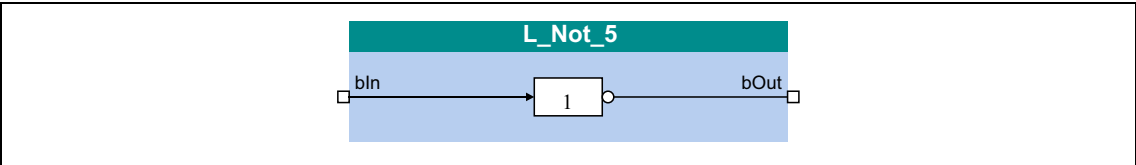
Identifier	Data type	Value/meaning
bIn	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Result of the NOT operation (negated input signal)

19.1.119 L_Not_5

This FB negates a signal of BOOL data type.



Inputs

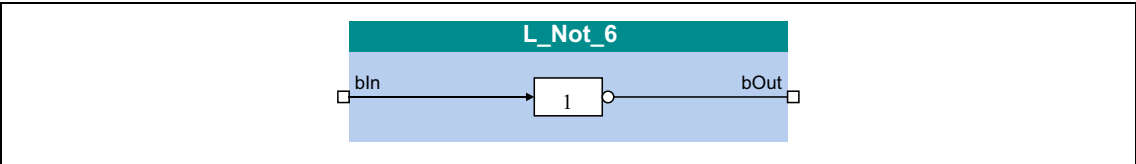
Identifier	Data type	Value/meaning
bIn	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Result of the NOT operation (negated input signal)

19.1.120 L_Not_6

This FB negates a signal of BOOL data type.



Inputs

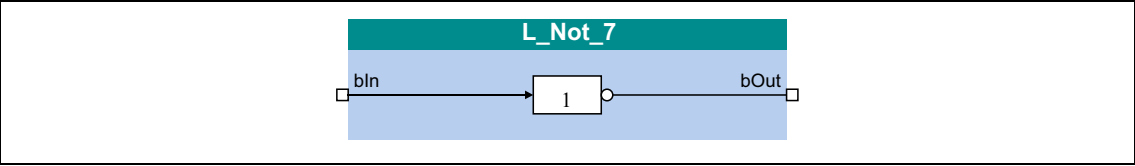
Identifier	Data type	Value/meaning
bIn	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Result of the NOT operation (negated input signal)

19.1.121 L_Not_7

This FB negates a signal of BOOL data type.



Inputs

Identifier	Data type	Value/meaning
bIn	BOOL	Input signal

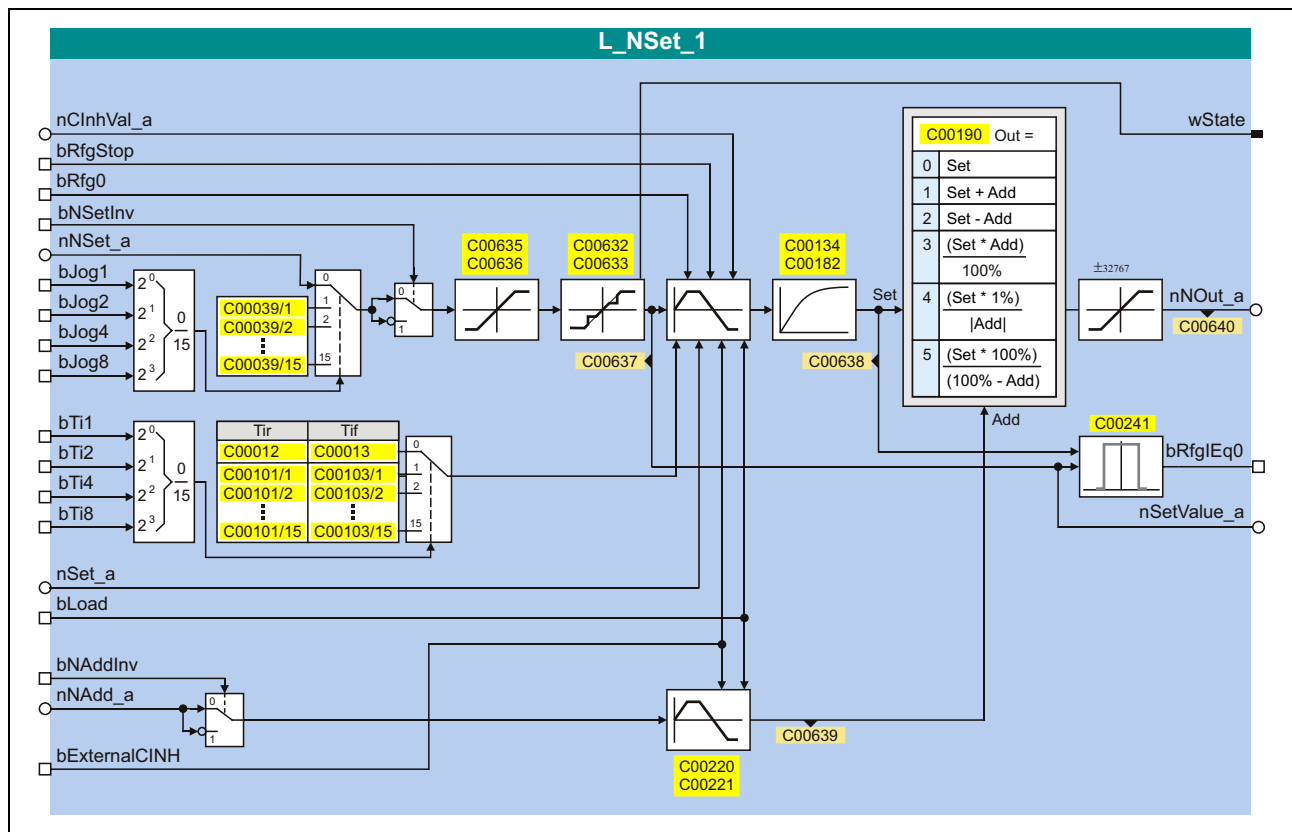
Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Result of the NOT operation (negated input signal)

19.1.122 L_NSet_1

This FB is used for general signal processing of process values and is provided with the following functions:

- Ramp function generator
 - With linear ramps for main and additional setpoint path
 - With S-shaped ramp (PT1 rounding)
 - Setting and holding
- Internal limitation of the input signal
- 3 adjustable blocking zones
- Arithmetic function
- 15 fixed setpoints (JOG setpoints)
- 15 acceleration and deceleration times



Inputs

Identifier	Data type	Information/possible settings
nClnhVal_a	INT	Main setpoint signal which is to be accepted by the main setpoint integrator when the controller is inhibited.
bRfgStop	BOOL	Holding (freezing) of the current value of the main setpoint integrator TRUE The current value of the main setpoint integrator is held.
bRfg0	BOOL	Leading the main setpoint integrator to 0 within the current Ti times TRUE The current value of the main setpoint integrator is led to "0" within the Ti time set.
bNsetInv	BOOL	Signal inversion for the main setpoint TRUE Main setpoint signal is inverted.
nNset_a	INT	Main setpoint signal • Other signals are also permitted
bJog1 ... bJog8	BOOL	Selection inputs for fixed changeover setpoints (JOG setpoints) for the main setpoint • Selection inputs are binary coded.
bTi1 ... bTi8	BOOL	Selection inputs for alternative acceleration/deceleration times for the main setpoint • Selection inputs are binary coded.
nSet_a	INT	Starting value which is loaded into the main setpoint integrator by setting <i>bLoad</i> to TRUE.
bLoad	BOOL	Control of both ramp function generators in special situations, e.g. QSP TRUE The <i>nSet_a</i> input signal is loaded into the main setpoint integrator and the additional setpoint integrator is set to "0".
bAddInv	BOOL	Signal inversion for the additional setpoint TRUE Additional setpoint signal is inverted.
nNAdd_a	INT	Additional setpoint signal • Other signals are also permitted
bExternalCINH	BOOL	Additional load input for the main setpoint integrator and the additional setpoint integrator TRUE The main setpoint integrator is set to the value applied at <i>nClnhVal_a</i> . The additional setpoint integrator is set to "0". ► Application example for the additional load function (1588)

Outputs

Identifier	Data type	Value/meaning
nNOut_a	INT	Speed setpoint output signal • Scaling: 16384 \equiv 100 %
bRfgIEQO	BOOL	Status signal "setpoint = 0"

Identifier	Data type	Value/meaning
wState	WORD	Bit-coded status word <ul style="list-style-type: none"> Bits that are not listed are reserved for future extensions.
		Bit 0 No blocking zone active
		Bit 1 Blocking zone 1 active
		Bit 2 Blocking zone 2 active
		Bit 3 Blocking zone 3 active
		Bit 4 Jog in blocking zone
		Bit 5 MaxLimit active
		Bit 6 MinLimit active
nSetValue_a	INT	Speed-setpoint input signal of the ramp function generator <ul style="list-style-type: none"> Scaling: 16384 \equiv 100 %

Parameter

Parameter	Possible settings			Info
C00012	0.000	s	999.900	Acceleration time T_{ir} for the main setpoint • Lenze setting: 0.000 s
C00013	0.000	s	999.900	Deceleration time T_{if} for the main setpoint • Lenze setting: 0.000 s
C00039/1..15	-199.99	%	199.99	Fixed setpoints (JOG setpoints) • Lenze setting: 0.00 %
C00101/1..15	0.000	s	999.900	Alternative acceleration times (T_{ir}) for the main setpoint • Lenze setting: 0.000 s
C00103/1..15	0.000	s	999.900	Alternative deceleration times (T_{if}) for the main setpoint • Lenze setting: 0.000 s
C00134				Activates ramp rounding with PT1 behaviour for the main setpoint • The corresponding S-ramp time must be set in C00182 . • Lenze setting: 0 (deactivated)
	0	Off		
	1	PT1 behaviour		
C00182	0.01	s	50.00	S-ramp time PT1 • Lenze setting: 20.00 s
C00190				Selection of the arithmetic function for combining main and additional setpoint
	0	NOut = NSet		Lenze setting • The additional setpoint is not processed.
	1	NOut = NSet + NAdd		
	2	NOut = NSet - NAdd		
	3	NOut = (NSet * NAdd) / 100%		
	4	NOut = (NSet * 1%) / NAdd		
	5	NOut = (NSet * 100%) / (100% - NAdd)		
C00220	0.000	s	999.900	Acceleration time T_{ir} for the additional setpoint • Lenze setting: 0.000 s

Parameter	Possible settings			Info
C00221	0.000	s	999.900	Deceleration time T_{if} for the additional setpoint • Lenze setting: 0.000 s
C00241	0.00	%	100.00	Hysteresis window for zero detection of speed output setpoint (output <i>bRfgIEqO</i>) • Lenze setting: 0.50 %
C00632/1...3	0.00	%	199.99	Maximum limit values for the speed blocking zones • Selection of the maximum limit values for the blocking zones in which the speed must not be constant. • Lenze setting: 0.00 %
C00633/1...3	0.00	%	199.99	Minimum limit values for the speed blocking zones • Selection of the minimum limit values for the blocking zones in which the speed must not be constant. • Lenze setting: 0.00 %
C00634				Status (bit-coded) • Bits that are not listed are reserved for future extensions.
	Bit 0	No blocking zone active		
	Bit 1	Blocking zone 1 active		
	Bit 2	Blocking zone 2 active		
	Bit 3	Blocking zone 3 active		
	Bit 4	Jog in blocking zone		
	Bit 5	MaxLimit active		
	Bit 6	MinLimit active		
C00635	-199.99	%	199.99	nMaxLimit • Maximum speed setpoint for speed setpoint limitation • Lenze setting: 199.99 %
C00636	-199.99	%	199.99	nMinLimit • Minimum speed setpoint for speed setpoint limitation • Lenze setting: -199.99 %
C00637	-199.99	%	199.99	Blocking zone output • Display of the speed setpoint after being processed by blocking zone function.
C00638	-199.99	%	199.99	Ramp smoothing output • Display of the speed setpoint after being processed by PT1 filter function.
C00639	-199.99	%	199.99	Additional value output • Display of the additional speed setpoint after being processed by ramp generator.
C00640	-199.99	%	199.99	Output nNOut_a • Display of the generated main speed setpoint at the <i>nNOut_a</i> output.

19.1.122.1 Main setpoint path

- The signals in the main setpoint path are limited to a value range of ± 32767 .
- The signal at *nNSet_a* is first led via the JOG selection function.
- A selected JOG value switches the *nNSet_a* input inactive. Then, the subsequent signal conditioning operates with the JOG value.

19.1.122.2 JOG setpoints

In addition to the direct main setpoint selection via the *nNSet_a* input, so-called JOG setpoints can be preset in [C00039/1...15](#).

- The JOG setpoints are binary-coded and can be called using the *bJog1* ... *bJog8* selection inputs so that 15 options are available:

Selection inputs				Main setpoint Main setpoint
<i>bJog8</i>	<i>bJog4</i>	<i>bJog2</i>	<i>bJog1</i>	
FALSE	FALSE	FALSE	FALSE	<i>nNset_a</i>
FALSE	FALSE	FALSE	TRUE	C00039/1
FALSE	FALSE	TRUE	FALSE	C00039/2
FALSE	FALSE	TRUE	TRUE	C00039/3
FALSE	TRUE	FALSE	FALSE	C00039/4
FALSE	TRUE	FALSE	TRUE	C00039/5
FALSE	TRUE	TRUE	FALSE	C00039/6
FALSE	TRUE	TRUE	TRUE	C00039/7
TRUE	FALSE	FALSE	FALSE	C00039/8
TRUE	FALSE	FALSE	TRUE	C00039/9
TRUE	FALSE	TRUE	FALSE	C00039/10
TRUE	FALSE	TRUE	TRUE	C00039/11
TRUE	TRUE	FALSE	FALSE	C00039/12
TRUE	TRUE	FALSE	TRUE	C00039/13
TRUE	TRUE	TRUE	FALSE	C00039/14
TRUE	TRUE	TRUE	TRUE	C00039/15

- The number of selection inputs to be assigned depends on the number of JOG setpoints required:

Number of JOG setpoints required	Number of selection inputs to be assigned (<i>bJog1</i> ... <i>bJog8</i>)
1	At least 1
2 ... 3	at least 2
4 ... 7	at least 3
8 ... 15	4

19.1.122.3 Setpoint inversion

The output signal of the JOG function is led via an inverter.

The sign of the setpoint changes if *bNSetInv* is set to TRUE.

19.1.122.4 Value range of the input signal

The value range of the input signal can be limited by using the following parameters:

- [C00635](#): MaxLimit (default setting: +199.99 %)
- [C00636](#): MinLimit (default setting: -199.99 %)

19.1.122.5 Skip frequency function

If the speed setpoints in speed-variable drives are linearly increasing, for instance, the frequency/speed range is divided into a number of equal time segments. Therefore, there may be speeds during acceleration time which must be bridged very fast (e.g. natural resonant frequencies).

The skip frequency function offers the opportunity to select a range in which the initial speed is maintained. If the speed setpoint leaves that range, the drive will be accelerated to reach the desired speed.



Note!

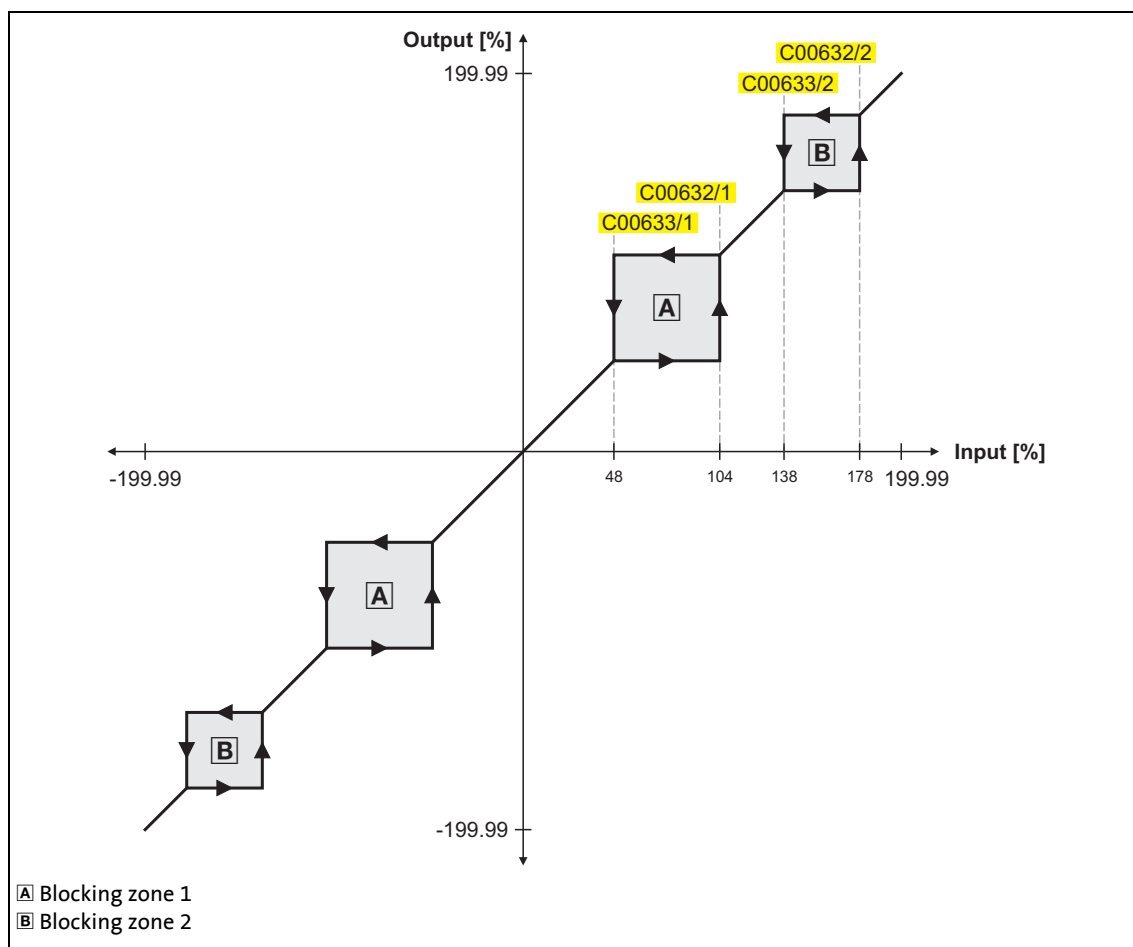
- Skip frequencies only affect main setpoints.
- It is not possible to exclude "0" speed if there is a sign reversal of the speed setpoint.

Definition of the blocking zones

The subcodes of codes [C00632](#) and [C00633](#) can be used to define three zones which are to be skipped by the output setpoint and which are to be passed as fast as possible by the ramp function generator.

The example below shows the parameter setting of two blocking zones:

Parameter	Blocking zone 1	Blocking zone 2	Blocking zone 3
Minimum limit value	C00633/1: 48 %	C00633/2: 138 %	C00633/3: 0 %
Maximum limit value	C00632/1: 104 %	C00632/2: 178 %	C00632/3: 0 %



[19-52] Zone masking by means of parameterisable blocking zones

- The parameterised blocking zones have the same effect on negative input signals.
- A blocking zone is deactivated by entering identical limit values (in our example: blocking zone 3).

Overlapping of blocking zones

If blocking zones overlap, the lowest and highest value of the overlapping zones form a new zone.

In this case, the status display (output *wState* or display parameter [C00634](#)) only indicates one zone (the lower of the two original zones).

Abutting blocking zones

If two blocking zones abut (e.g. 20 ... 30 % and 30 ... 40 %), the limit value between the two zones (in this example 30 %) is also passed through.

The same applies to a limit range of 0 ... xx %. During zero crossing of the speed setpoint, "0" speed is output as setpoint. It is possible to exclude "0" speed. However, in this case, the output speed will remain on the upper limit value when the input setpoint becomes "0".

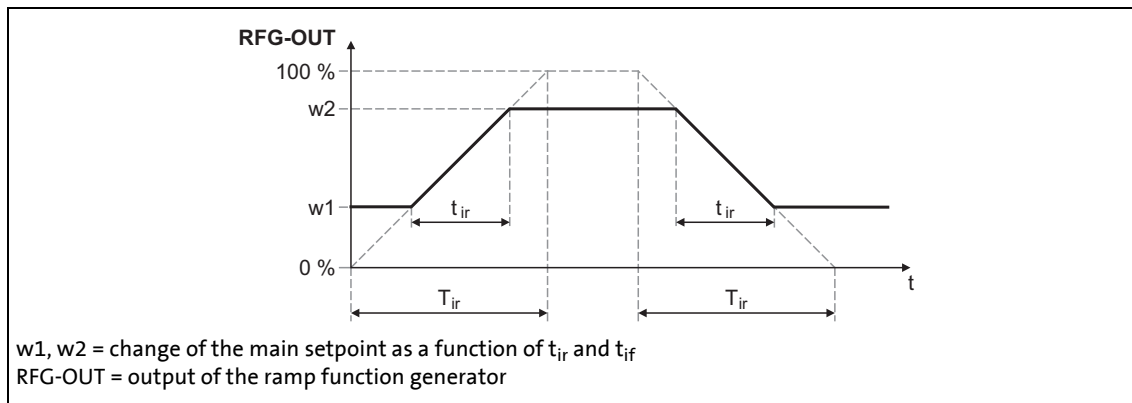


Tip!

As described above, the acceleration phase starts after the blocking zones have been passed through. The ramp function generator integrated in the **L_Nset** function block limits the progression of the speed. For this reason, the time values set for the integrated ramp function generator should be as low as possible whereas the setpoint for the **L_Nset** function block should be generated by a ramp function generator with higher time values (e.g. **L_MPot** function block).

19.1.122.6 Ramp function generator for the main setpoint

The setpoint is now led via a ramp function generator with linear characteristic. The ramp function generator converts setpoint step-changes at the input into a ramp.



[19-53] Acceleration and deceleration times

- t_{ir} and t_{if} are the desired times for changing between $w1$ and $w2$.
- S-ramps are possible by selecting S-ramp times.
- The t_{ir}/t_{if} values are converted into the required T_i times according to the following formula:

$$T_{ir} = t_{ir} \cdot \frac{100\%}{w2 - w1}$$

$$T_{if} = t_{if} \cdot \frac{100\%}{w2 - w1}$$

Setting and selection of Ti times

Via parameters, you can select 16 different *Tir* and *Tif* times each for the ramp function generator.

- The selection is made via the binary coded selection inputs *bTI1* ... *bTI8*:

Selection inputs				Used Acceleration time	Used Deceleration time
<i>bTI8</i>	<i>bTI4</i>	<i>bTI2</i>	<i>bTI1</i>		
FALSE	FALSE	FALSE	FALSE	C00012	C00013
FALSE	FALSE	FALSE	TRUE	C00101/1	C00103/1
FALSE	FALSE	TRUE	FALSE	C00101/2	C00103/2
FALSE	FALSE	TRUE	TRUE	C00101/3	C00103/3
FALSE	TRUE	FALSE	FALSE	C00101/4	C00103/4
FALSE	TRUE	FALSE	TRUE	C00101/5	C00103/5
FALSE	TRUE	TRUE	FALSE	C00101/6	C00103/6
FALSE	TRUE	TRUE	TRUE	C00101/7	C00103/7
TRUE	FALSE	FALSE	FALSE	C00101/8	C00103/8
TRUE	FALSE	FALSE	TRUE	C00101/9	C00103/9
TRUE	FALSE	TRUE	FALSE	C00101/10	C00103/10
TRUE	FALSE	TRUE	TRUE	C00101/11	C00103/11
TRUE	TRUE	FALSE	FALSE	C00101/12	C00103/12
TRUE	TRUE	FALSE	TRUE	C00101/13	C00103/13
TRUE	TRUE	TRUE	FALSE	C00101/14	C00103/14
TRUE	TRUE	TRUE	TRUE	C00101/15	C00103/15

Function

- When the controller is inhibited (CINH), the ramp function generator accepts the value applied at *nCInhVal_a* and transfers it to the downstream function. This function has priority over all other functions.
- bRfgStop* = TRUE
 - The ramp function generator is stopped. Changes at the input of the ramp function generator have no effect on the output signal.
- bRfg0* = TRUE
 - The ramp function generator runs to 0 along its deceleration ramp.
- Furthermore it is possible to load the ramp function generator online with a defined value. For this purpose, *bLoad* must be set to TRUE. As long as this input is set, the value at *nSet_a* is transferred to the ramp function generator and provided at the output.

Priorities:

CINH	bLoad	bRfg0	bRfgStop	Function
FALSE	FALSE	FALSE	FALSE	The ramp function generator follows the input value via the set ramps.
FALSE	FALSE	FALSE	TRUE	Stop the ramp function generator: The value at the output of the ramp function generator is held.
FALSE	FALSE	TRUE	FALSE	Ramp down the ramp function generator: The ramp function generator runs to 0 within the set deceleration time.
FALSE	FALSE	TRUE	TRUE	
FALSE	TRUE	FALSE	FALSE	Load ramp function generator online: The ramp function generator accepts the value at <i>nSet_a</i> and provides it at its output.
FALSE	TRUE	FALSE	TRUE	
FALSE	TRUE	TRUE	FALSE	
FALSE	TRUE	TRUE	TRUE	
TRUE	FALSE	FALSE	FALSE	Controller inhibit: The ramp function generator accepts the value at <i>nClnhVal_a</i> and provides it at its output.
TRUE	FALSE	FALSE	TRUE	
TRUE	FALSE	TRUE	FALSE	
TRUE	FALSE	TRUE	TRUE	
TRUE	TRUE	FALSE	FALSE	
TRUE	TRUE	FALSE	TRUE	
TRUE	TRUE	TRUE	FALSE	
TRUE	TRUE	TRUE	TRUE	

19.1.122.7 S-shaped ramp

A PT1 element is connected downstream of the linear ramp function generator. This arrangement implements an S-shaped ramp for a nearly jerk-free acceleration and deceleration.

- The PT1 element can be switched on/off via the *bSShapeActive* input.
- The corresponding S-ramp time can be set under [C00182](#).

19.1.122.8 Additional setpoint

Use the *nNAdd_a* input to define an additional value (e.g. a correcting signal) and combine it arithmetically with the main setpoint *nNSet_a*.

- First, the additional setpoint is led via a ramp function generator with linear characteristic. Its Ti times can be set in [C00220](#) (acceleration time) and [C00221](#) (deceleration time).
- When the input *bNAddInv* is set to TRUE, the additional setpoint can be inverted before having an effect on the ramp function generator.
- When the input *bLoad* is set to TRUE, the ramp function generator is set to zero for the additional setpoint and held there without considering the Ti times. The same applies when the controller is inhibited.
- The following arithmetic combination of main setpoint and additional setpoint can be selected in [C00190](#):

Value in C00190	Function	Info
0	$nNOut_a = nNSet_a$	The additional setpoint <i>nNAdd_a</i> is not processed.
1	$nNOut_a = nNSet_a + nNAdd_a$	
2	$nNOut_a = nNSet_a - nNAdd_a$	
3	$nNOut_a = (nNSet_a * nNAdd_a) / 100 \%$	Internal scaling: • 100 % \equiv 16384 • 1 % \equiv 164
4	$nNOut_a = (nNSet_a * 1 \%) / nNAdd_a $	
5	$nNOut_a = (nNSet_a * 100 \%) / (100 \% - nNAdd_a)$	

19.1.122.9 Application example for the additional load function

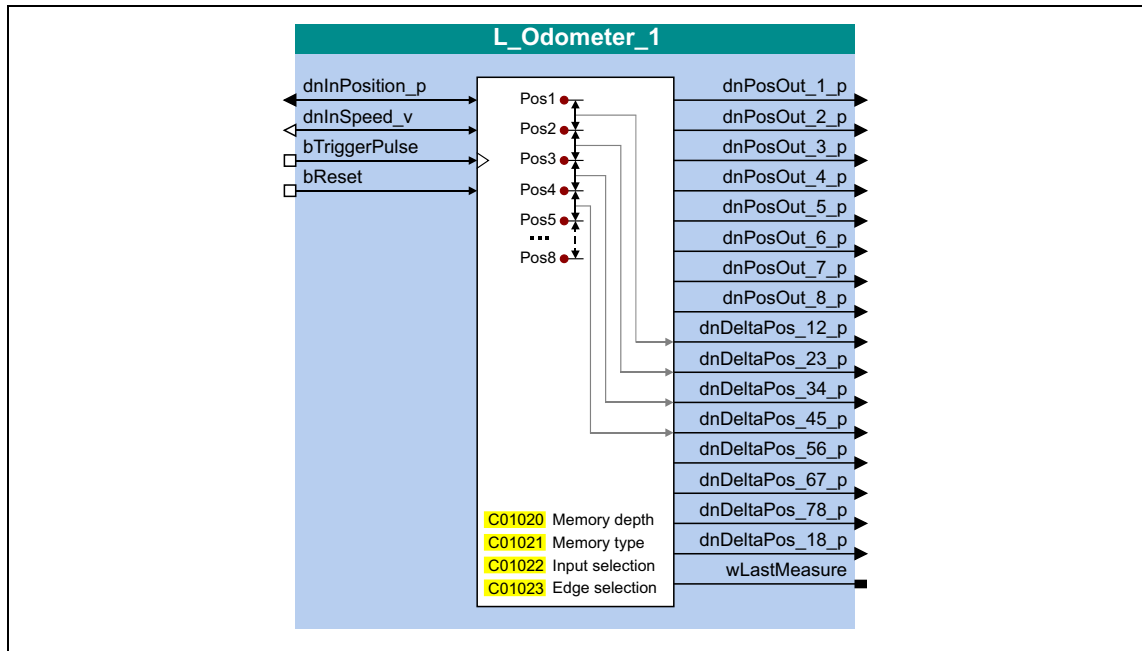
The motor control of the drive is provided with a function for automatically carrying along ramp function generators for "jerk-free" setpoint connection. For speed-controlled drive tasks, the [LS_MotorInterface](#) SB outputs the current actual speed value via the *nHlgSetValue_a* output (e.g. in case of a pulse inhibit, flying restart, controller inhibit).

- In case of a pulse inhibit, the main setpoint generator must be carried along with the current actual speed value to ensure jerk-free setpoint transfer.
- The actual speed value is carried along automatically if the following wiring is provided:
 - [LS_MotorInterface.nHlgSetValue_a](#) \rightarrow [L_NSet_1.nClnhValue_a](#)
 - [LS_MotorInterface.bHlgLoad](#) \rightarrow [L_NSet_1.bExternalCINH](#)

19.1.123 L_Odometer_1

This FB is used to detect positions and calculate distances.

- Depending on the input selection set in [C01022](#), a position signal can be detected at the *dnInPosition_p* input or a speed can be detected at the *nInSpeed_v* input.
- The position is detected/accepted via the edge selected in [C01023](#) at the *bTriggerPulse* input.
- If "Ring buffer" is selected in [C01021](#), the measurement will start all over again after the number of measurements selected in [C01020](#) has been performed and the old values will be overwritten. Otherwise, the measurement will stop.



Inputs

Identifier	Data type	Information/possible settings
dnInPosition_p	DINT	Position measurement input <ul style="list-style-type: none"> Input is only evaluated if C01022 = "0: Pos input" has been set.
nInSpeed_v	INT	Speed measurement input <ul style="list-style-type: none"> The speed is internally integrated into a position. Input is only evaluated if C01022 = "1: V input" has been set.
bTriggerPulse	BOOL	Detect position/speed <ul style="list-style-type: none"> The tripping edge can be parameterised in C01023.
bReset	BOOL	Reset measurement results and internal integrator
	TRUE	Reset measurement results and internal integrator.

Outputs

Identifier Data type	Value/meaning
dnPosOut_1_p ... dnPosOut_8_p DINT	Detected positions
dnDeltaPos_12_p dnDeltaPos_23_p dnDeltaPos_34_p ... dnDeltaPos_18_p DINT	Calculated distances between the detected positions <ul style="list-style-type: none"> • <i>dnDeltaPos_12_p</i> = Distance between <i>dnPosOut_1_p</i> and <i>dnPosOut_1_p</i> • <i>dnDeltaPos_23_p</i> = Distance between <i>dnPosOut_2_p</i> and <i>dnPosOut_3_p</i> • <i>dnDeltaPos_34_p</i> = Distance between <i>dnPosOut_3_p</i> and <i>dnPosOut_4_p</i> ... • <i>dnDeltaPos_18_p</i> = Distance between <i>dnPosOut_1_p</i> and <i>dnPosOut_8_p</i>
wLastMeasure WORD	Memory location number (1 ... 8) of the last measurement

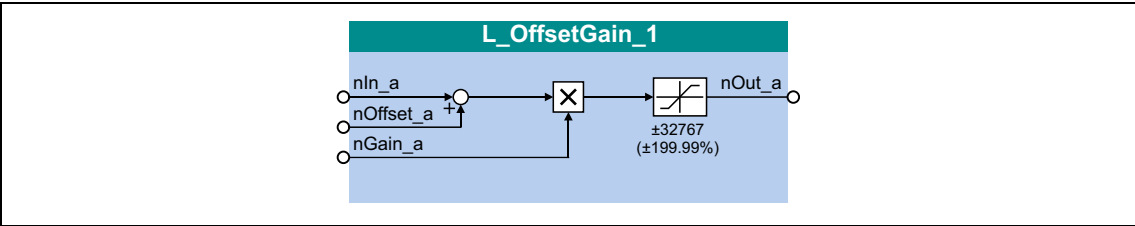
Parameter

Parameter	Possible settings	Info
C01020		Memory length • Lenze setting: 7 measurements
	1 1 measurement	
	2 2 measurements	
	
	7 7 measurements	
C01021		Memory type • Lenze setting: No ring buffer
	0 No ring buffer	
	1 Ring buffer	
C01022		Input selection • Lenze setting: Pos input
	0 Pos input	
	1 V input	
C01023		Edge selection • Lenze setting: HIGH edge
	0 High edge	
	1 Low edge	
	2 High and low edge	

19.1.124 L_OffsetGain_1

This FB can add an offset to an analog input signal and then amplify it. Preferably to be interconnected directly after the analog input terminals.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Offset and gain are selected via FB inputs.
- The value provided at the *nOut_a* output is internally limited to ±199.99 %.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal • Scaling: 16384 ≡ 100 %
nOffset_a	INT	Offset • Scaling: 16384 ≡ 100 %
nGain_a	INT	Gain factor • Scaling: 16384 ≡ 100 % • 199.99 % ≈ 2

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal • Internal limitation to ±199.99 %

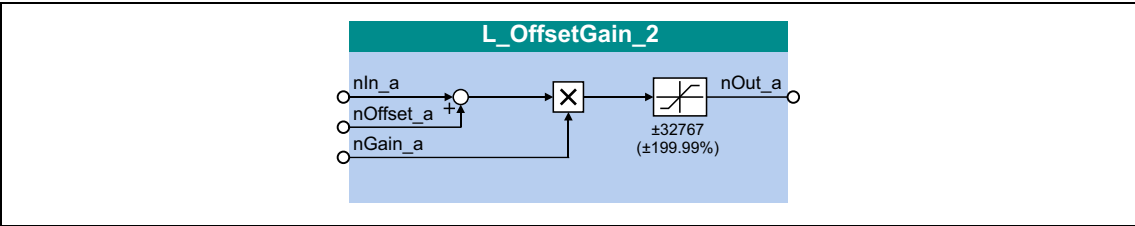
Function

$$nOut_a = (nIn_a + Offset) \cdot Gain\ factor$$

19.1.125 L_OffsetGain_2

This FB can add an offset to an analog input signal and then amplify it. Preferably to be interconnected directly after the analog input terminals.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Offset and gain are selected via FB inputs.
- The value provided at the *nOut_a* output is internally limited to $\pm 199.99\%$.



Inputs

Identifier	Data type	Information/possible settings
<i>nIn_a</i>	INT	Input signal • Scaling: 16384 \equiv 100 %
<i>nOffset_a</i>	INT	Offset • Scaling: 16384 \equiv 100 %
<i>nGain_a</i>	INT	Gain factor • Scaling: 16384 \equiv 100 % • 199.99 % \approx 2

Outputs

Identifier	Data type	Value/meaning
<i>nOut_a</i>	INT	Output signal • Internal limitation to $\pm 199.99\%$

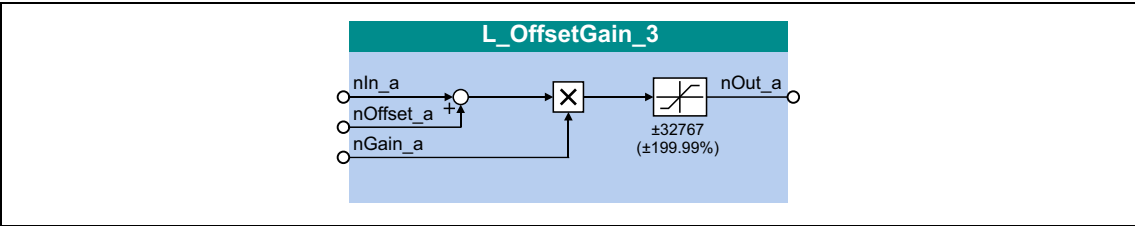
Function

$$nOut_a = (nIn_a + Offset) \cdot Gain\ factor$$

19.1.126 L_OffsetGain_3

This FB can add an offset to an analog input signal and then amplify it. Preferably to be interconnected directly after the analog input terminals.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Offset and gain are selected via FB inputs.
- The value provided at the *nOut_a* output is internally limited to $\pm 199.99\%$.



Inputs

Identifier	Data type	Information/possible settings
<i>nIn_a</i>	INT	Input signal • Scaling: 16384 \equiv 100 %
<i>nOffset_a</i>	INT	Offset • Scaling: 16384 \equiv 100 %
<i>nGain_a</i>	INT	Gain factor • Scaling: 16384 \equiv 100 % • 199.99 % \approx 2

Outputs

Identifier	Data type	Value/meaning
<i>nOut_a</i>	INT	Output signal • Internal limitation to $\pm 199.99\%$

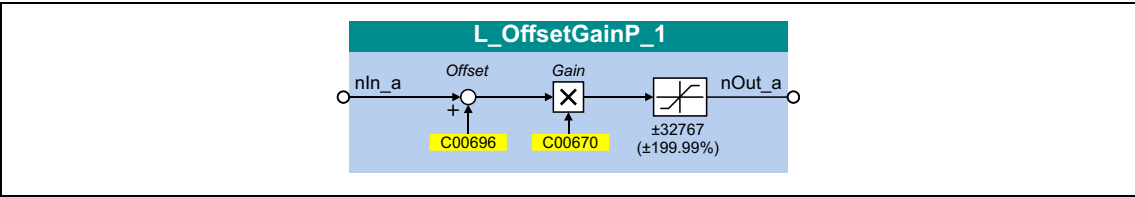
Function

$$nOut_a = (nIn_a + Offset) \cdot Gain\ factor$$

19.1.127 L_OffsetGainP_1

This FB can add an offset to an analog input signal and amplify it afterwards. Preferably to be interconnected directly after the analog input terminals.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Offset and gain are selected via parameters.
- The value provided at the *nOut_a* output is internally limited to ±199.99 %.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal <ul style="list-style-type: none">• Internal limitation to ±199.99 %

Parameter

Parameter	Possible settings			Info
C00670	-100.0000		100.0000	Gain factor <ul style="list-style-type: none">• High gain factor for further processing of smallest input signals.• Please observe the difference with regard to the gain factors of other blocks in percent (±199.99 % ≈ 2).• Lenze setting: 1.0000
C00696	-199.99	%	199.99	Offset <ul style="list-style-type: none">• Lenze setting: 0.00 %

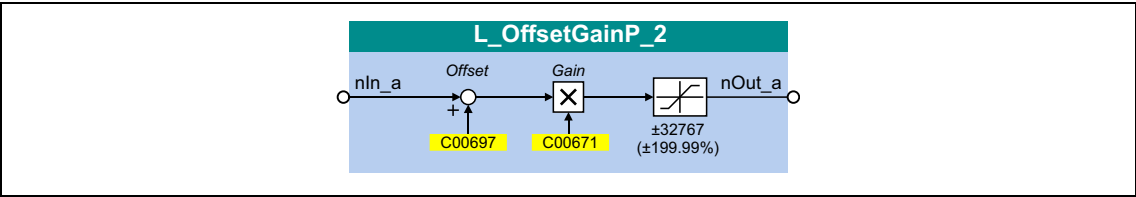
Function

$$nOut_a = (nIn_a + Offset) \cdot Gain\ factor$$

19.1.128 L_OffsetGainP_2

This FB can add an offset to an analog input signal and amplify it afterwards. Preferably to be interconnected directly after the analog input terminals.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Offset and gain are selected via parameters.
- The value provided at the *nOut_a* output is internally limited to ±199.99 %.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal • Internal limitation to ±199.99 %

Parameter

Parameter	Possible settings			Info
C00671	-100.0000		100.0000	Gain factor • High gain factor for further processing of smallest input signals. • Please observe the difference with regard to the gain factors of other blocks in percent (±199.99 % ≈ 2). • Lenze setting: 1.0000
C00697	-199.99	%	199.99	Offset • Lenze setting: 0.00 %

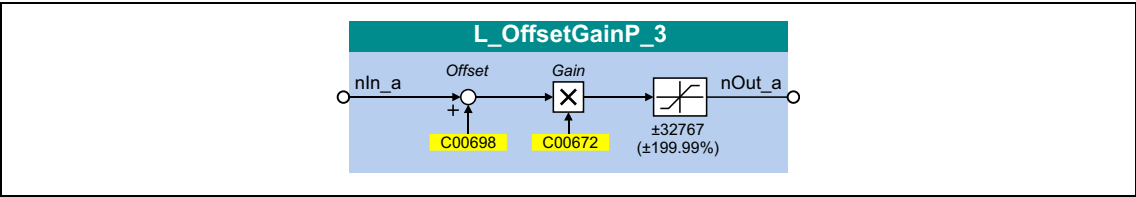
Function

$$nOut_a = (nIn_a + Offset) \cdot Gain\ factor$$

19.1.129 L_OffsetGainP_3

This FB can add an offset to an analog input signal and amplify it afterwards. Preferably to be interconnected directly after the analog input terminals.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Offset and gain are selected via parameters.
- The value provided at the *nOut_a* output is internally limited to ±199.99 %.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal <ul style="list-style-type: none">• Internal limitation to ±199.99 %

Parameter

Parameter	Possible settings			Info
C00672	-100.0000		100.0000	Gain factor <ul style="list-style-type: none">• High gain factor for further processing of smallest input signals.• Please observe the difference with regard to the gain factors of other blocks in percent (±199.99 % ≈ 2).• Lenze setting: 1.0000
C00698	-199.99	%	199.99	Offset <ul style="list-style-type: none">• Lenze setting: 0.00 %

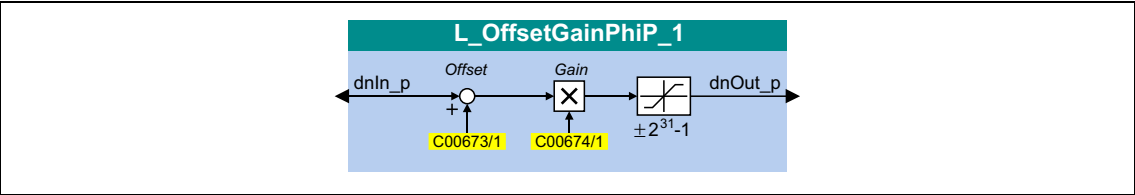
Function

$$nOut_a = (nIn_a + Offset) \cdot Gain\ factor$$

19.1.130 L_OffsetGainPhiP_1

This FB can add an offset to an angle signal and amplify it afterwards.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Offset and gain are selected via parameters.
- The value provided at the *dnOut_p* output is internally limited to $\pm 2^{31}-1$.



Inputs

Identifier	Data type	Information/possible settings
dnIn_p	DINT	Input signal

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal <ul style="list-style-type: none">• Internal limitation to $\pm 2^{31}-1$ (± 2147483647)

Parameter

Parameter	Possible settings			Info
C00673/1	-2147483647	Incr.	2147483647	Offset <ul style="list-style-type: none">• Lenze setting: 0 incr.
C00674/1	-2147483647		2147483647	Gain factor <ul style="list-style-type: none">• Scaling: 65535 \equiv gain factor 1• Lenze setting: 65536

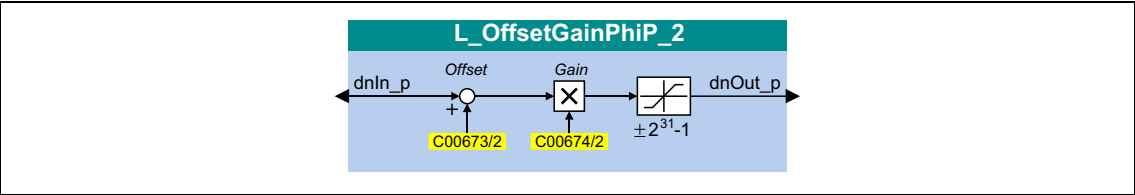
Function

$$dnOut_p = (dnIn_p + Offset) \cdot Gain\ factor$$

19.1.131 L_OffsetGainPhiP_2

This FB can add an offset to an angle signal and amplify it afterwards.

- The internal calculations (addition and subtraction) are carried out with 32 bits without overflow/underflow. Division is not remainder considered.
- Offset and gain are selected via parameters.
- The value provided at the *dnOut_p* output is internally limited to $\pm 2^{31}-1$.



Inputs

Identifier	Data type	Information/possible settings
dnIn_p	DINT	Input signal

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal <ul style="list-style-type: none">• Internal limitation to $\pm 2^{31}-1$ (± 2147483647)

Parameter

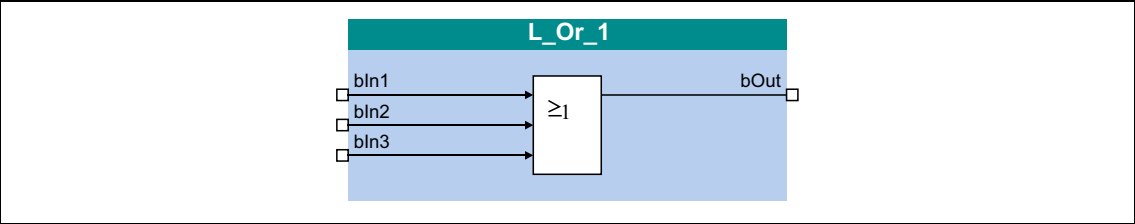
Parameter	Possible settings			Info
C00673/2	-2147483647	Incr.	2147483647	Offset <ul style="list-style-type: none">• Lenze setting: 0 incr.
C00674/2	-2147483647		2147483647	Gain factor <ul style="list-style-type: none">• Scaling: 65535 \equiv gain factor 1• Lenze setting: 65536

Function

$$dnOut_p = (dnIn_p + Offset) \cdot Gain\ factor$$

19.1.132 L_Or_1

This FB implements the ORing of the inputs signals.



Inputs

Identifier	Data type	Information/possible settings
bIn1 bIn2 bIn3	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal

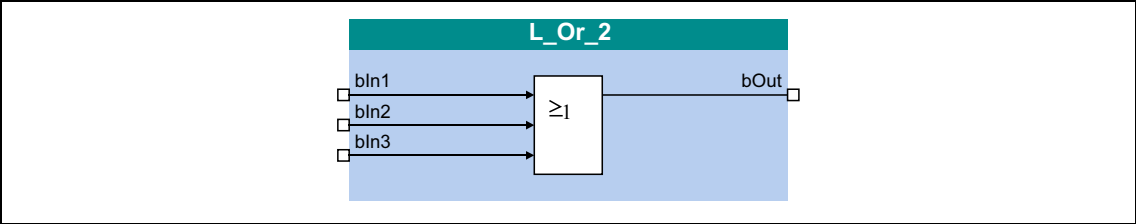
Function

Inputs			Output
bIn3	bIn2	bIn1	bOut
FALSE	FALSE	FALSE	FALSE
FALSE	FALSE	TRUE	TRUE
FALSE	TRUE	FALSE	
FALSE	TRUE	TRUE	
TRUE	FALSE	FALSE	
TRUE	FALSE	TRUE	
TRUE	TRUE	FALSE	
TRUE	TRUE	TRUE	

[19-54] Truth table of the FB L_Or_1

19.1.133 L_Or_2

This FB implements the ORing of the inputs signals.



Inputs

Identifier	Data type	Information/possible settings
bIn1 bIn2 bIn3	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal

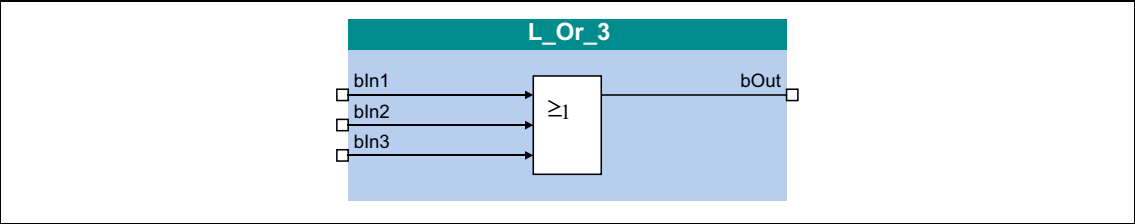
Function

Inputs			Output
bIn3	bIn2	bIn1	bOut
FALSE	FALSE	FALSE	FALSE
FALSE	FALSE	TRUE	TRUE
FALSE	TRUE	FALSE	
FALSE	TRUE	TRUE	
TRUE	FALSE	FALSE	
TRUE	FALSE	TRUE	
TRUE	TRUE	FALSE	
TRUE	TRUE	TRUE	

[19-55] Truth table of the FB L_Or_2

19.1.134 L_Or_3

This FB implements the ORing of the inputs signals.



Inputs

Identifier	Information/possible settings
<div><div>bIn1</div><div>bIn2</div><div>bIn3</div><div>BOOL</div></div>	Input signal

Outputs

Identifier	Value/meaning
<div><div>bOut</div><div>BOOL</div></div>	Output signal

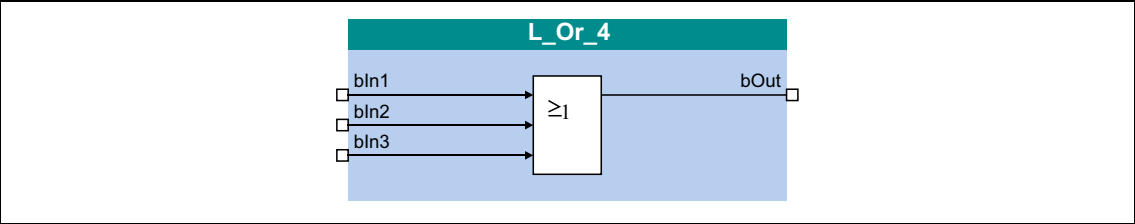
Function

Inputs			Output
bIn3	bIn2	bIn1	bOut
FALSE	FALSE	FALSE	FALSE
FALSE	FALSE	TRUE	TRUE
FALSE	TRUE	FALSE	
FALSE	TRUE	TRUE	
TRUE	FALSE	FALSE	
TRUE	FALSE	TRUE	
TRUE	TRUE	FALSE	
TRUE	TRUE	TRUE	

[19-56] Truth table of the L_Or_3 FB

19.1.135 L_Or_4

This FB implements the ORing of the inputs signals.



Inputs

Identifier	Information/possible settings
<div><div>bIn1</div><div>bIn2</div><div>bIn3</div></div> <div>BOOL</div>	Input signal

Outputs

Identifier	Value/meaning
<div><div>bOut</div><div>BOOL</div></div>	Output signal

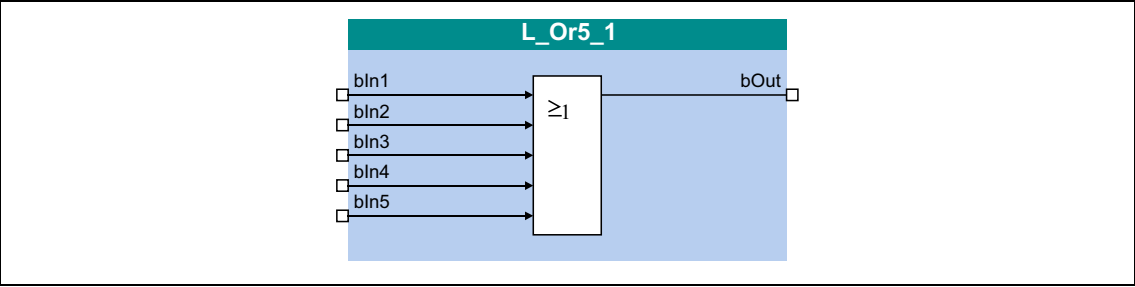
Function

Inputs			Output
bIn3	bIn2	bIn1	bOut
FALSE	FALSE	FALSE	FALSE
FALSE	FALSE	TRUE	TRUE
FALSE	TRUE	FALSE	
FALSE	TRUE	TRUE	
TRUE	FALSE	FALSE	
TRUE	FALSE	TRUE	
TRUE	TRUE	FALSE	
TRUE	TRUE	TRUE	

[19-57] Truth table of the L_Or_4 FB

19.1.136 L_Or5_1

This FB implements the ORing of the inputs signals.



Inputs

Identifier	Data type	Information/possible settings
bIn1 ... bIn5	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal

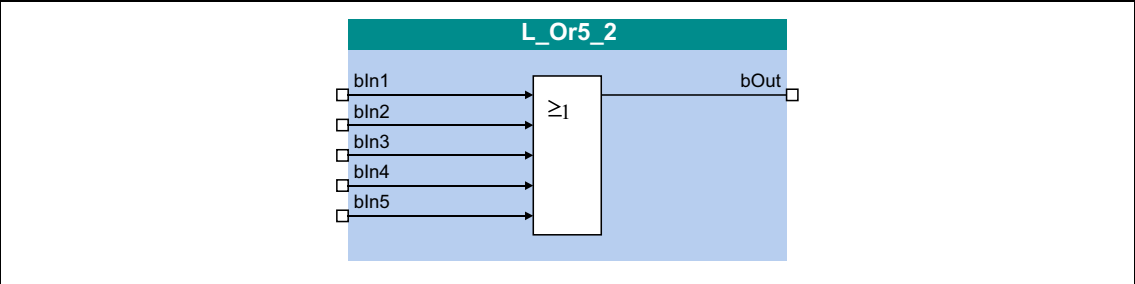
Function

Inputs					Output
bIn5	bIn4	bIn3	bIn2	bIn1	bOut
FALSE	FALSE	FALSE	FALSE	FALSE	FALSE
FALSE	FALSE	FALSE	FALSE	TRUE	TRUE
FALSE	FALSE	FALSE	TRUE	FALSE	
FALSE	FALSE	FALSE	TRUE	TRUE	
FALSE	FALSE	TRUE	FALSE	FALSE	
...					
TRUE	TRUE	TRUE	FALSE	TRUE	
TRUE	TRUE	TRUE	TRUE	FALSE	
TRUE	TRUE	TRUE	TRUE	TRUE	

[19-58] Truth table of the FB L_Or5_1

19.1.137 L_Or5_2

This FB implements the ORing of the inputs signals.



Inputs

Identifier	Data type	Information/possible settings
bIn1 ... bIn5	BOOL	Input signal

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal

Function

Inputs					Output
bIn5	bIn4	bIn3	bIn2	bIn1	bOut
FALSE	FALSE	FALSE	FALSE	FALSE	FALSE
FALSE	FALSE	FALSE	FALSE	TRUE	TRUE
FALSE	FALSE	FALSE	TRUE	FALSE	
FALSE	FALSE	FALSE	TRUE	TRUE	
FALSE	FALSE	TRUE	FALSE	FALSE	
...					
TRUE	TRUE	TRUE	FALSE	TRUE	
TRUE	TRUE	TRUE	TRUE	FALSE	
TRUE	TRUE	TRUE	TRUE	TRUE	

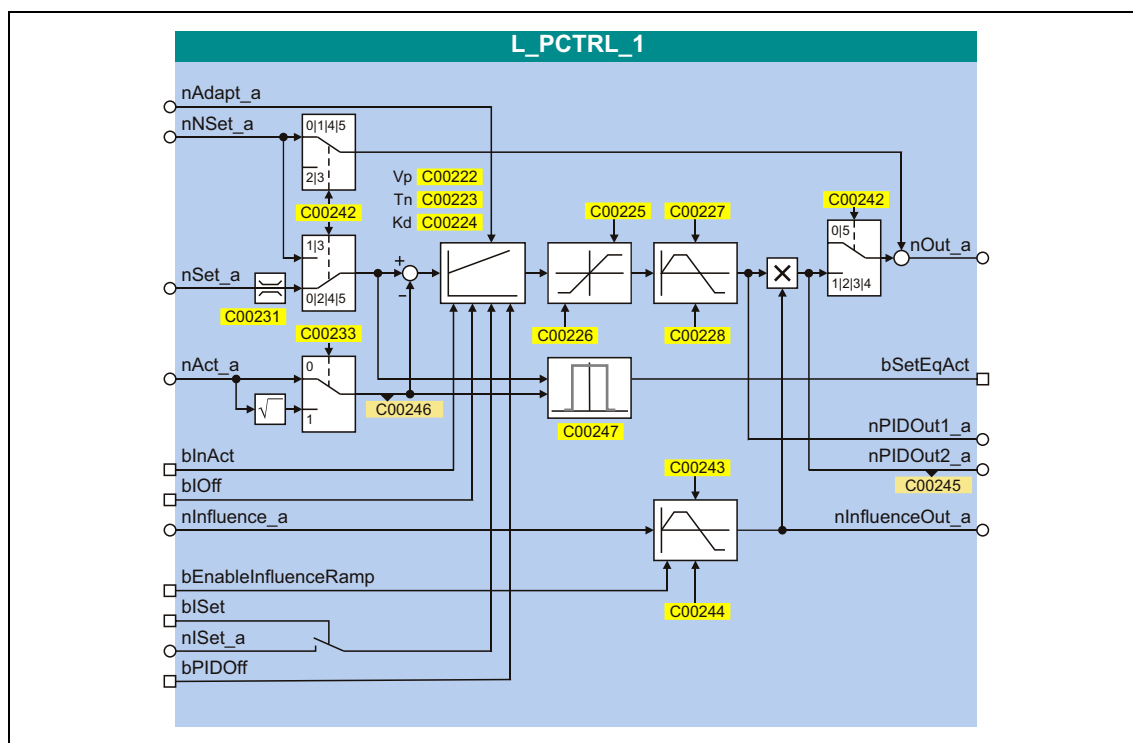
[19-59] Truth table of the FB L_Or5_2

19.1.138 L_PCTRL_1

This FB is a PID controller and can be used for various control tasks (e.g. as dancer position controller, tension controller, or pressure controller).

The FB is provided with the following functions:

- Adjustable control algorithm (P, PI, PID)
- Ramp function generator for preventing setpoint step-changes at the input
- Limitation of the controller output
- Factorisation of the output signal
- Vp adaptation
- Integral action component can be switched off
- Comparison function "Actual value = setpoint"



Inputs

Identifier	Data type	Information/possible settings
nAdapt_a	INT	<p>Percentage adaptation of the gain Vp set in C00222 and the reset time Tn set in C00223.</p> <p>Then, the adapted reset time is as follows:</p> $T_n = \frac{V_{pC222} \cdot nAdapt_a [\%] \cdot T_{nC223} [ms]}{100 [\%]}$ <ul style="list-style-type: none"> • Internal limitation to $\pm 199.99 \%$ • Changes can be done online. • Display parameter: C00830/62
nNset_a	INT	<p>Speed setpoint</p> <ul style="list-style-type: none"> • Scaling: $16384 \equiv 100 \%$ • Internal limitation to $\pm 199.99 \%$ • Display parameter: C00830/89

Identifier	Data type	Information/possible settings	
nSet_a	INT	Sensor and process setpoint for operating modes 2, 4 and 5 <ul style="list-style-type: none">• Scaling: 16384 ≡ 100 %• Internal limitation to ± 199.99 %• Display parameter: C00830/63	
nAct_a	INT	Speed or actual sensor value (actual process value) <ul style="list-style-type: none">• Scaling: 16384 ≡ 100 %• Internal limitation to ± 199.99 %• Display parameter: C00830/61	
bInAct	BOOL	Deactivate process controller temporarily (stop) <ul style="list-style-type: none">• Changes can be done online.• Display parameter: C00833/76 Note: This input is not interconnected in the LA_NCtrl application block.	
		TRUE	<ul style="list-style-type: none">• The current output value is frozen.• The internal control algorithm is stopped.• However, a setpoint selected via input <i>nNSet_a</i> is still provided in operating modes 0/1/4/5.
bIOff	BOOL	Switch off the I-component of the process controller <ul style="list-style-type: none">• Changes can be done online.• Display parameter: C00833/77	
		TRUE	The I component of the process controller is set to zero.
nInfluence_a	INT	Limitation of the influencing factor in percent <ul style="list-style-type: none">• <i>nInfluence_a</i> serves to limit the influencing factor of the PID controller contained in the FB to a required value (- 199.99 % ... + 199.99 %).• Scaling: 16384 ≡ 100 %• Internal limitation to ± 199.99 %• Display parameter: C00830/64	
bEnableInfluenceRamp	BOOL	Activate ramp for influencing factor <ul style="list-style-type: none">• Display parameter: C00833/106	
		TRUE	Influencing factor of the PID controller is ramped up to the <i>nInfluence_a</i> value.
		FALSE	Influencing factor of the PID controller is ramped down to "0".
bISet	BOOL	Accept I component <i>nISet_a</i> in PID controller	
		TRUE	The value at the input <i>nISet_a</i> is accepted in the PID controller.
nISet_a	INT	Selection of I component of PID controller <ul style="list-style-type: none">• With a TRUE signal at <i>bISet</i>, the assigned value is accepted in the PID controller.• Scaling: 16384 ≡ 100 %• Internal limitation to ± 199.99 %	
bPIDOff	BOOL	Reset the entire PID controller	
		TRUE	<ul style="list-style-type: none">• The I component of the controller is set to zero.• The controller output is set to zero.• The internal control algorithm is stopped.

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Output signal <ul style="list-style-type: none"> Internal limitation to ± 32767 ($\pm 199.99\%$) Scaling: $16384 \equiv 100\%$
bSetEqAct	INT	Comparison function "Actual value = setpoint" <ul style="list-style-type: none"> The window for the comparison operation can be set in C00247.
		TRUE Setpoint and actual value are identical, i.e. no system deviation available.
nPIDOut1_a	INT	PID controller output <u>without</u> influencing factor <i>nInfluence_a</i> <ul style="list-style-type: none"> Inputs <i>bEnableInfluenceRamp</i> and <i>nInfluence_a</i> do not have any effect here, the limited PID output value influenced by the internal ramp times is output. There is no connection with the additive input <i>nNSet_a</i>. Scaling: $16384 \equiv 100\%$
nPIDOut2_a	INT	PID controller output <u>with</u> influencing factor <i>nInfluence_a</i> . <ul style="list-style-type: none"> There is no connection with the additive input <i>nNSet_a</i>. Scaling: $16384 \equiv 100\%$ Display parameter: C00245
nInfluenceOut_a	INT	Current influencing factor ("ramp status") on the PID output value <ul style="list-style-type: none"> Scaling: $16384 \equiv 100\%$

Parameter

Parameter	Possible settings			Info
C00222	0.1	0.1	500.0	Gain Vp <ul style="list-style-type: none"> Lenze setting: 1.0
C00223	20	ms	6000	Reset time Tn <ul style="list-style-type: none"> Lenze setting: 400 ms
C00224	0.0	0.1	5.0	Differential component Kd <ul style="list-style-type: none"> Lenze setting: 0.0
C00225	-199.99	%	+199.99	MaxLimit <ul style="list-style-type: none"> Maximum value of the PID operating range Lenze setting: 199.99 %
C00226	-199.99	%	+199.99	MinLimit <ul style="list-style-type: none"> Minimum value of the PID operating range Lenze setting: -199.99 %
C00227	0.000	s	999.999	Acceleration time for the ramp at the PID output (should be set as steep as possible) <ul style="list-style-type: none"> Lenze setting: 0.010 s
C00228	0.000	s	999.999	Deceleration time for the ramp at the PID output <ul style="list-style-type: none"> Lenze setting: 0.010 s
C00231/1 (Pos. Maximum) C00231/2 (Pos. Minimum) C00231/3 (Neg. Minimum) C00231/4 (Neg. Maximum)	0.00	%	199.99	Operating range <ul style="list-style-type: none"> Determination of the operating range for the PID process controller by limiting the input signal <i>nSet_a</i>. Lenze setting: No limitation (-199.99 % ... +199.99 %)

Parameter	Possible settings			Info
C00233				Root function • Lenze setting: "0: Off"
	0	Off		The actual value at <i>nAct_a</i> is not changed for further processing.
	1	On		The square root of the actual value at <i>nAct_a</i> is taken for further processing.
C00242				Operating mode • Lenze setting: "0: Off"
	0	Off		The input setpoint <i>nNSet_a</i> is output without any changes at the output <i>nOut_a</i> .
	1	<i>nNSet</i> + <i>nNSet_PID</i>		<i>nNSet_a</i> and <i>nAct_a</i> are used as PID input values. The arriving <i>nNSet_a</i> is additively linked to the value output by the PID element.
	2	<i>nSet_PID</i>		<i>nSet_a</i> and <i>nAct_a</i> are used as PID input values. The input <i>nNSet_a</i> is not considered.
	3	<i>nNSet_PID</i>		<i>nNSet_a</i> and <i>nAct_a</i> are used as PID input values. The input <i>nSet_a</i> is not considered.
	4	<i>nNSet</i> + <i>nSet_PID</i>		<i>nSet_a</i> and <i>nAct_a</i> are used as PID input values. The arriving <i>nNSet_a</i> setpoint is additively linked to the value output by the PID element.
	5	<i>nNSet</i> <i>nSet_PID</i>		<i>nSet_a</i> and <i>nAct_a</i> are used as PID input values. The setpoint <i>nNSet_a</i> is output at the output <i>nOut_a</i> . The PID output value is output at the output <i>nPIDOut_a</i> .
C00243	0.000	s	999.999	Influence acceleration time • Acceleration time <i>T_{ir}</i> for the influencing factor. • Lenze setting: 5.000 s
C00244	0.000	s	999.999	Influence deceleration time • Deceleration time <i>T_{if}</i> for the influencing factor. • Lenze setting: 5.000 s
C00245	-199.99	%	+199.99	Display of PID output value <i>nPIDOut_a</i>
C00246	-199.99	%	+199.99	Display of the internal PID input value <i>nAct_a</i>
C00247	0	%	100	Window for comparison function "Actual value = setpoint" • Lenze setting: 2 % • Hysteresis: 1 % (fixed)

19.1.138.1 Control characteristic

The PI algorithm is active in the Lenze setting.

Gain (P component)

The input value is controlled by a linear characteristic. The slope of the characteristic is determined by the controller gain V_p .

The controller gain V_p is set under [C00222](#).

- The controller gain can be adapted via the input $nAdapt_a$ (also possible in online mode).
- The input value $nAdapt_a$ has a direct effect on the controller gain:

$$P = nAdapt_a \cdot C00222$$

Example: With the parameterised controller gain $V_p = 2.0$ and $nAdapt_a = 75\%$, the resulting gain factor is as follows:

$$P = \frac{75 [\%]}{100 [\%]} \cdot 2.0 = 1.5$$

Integral action component (I component)

The I component can be selected via the input $nIset_a$. With a TRUE signal at $bIset$, the assigned value is accepted in the PID controller.

- Setting the adjustment time T_n to the maximum value of "6000 ms" deactivates the I component.
- The I component of the controller can also be deactivated by setting the input $bIOff$ to TRUE.
- The I component can be switched on and off online.

Reset time

The adjustment time T_n is set under [C00223](#).

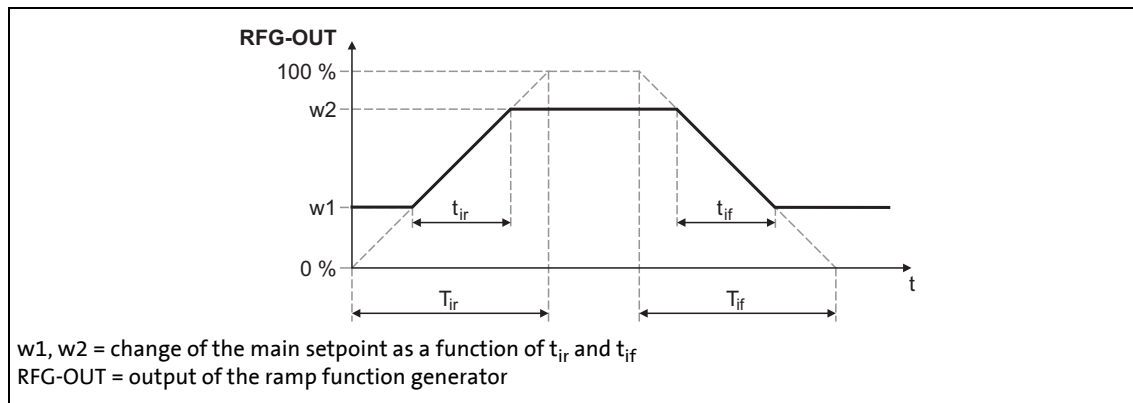
Differential component K_d (D component)

The differential component K_d is set under [C00224](#).

- The setting "0.0 s" deactivates the D component (Lenze setting). In this way, the PID controller becomes a PI controller or P controller, if the I component has been deactivated as well.

19.1.138.2 Ramp function generator

The PID output is led via a ramp function generator with linear characteristic. This serves to transfer setpoint step-changes at the PID output into a ramp which should be as steep as possible.



[19-60] Acceleration and deceleration times

- t_{ir} and t_{if} are the desired times for changing between $w1$ and $w2$.
- The ramps for acceleration and deceleration can be set individually.
 - [C00227](#): Acceleration time t_{ir}
 - [C00228](#): Deceleration time t_{if}
- The t_{ir}/t_{if} values are converted into the required T_i times according to the following formula:

$T_{ir} = t_{ir} \cdot \frac{100\%}{w2 - w1}$	$T_{if} = t_{if} \cdot \frac{100\%}{w2 - w1}$
---	---

- The ramp function generator is immediately set to "0" by setting *blnAct* to TRUE.

19.1.138.3 Operating range of the PID process controller

The value range of the input signal *nSet_a* and thus the operating range of the PID process controller can be limited with the following parameters:

- [C00231/1](#): Pos. maximum (default setting: 199.99 %)
- [C00231/2](#): Pos. minimum (default setting: 0.00 %)
- [C00231/3](#): Neg. minimum (default setting: 0.00 %)
- [C00231/4](#): Neg. maximum (default setting: 199.99 %)

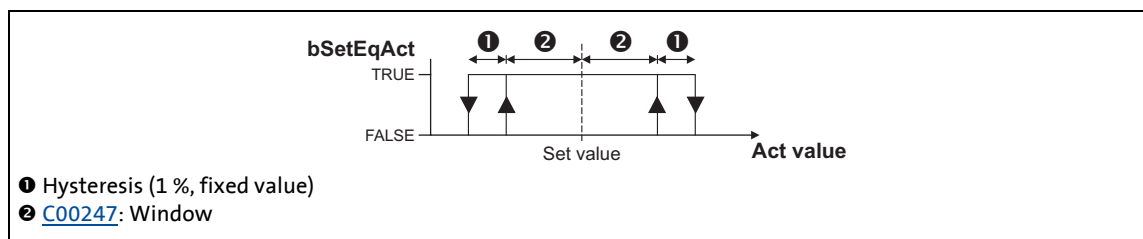
19.1.138.4 Evaluation of the output signal

After the limitation, the output signal is evaluated with the influencing factor *nInfluence_a*. The evaluation is activated/suppressed along a ramp when the *bEnableInfluenceRamp* input is set to TRUE. The ramp times are set with the parameters "Influence acceleration time" ([C00243](#)) and "Influence deceleration time" ([C00244](#)).

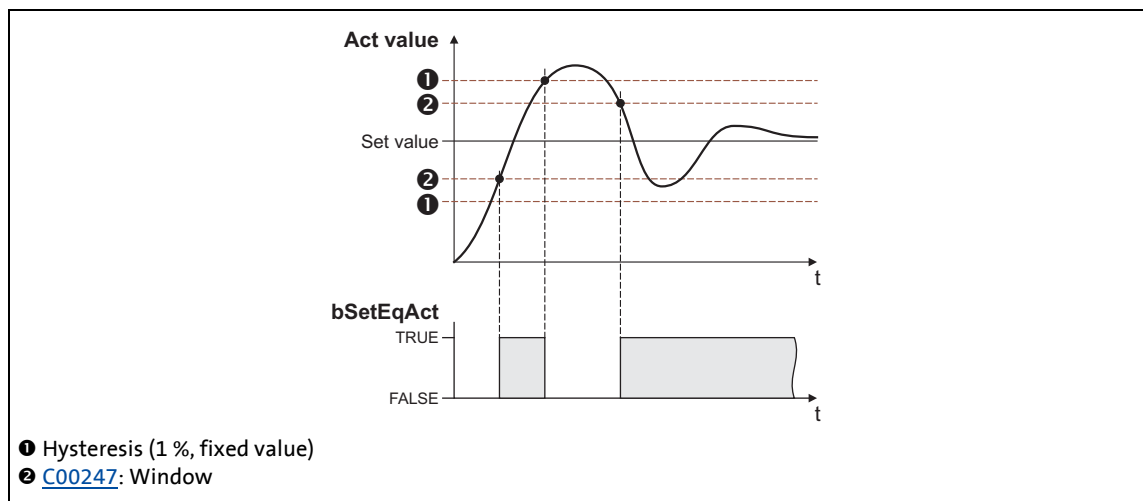
19.1.138.5 Comparison function "Actual value = setpoint"

If setpoint and actual value are identical and there is no system deviation, the *bSetEqAct* status output is set to TRUE.

- The hysteresis of the comparison function has a fixed value of 1 %.
- The symmetrical window around the setpoint for the comparison function can be set in [C00247](#) (Lenze setting: 2 %).



[19-61] Comparison function: Switching performance



[19-62] Comparison function: Example

19.1.138.6 Control functions

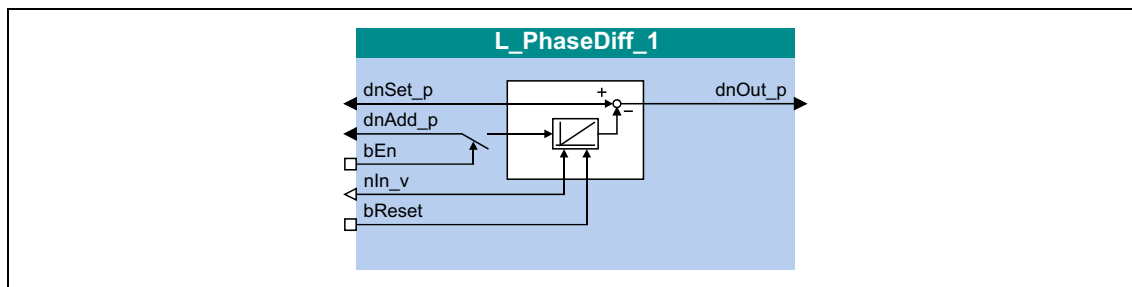
The process controller has various digital inputs for controlling the FB:

Identifier	Data type	Information/possible settings
bInAct	BOOL	Deactivate process controller temporarily (stop) <ul style="list-style-type: none"> • Changes can be done online. • Display parameter: C00833/76 Note: This input is not interconnected in the LA_NCtrl application block.
		TRUE <ul style="list-style-type: none"> • The current output value is frozen. • The internal control algorithm is stopped. • However, a setpoint selected via input <i>nNSet_a</i> is still provided in operating modes 0/1/4/5.
bIOff	BOOL	Switch off the I-component of the process controller <ul style="list-style-type: none"> • Changes can be done online. • Display parameter: C00833/77
		TRUE The I component of the process controller is set to zero.
bPIDOff	BOOL	Reset the entire PID controller
		TRUE <ul style="list-style-type: none"> • The I component of the controller is set to zero. • The controller output is set to zero. • The internal control algorithm is stopped.

19.1.139 L_PhaseDiff_1

This FB generates a position difference for the defined position setpoint from a position value and a speed signal.

- In an integrator, the *nIn_v* speed signal is integrated into a position value and subtracted from the *dnSet_p* position setpoint.
- In addition, the adaptive *dnAdd_p* position value can be added to the integrator content by setting *bEn* to TRUE.

**Inputs**

Identifier	Data type	Information/possible settings
dnSet_p	DINT	Selection of a position setpoint
dnAdd_p	DINT	Adaptive position value for the actual position
bEn	BOOL	Activate addition of the adaptive position value
		<div>FALSE</div> <ol style="list-style-type: none"> 1. The speed signal at <i>nIn_v</i> is integrated by the angle integrator. 2. The result of the angle integrator is subtracted from the angle signal at <i>dnSet_p</i> and output at <i>dnOut_p</i> afterwards.
		<div>TRUE</div> <p>The adaptive position value selected via <i>dnAdd_p</i> is added:</p> <ol style="list-style-type: none"> 1. The speed signal at <i>nIn_v</i> is integrated by the angle integrator. 2. The angle signal at <i>dnAdd_p</i> is added to the integrated speed signal in every task cycle. 3. The result of the angle integrator is subtracted from the angle signal at <i>dnSet_p</i> and output at <i>dnOut_p</i> afterwards.
nIn_v	INT	Selection of the actual speed to be converted into the position value
bReset	BOOL	Reset actual angle integrator
		<div>TRUE</div> <p>Actual angle integrator is set to "0".</p>

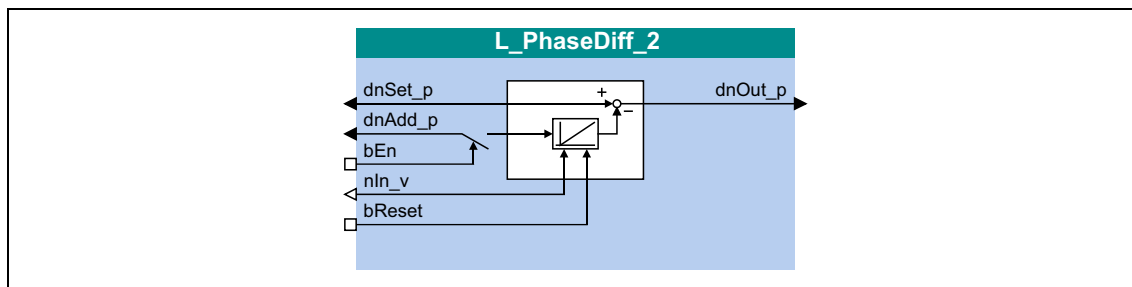
Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output angle signal (position difference) <ul style="list-style-type: none"> • Without limitation

19.1.140 L_PhaseDiff_2

This FB generates a position difference for the defined position setpoint from a position value and a speed signal.

- In an integrator, the *nIn_v* speed signal is integrated into a position value and subtracted from the *dnSet_p* position setpoint.
- In addition, the adaptive *dnAdd_p* position value can be added to the integrator content by setting *bEn* to TRUE.

**Inputs**

Identifier	Data type	Information/possible settings
dnSet_p	DINT	Selection of a position setpoint
dnAdd_p	DINT	Adaptive position value for the actual position
bEn	BOOL	Activate addition of the adaptive position value
		<div>FALSE</div> <ol style="list-style-type: none"> 1. The speed signal at <i>nIn_v</i> is integrated by the angle integrator. 2. The result of the angle integrator is subtracted from the angle signal at <i>dnSet_p</i> and output at <i>dnOut_p</i> afterwards.
		<div>TRUE</div> <p>The adaptive position value selected via <i>dnAdd_p</i> is added:</p> <ol style="list-style-type: none"> 1. The speed signal at <i>nIn_v</i> is integrated by the angle integrator. 2. The angle signal at <i>dnAdd_p</i> is added to the integrated speed signal in every task cycle. 3. The result of the angle integrator is subtracted from the angle signal at <i>dnSet_p</i> and output at <i>dnOut_p</i> afterwards.
nIn_v	INT	Selection of the actual speed to be converted into the position value
bReset	BOOL	Reset actual angle integrator
		<div>TRUE</div> <p>Actual angle integrator is set to "0".</p>

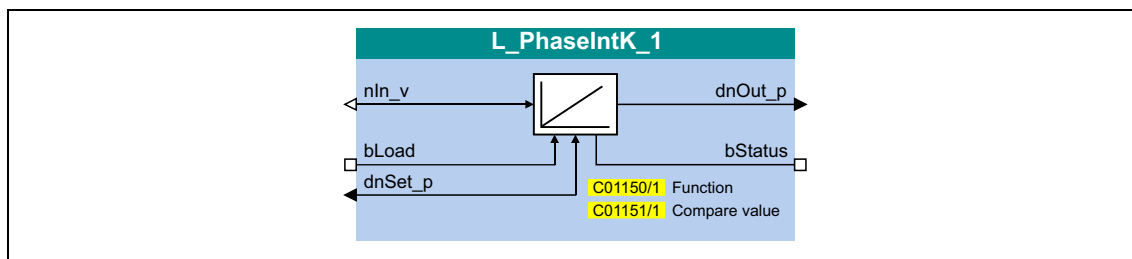
Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output angle signal (position difference) <ul style="list-style-type: none"> • Without limitation

19.1.141 L_PhaseIntK_1

The FB can integrate a speed or velocity to an angle (path). In addition, the FB can recognise a relatively covered distance.

- The integrator can take max. ± 32000 encoder revolutions.



Inputs

Identifier	Data type	Information/possible settings
nIn_v	INT	Selection of the actual speed • 16384 \equiv 15000 rpm
bLoad	BOOL	Load angle integrator with starting value and reset status signal TRUE Angle integrator is loaded with the value at <i>dnSet_p</i> and <i>bStatus</i> is reset to FALSE.
dnSet_p	DINT	Starting value for angle integrator

Outputs

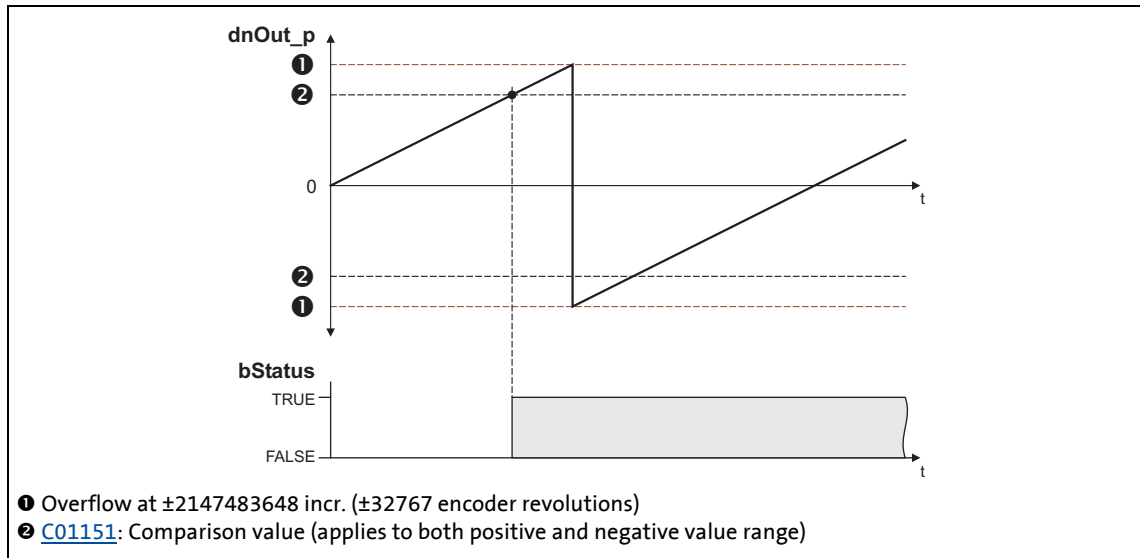
Identifier	Data type	Value/meaning
dnOut_p	DINT	Angle output signal • 65536 [incr.] \equiv 1 encoder revolution • Overflow is possible (display via <i>bStatus</i>)
bStatus	BOOL	Status signal "Overflow occurred/distance processed" • Status signal can be reset via <i>bLoad</i> . TRUE Overflow has occurred or distance is processed.

Parameter

Parameter	Possible settings	Info
C01150/1		Function
	0 Loading with level	Load integrator with TRUE level at the input <i>bLoad</i> (Lenze setting)
	1 Loading with edge	Load integrator with FALSE/TRUE edge at the input <i>bLoad</i> .
	2 Loading with level + reset	Load integrator when reaching the comparison value or with TRUE level at the input <i>bLoad</i> .
C01151/1	0	2000000000 Comparison value • Is valid for both the positive and the negative value range. • Lenze setting: 0

19.1.141.1 Function at constant input value

Selection: [C01150](#) = "0: Loading with level" or "1: Loading with edge"

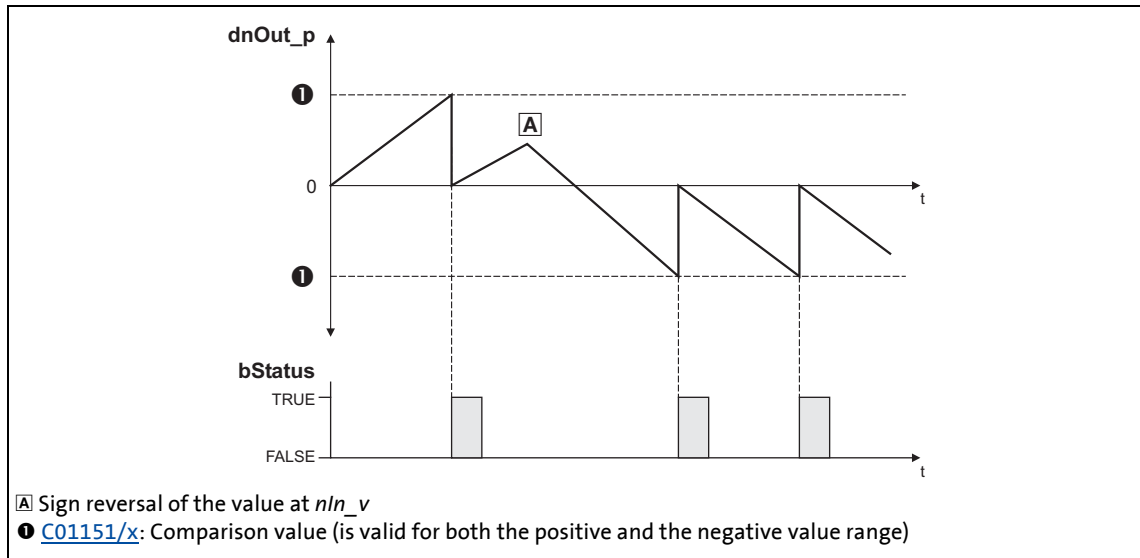


[19-63] Switching performance if the overflow is in the positive direction

- If "0: Loading with level" is selected in [C01150](#), the *bLoad* input is status-controlled: In case of a TRUE signal, the integrator is loaded with the value at *dnSet_p* and the *bStatus* output is set to FALSE.
- If "1: Loading with edge" is selected in [C01150](#), the *bLoad* input is edge-controlled: In case of a FALSE/TRUE edge, the integrator is loaded with the value at *dnSet_p* and then immediately continues to integrate, the *bStatus* output is set to FALSE.
- A positive signal at *nIn_v* is incremented (the counter content is increased with every function call).
- A negative signal at *nIn_v* is decremented (the counter content is reduced with every function call).
- *dnOut_p* outputs the counter content of the bipolar integrator.
 - If the counter content exceeds a value of +32767 encoder revolutions (corresponds to +2147483647 incr.), an overflow occurs and the counting process continues at a value of -32768 encoder revolutions.
 - If the counter content falls below a value of -32768 encoder revolutions (corresponds to -2147483648 incr.), an overflow occurs and the counting process starts at a value of +32767 encoder revolutions.
- *bStatus* will be set to TRUE if the comparison value set in [C01151/x](#) is reached.

19.1.141.2 Function at input value with sign reversal

Selection: [C01150](#) = "2: Loading with level + reset"



[19-64] Switching performance if the input signal changes signs

- If "2: Loading with level + reset" is selected in [C01150](#), the *bLoad* input is status-controlled: In case of a TRUE signal, the integrator is loaded with the value at *dnSet_p* and the *bStatus* output is set to FALSE.
- A positive signal at n/n_v is incremented (the counter content is increased with every function call).
- A negative signal at n/n_v is decremented (the counter content is reduced with every function call).
- *dnOut_p* outputs the counter content of the bipolar integrator.
 - If the positive counter content is higher than the comparison value set in [C01151/x](#), the comparison value will be subtracted from the counter content, and *bStatus* will be set to TRUE for one task cycle.
 - If the negative counter content is lower than the comparison value set in [C01151/x](#), the comparison value will be added to the counter content, and *bStatus* will be set to TRUE for one task cycle.

19.1.141.3 Calculation of the output signal

The output value at $dnOut_p$ can be detected according to the following formula:

$$dnOut_p [incr.] = nIn_v [rpm] \cdot t [s] \cdot 65535 [incr./rev.]$$

t = integration time
 $16384 \approx 15000$ rpm
 $1 \approx 1$ incr.

Example

You want to determine the counter content of the integrator at a certain speed at the input and a certain integration time t .

Given values:

- $nIn_v = 1000$ rpm \approx integer value 1092
- Integration time $t = 10$ s
- Starting value of the integrator = 0

Solution:

- Conversion of the input signal at nIn_v :

$$1000 \text{ rpm} = \frac{1000 \text{ rev.}}{60 \text{ s}}$$

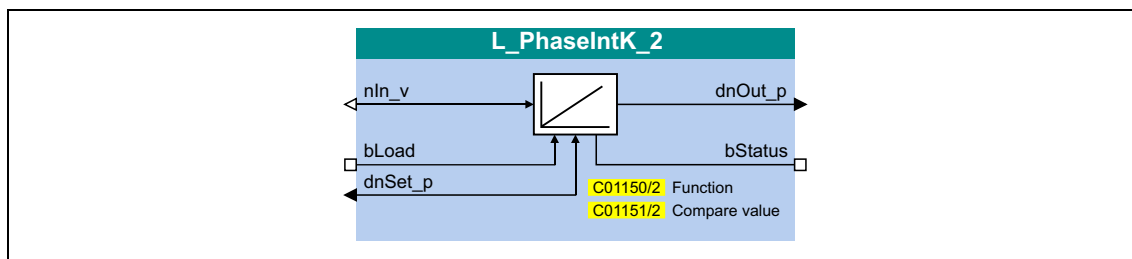
- Calculation of the output value:

$$dnOut_p = \frac{1000 \text{ rev.}}{60 \text{ s}} \cdot 10 \text{ s} \cdot \frac{65535 \text{ incr.}}{\text{Rev.}} = 10922666 \text{ incr.}$$

19.1.142 L_PhaseIntK_2

The FB can integrate a speed or velocity to an angle (path). In addition, the FB can recognise a relatively covered distance.

- The integrator can take max. ± 32000 encoder revolutions.



Inputs

Identifier	Data type	Information/possible settings
nIn_v	INT	Selection of the actual speed • 16384 \equiv 15000 rpm
bLoad	BOOL	Load angle integrator with starting value and reset status signal TRUE Angle integrator is loaded with the value at <i>dnSet_p</i> and <i>bStatus</i> is reset to FALSE.
dnSet_p	DINT	Starting value for angle integrator

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Angle output signal • 65536 [incr.] \equiv 1 encoder revolution • Overflow is possible (display via <i>bStatus</i>)
bStatus	BOOL	Status signal "Overflow occurred/distance processed" • Status signal can be reset via <i>bLoad</i> . TRUE Overflow has occurred or distance is processed.

Parameter

Parameter	Possible settings	Info
C01150/2		Function
	0 Loading with level	Load integrator with TRUE level at the input <i>bLoad</i> (Lenze setting)
	1 Loading with edge	Load integrator with FALSE/TRUE edge at the input <i>bLoad</i> .
	2 Loading with level + reset	Load integrator when reaching the comparison value or with TRUE level at the input <i>bLoad</i> .
C01151/2	0	2000000000 Comparison value • Is valid for both the positive and the negative value range. • Lenze setting: 0

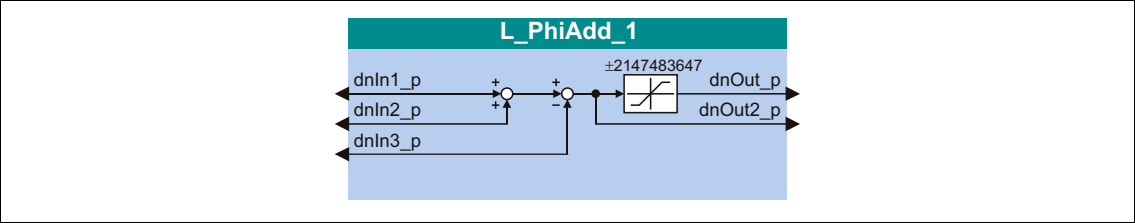


For a detailed functional description see [L PhaseIntK 1.](#)

19.1.143 L_PhiAdd_1

This FB adds or subtracts angle signals depending on the input used.

- The value provided at the *dnOut_p* output is internally limited to ± 2147483647 ($\pm 2^{31} - 1$).
- The value provided at the *dnOut2_p* output is not limited internally, this enables an internal overflow.



Inputs

Identifier	Data type	Information/possible settings
dnIn1_p	DINT	Input signal 1
dnIn2_p	DINT	Input signal 2 (addition)
dnIn3_p	DINT	Input signal 3 (subtraction)

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal <ul style="list-style-type: none">• Internal limitation to ± 2147483647
dnOut2_p	DINT	Output signal 2 <ul style="list-style-type: none">• Without limitation/with overflow (which makes a wrong output possible)

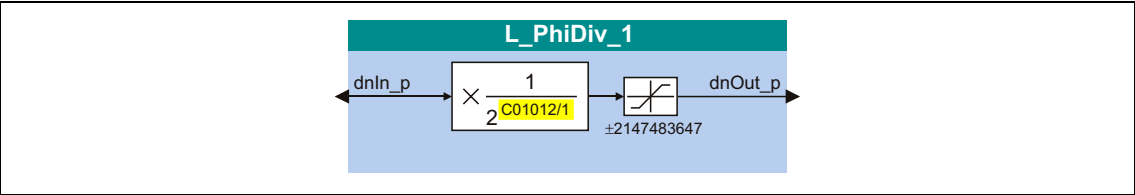
Function

$$dnOut_p = dnIn1_p + dnIn2_p - dnIn3_p$$

19.1.144 L_PhiDiv_1

This FB divides or multiplies angle signals in power of two format.

- A positive division factor ([C01012/1](#)) causes a division.
- A negative division factor ([C01012/1](#)) causes a multiplication.
- The value provided at the *dnOut_p* output is internally limited to $\pm 2^{31} - 1$.
- Division is not remainder considered.



Inputs

Identifier	Data type	Information/possible settings
dnIn_p	DINT	Input signal

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal • Internal limitation to $\pm 2^{31} - 1$

Parameter

Parameter	Possible settings	Info
C01012/1	-31	31 Division factor • Lenze setting: 0

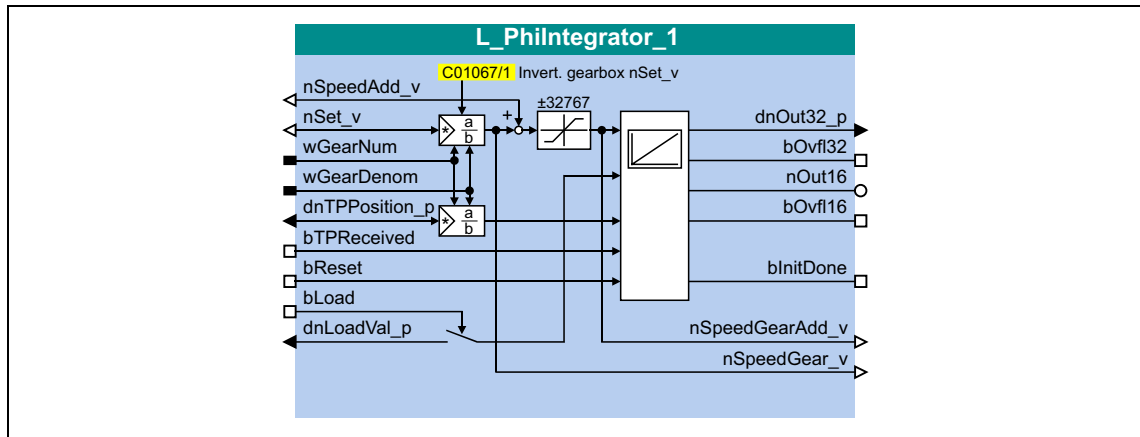
Function

$$dnOut_p = dnIn_p \cdot \frac{1}{2^{C01012/1}}$$

19.1.145 L_PhilIntegrator_1

This FB evaluates a speed with a gearbox factor and adds them in an integrator.

- The integrator value is output as 16-bit value and 32-bit value.
- An overflow of the prevailing output is signalled.
- The integrator can be loaded and initialised (e.g. with a touch probe signal).



Inputs

Identifier	Data type	Information/possible settings	
nSpeedAdd_v	INT	Additive speed	
nSet_v	INT	Speed input (angular difference)	
wGearNum	WORD	Gearbox factor (numerator)	
wGearDenom	WORD	Gearbox factor (denominator) • When <i>wGearDenom</i> = 0, it is internally calculated with 1.	
dnTPPosition_p	DINT	Initialisation value	
bTPReceived	BOOL	Initialise integrator	
		FALSE → TRUE	Initialise integrator
bReset	BOOL	Reset integrator	
		TRUE	Reset integrator • The integrator is not integrated.
bLoad	BOOL	Load integrator	
		TRUE	Load integrator with <i>dnLoadVal_p</i> • The integrator is not integrated. • The <i>bInitDone</i> output is reset to FALSE with a delay of one call cycle after <i>bLoad</i> is reset to FALSE and a subsequent FALSE/TRUE edge to <i>bTPReceived</i> .
dnLoadVal_p	DINT	Value the integrator is to be loaded with.	

Outputs

Identifier	Data type	Value/meaning
dnOut32_p	DINT	Integrator value (32 bits)
bOvfl32	BOOL	Status signal "overflow (32 bits)"
		TRUE Overflow
nOut16	INT	Integrator value (16 bits)
bOvfl16	BOOL	Status signal "overflow (16 bits)"
		TRUE Overflow
blnitDone	BOOL	Status signal "Initialisation completed"
		TRUE Integrator is initialised
nSpeedGearAdd_v	INT	Resulting speed with additive speed ($nSet_v \cdot \text{gearbox factor} + nSpeedAdd_v$)
nSpeedGear_v	INT	Resulting speed without additive speed ($nSet_v \cdot \text{gearbox factor}$)

Parameter

Parameter	Possible settings	Info
C01067/1		Invert. gearbox nSet_v
	0 not inverted	
	1 inverted	
	2 Automatically from MCK	

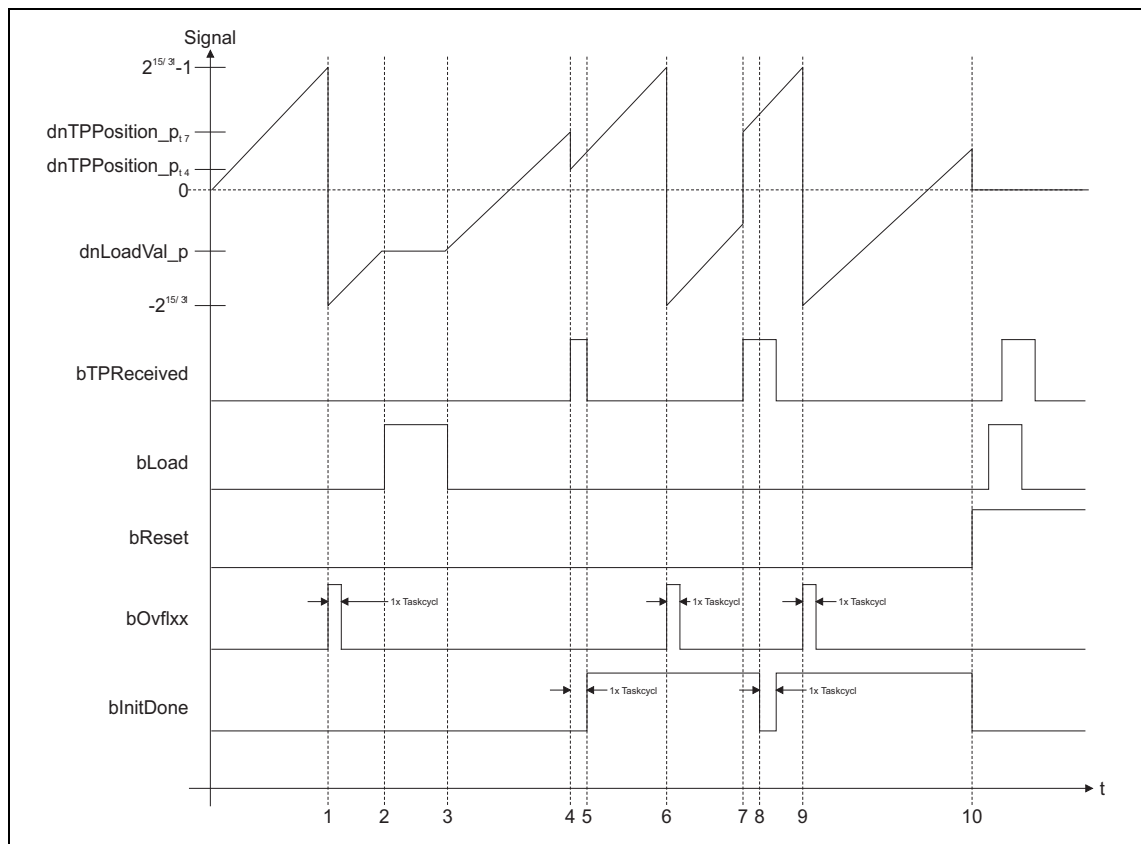
19.1.145.1 Function

The $nSet_v$ input value is evaluated, integrated and output as 16-bit value ($nOut16$) and 32-bit value $dnOut32_p$ with the gearbox factors $wGearNum$ and $wGearDenom$.

$$nOut16 = nOut16 + nSet_v \cdot \frac{wGearNum}{wGearDenom}$$

$$dnOut32_p = dnOut32_p + nSet_v \cdot \frac{wGearNum}{wGearDenom}$$

- Evaluation of the gearbox factor is remainder considered.
- A positive or negative overflow of the integrator is signalled by a TRUE signal (for a task cycle) at the $bOvfl16$ output for the $nOut16$ output or at the $bOvfl32$ output for the $dnOut32_p$ output.



[19-65] Signal characteristic

19.1.145.2 Example

The current speed at *nSet_v* and the gearbox factors serve to create a specific machine measuring system from the motor measuring system.

- 216 increments in the motor measuring system are to correspond to 1 motor revolution.
- 216 increments in the machine measuring system (*nOut16*) are to correspond to 1 machine shaft revolution.

Initialise integrator

A FALSE/TRUE edge at *bTPReceived* initialises the integrator, i.e. a calculation with *dnTPPosition_p* and *dnLoadVal_p* is made:

$$\begin{aligned} nOut16 &= (INT)(dnLoadVal_p + dnTPPosition_p \cdot \text{Gearbox factor}) \\ dnOut32_p &= dnLoadVal_p + dnTPPosition_p \cdot \text{Gearbox factor} \end{aligned}$$

- After initialisation is completed, the *blnitDone* output is set to TRUE in the next call cycle.
- In case of a renewed initialisation without a previous reset (*bReset* = TRUE), the *blnitDone* output is set to FALSE for a task cycle.

Reset integrator

When *bReset* is set to TRUE, the integrator is set to 0. No calculations are made.

- The Boolean outputs are set to FALSE.
- The *bReset* input has the highest priority.

Load integrator

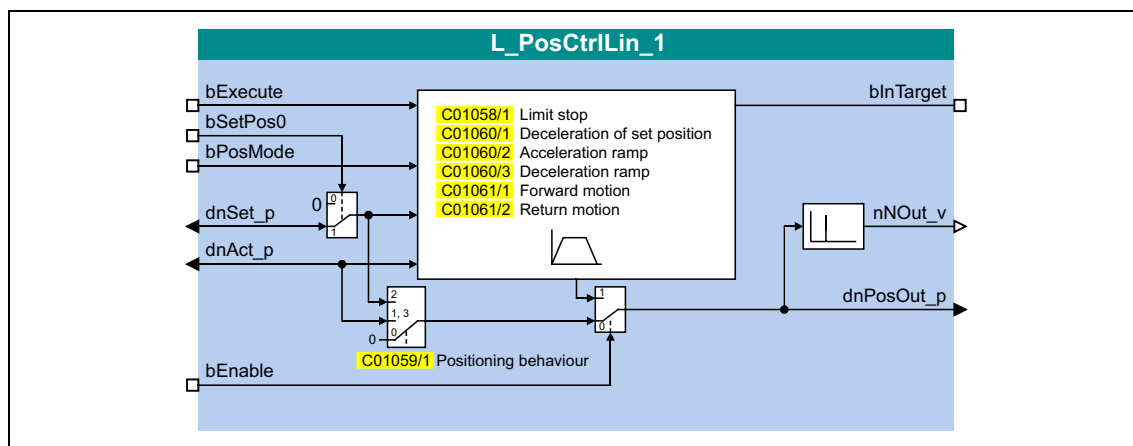
When *bLoad* is set to TRUE, the integrator is loaded with the value at *dnLoadVal_p* and the outputs are set.

- When *bLoad* is set to TRUE, the input is not integrated and no check for overflow is executed.
- When *bLoad* is reset to FALSE, the integrator continues from the loaded value. The *blnitDone* output is reset to FALSE after a FALSE/TRUE edge at *bTPReceived* with a delay of one call cycle.

19.1.146 L_PosCtrlLin_1

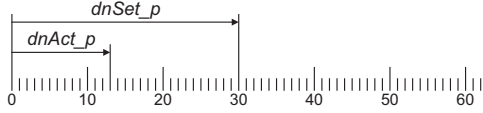
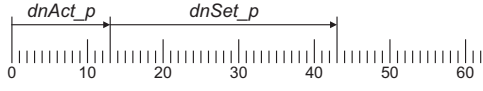
This FB serves to implement the following positioning functions:

- Bring drive to curve position (e.g. after mains connection, manual jog, homing)
- Release drive from curve and bring it to safe position (position override function)
- Positioning the X axis via X offset (higher-level positioning)
- Positioning the Y axis via Y offset (higher-level positioning)



Inputs

Identifier	Data type	Information/possible settings
bExecute	BOOL	Execute positioning profile <ul style="list-style-type: none"> • Only possible if the <i>bEnable</i> input is set to TRUE.
		FALSE No positioning/positioning is aborted. <ul style="list-style-type: none"> • The speed at the <i>nNOOut_v</i> output is braked to standstill via the deceleration ramp set in C01060/1 (<i>nNOOut_v</i> = 0). • At the same time, the <i>dnPosOut_p</i> output is stopped.
		FALSE → TRUE Positioning is executed/continued. <ul style="list-style-type: none"> • In case of an activated limit stop (C01058/1 = TRUE), a renewed positive edge for a following positioning procedure is required.
bSetPos0	BOOL	Travel to zero position <ul style="list-style-type: none"> • Only possible if the <i>bEnable</i> input is set to TRUE.
		FALSE The value at the <i>dnSet_p</i> input is used as setpoint position.
		TRUE The value at the <i>dnSet_p</i> input is ignored. The setpoint position is internally set to "0" and the <i>dnPosOut_p</i> output can be travelled to zero position.

Identifier	Data type	Information/possible settings
bPosMode	BOOL	Positioning mode
		<p>FALSE Absolute positioning</p> <ul style="list-style-type: none"> The setpoint at <i>dnSet_p</i> is the absolute setpoint position (with regard to zero position):  <p>TRUE Relative positioning</p> <ul style="list-style-type: none"> With a FALSE/TRUE edge at the <i>bExecute</i> input, the outputs of the current position (<i>dnAct_p</i>) are traversed by the <i>dnSet_p</i> value:  <p>Note: Only to be used with activated limit stop (C01058/1 = TRUE)!</p>
dnSet_p	DINT	Setpoint for positioning in [increments] <ul style="list-style-type: none"> Scaling: A revolution is displayed with 65536 increments or steps.
dnAct_p	DINT	Actual position in [increments] <ul style="list-style-type: none"> Connect this input with e.g. <i>dnPosOut_p</i> of this FB or with another FB which outputs the actual position of the drive.
bEnable	BOOL	Activate/deactivate positioning function <ul style="list-style-type: none"> This input has the highest priority.
		<p>FALSE Positioning function deactivated.</p> <ul style="list-style-type: none"> For behaviour see C01059/1. <p>TRUE Positioning function activated.</p>

Outputs

Identifier	Data type	Value/meaning
bInTarget	BOOL	Status signal "Target position reached"
		TRUE Target position reached.
nNOOut_v	INT	Speed output of the profile generator <ul style="list-style-type: none"> Scaling: 16384 \equiv 15000 rpm
dnPosOut_p	DINT	Output position of the profile generator in [increments] <ul style="list-style-type: none"> Scaling: A revolution is displayed with 65536 increments or steps.

Parameter

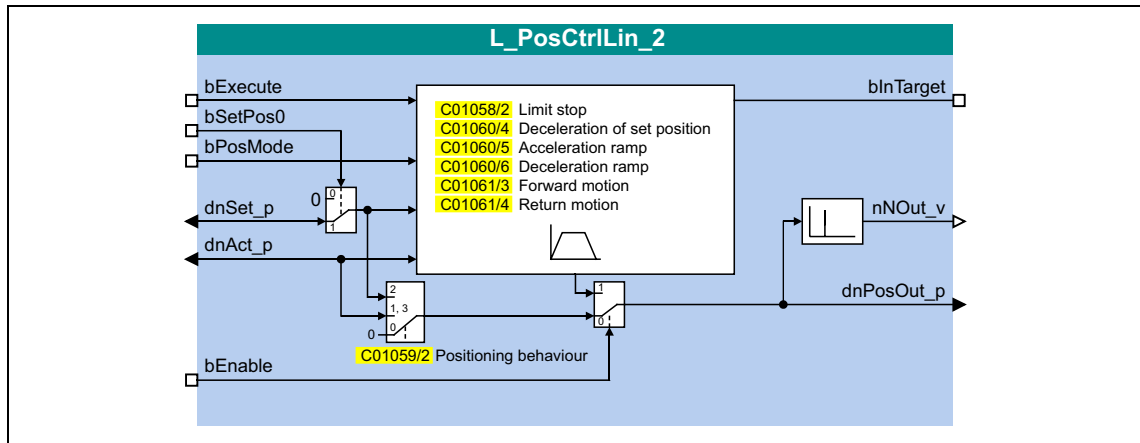
Parameter	Possible settings	Info
C01058/1		Limit stop
	0 deactivated (Lenze setting)	The outputs continuously follow the setpoint at <i>dnSet_p</i> .
	1 activated	<p>The outputs follow the setpoint at <i>dnSet_p</i> once.</p> <ul style="list-style-type: none"> If the setpoint position changes, a new FALSE/TRUE edge is required at the <i>bExecute</i> input for another positioning process.

Parameter	Possible settings			Info
C01059/1				Positioning behaviour • Behaviour with deactivated positioning function (<i>bEnable</i> = FALSE).
	0	<i>dnOut_p</i> = 0 (Lenze setting)		The <i>dnPosOut_p</i> output jumps to "0". • The speed signal at the <i>nNOut_v</i> output maps this position step change as angle signal. Note: If the <i>nNOut_v</i> output has an impact on the setpoint generation for the drive, undefined motions (shocks, following errors) may occur.
	1	<i>dnOut_p/nNOut_v</i> follow <i>dnAct_p</i>		The outputs <i>dnPosOut_p</i> and <i>nNOut_v</i> follow the value at the <i>dnAct_p</i> input (actual position).
	2	<i>dnOut_p/nNOut_v</i> follow <i>dnSet_p</i>		The outputs <i>dnPosOut_p</i> and <i>nNOut_v</i> follow the value at the <i>dnSet_p</i> input (setpoint).
	3	<i>dnOut_p/nNOut_v</i> follow <i>dnAct_p</i> (without limitation)		The outputs <i>dnPosOut_p</i> and <i>nNOut_v</i> follow the value at the <i>dnAct_p</i> input (actual position), but without limitation.
C01060/1	0.010	s	130.000	Deceleration of set position • Deceleration ramp for stop before reaching the setpoint position (<i>bExecute</i> = FALSE). • Lenze setting: 1.000 s
C01060/2	0.010	s	130.000	Acceleration ramp • Lenze setting: 1.000 s
C01060/3	0.010	s	130.000	Deceleration ramp • Lenze setting: 1.000 s
C01061/1	-15000	rpm	15000	Forward motion • Positive speed • Lenze setting: 200 rpm
C01061/2	-15000	rpm	15000	Return motion • Negative speed • Lenze setting: 200 rpm

19.1.147 L_PosCtrlLin_2

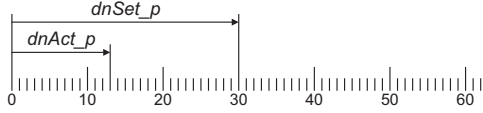
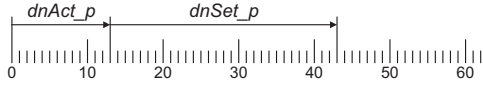
This FB serves to implement the following positioning functions:

- Bring drive to curve position (e.g. after mains connection, manual jog, homing)
- Release drive from curve and bring it to safe position (position override function)
- Positioning the X axis via X offset (higher-level positioning)
- Positioning the Y axis via Y offset (higher-level positioning)



Inputs

Identifier	Data type	Information/possible settings
bExecute	BOOL	Execute positioning profile <ul style="list-style-type: none"> • Only possible if the <i>bEnable</i> input is set to TRUE.
		FALSE No positioning/positioning is aborted. <ul style="list-style-type: none"> • The speed at the <i>nNOOut_v</i> output is braked to standstill via the deceleration ramp set in C01060/4 (<i>nNOOut_v</i> = 0). • At the same time, the <i>dnPosOut_p</i> output is stopped.
		FALSE → TRUE Positioning is executed/continued. <ul style="list-style-type: none"> • In case of an activated limit stop (C01058/2 = TRUE), a renewed positive edge for a following positioning procedure is required.
bSetPos0	BOOL	Travel to zero position <ul style="list-style-type: none"> • Only possible if the <i>bEnable</i> input is set to TRUE.
		FALSE The value at the <i>dnSet_p</i> input is used as setpoint position.
		TRUE The value at the <i>dnSet_p</i> input is ignored. The setpoint position is internally set to "0" and the <i>dnPosOut_p</i> output can be travelled to zero position.

Identifier	Data type	Information/possible settings
bPosMode	BOOL	Positioning mode
		<p>FALSE Absolute positioning</p> <ul style="list-style-type: none"> The setpoint at <i>dnSet_p</i> is the absolute setpoint position (with regard to zero position):  <p>TRUE Relative positioning</p> <ul style="list-style-type: none"> With a FALSE/TRUE edge at the <i>bExecute</i> input, the outputs of the current position (<i>dnAct_p</i>) are traversed by the <i>dnSet_p</i> value:  <p>Note: Only to be used with activated limit stop (C01058/2 = TRUE)!</p>
dnSet_p	DINT	Setpoint for positioning in [increments] <ul style="list-style-type: none"> Scaling: A revolution is displayed with 65536 increments or steps.
dnAct_p	DINT	Actual position in [increments] <ul style="list-style-type: none"> Connect this input with e.g. <i>dnPosOut_p</i> of this FB or with another FB which outputs the actual position of the drive.
bEnable	BOOL	Activate/deactivate positioning function <ul style="list-style-type: none"> This input has the highest priority.
		<p>FALSE Positioning function deactivated.</p> <ul style="list-style-type: none"> For behaviour see C01059/2. <p>TRUE Positioning function activated.</p>

Outputs

Identifier	Data type	Value/meaning
blnTarget	BOOL	Status signal "Target position reached"
		TRUE Target position reached.
nNOut_v	INT	Speed output of the profile generator <ul style="list-style-type: none"> Scaling: 16384 \equiv 15000 rpm
dnPosOut_p	DINT	Output position of the profile generator in [increments] <ul style="list-style-type: none"> Scaling: A revolution is displayed with 65536 increments or steps.

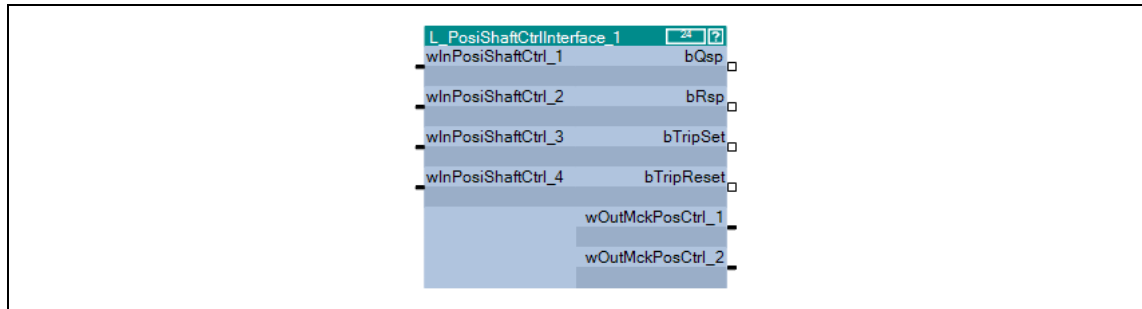
Parameter

Parameter	Possible settings	Info
C01058/2		Limit stop
	0 deactivated (Lenze setting)	The outputs continuously follow the setpoint at <i>dnSet_p</i> .
	1 activated	<p>The outputs follow the setpoint at <i>dnSet_p</i> once.</p> <ul style="list-style-type: none"> If the setpoint position changes, a new FALSE/TRUE edge is required at the <i>bExecute</i> input for another positioning process.

Parameter	Possible settings			Info
C01059/2				Positioning behaviour • Behaviour with deactivated positioning function (<i>bEnable</i> = FALSE).
	0	<i>dnOut_p</i> = 0 (Lenze setting)		The <i>dnPosOut_p</i> output jumps to "0". • The speed signal at the <i>nNOut_v</i> output maps this position step change as angle signal. Note: If the <i>nNOut_v</i> output has an impact on the setpoint generation for the drive, undefined motions (shocks, following errors) may occur.
	1	<i>dnOut_p/nNOut_v</i> follow <i>dnAct_p</i>		The outputs <i>dnPosOut_p</i> and <i>nNOut_v</i> follow the value at the <i>dnAct_p</i> input (actual position).
	2	<i>dnOut_p/nNOut_v</i> follow <i>dnSet_p</i>		The outputs <i>dnPosOut_p</i> and <i>nNOut_v</i> follow the value at the <i>dnSet_p</i> input (setpoint).
	3	<i>dnOut_p/nNOut_v</i> follow <i>dnAct_p</i> (without limitation)		The outputs <i>dnPosOut_p</i> and <i>nNOut_v</i> follow the value at the <i>dnAct_p</i> input (actual position), but without limitation.
C01060/4	0.010	s	130.000	Deceleration of set position • Deceleration ramp for stop before reaching the setpoint position (<i>bExecute</i> = FALSE). • Lenze setting: 1.000 s
C01060/5	0.010	s	130.000	Acceleration ramp • Lenze setting: 1.000 s
C01060/6	0.010	s	130.000	Deceleration ramp • Lenze setting: 1.000 s
C01061/3	-15000	rpm	15000	Forward motion • Positive speed • Lenze setting: 200 rpm
C01061/4	-15000	rpm	15000	Return motion • Negative speed • Lenze setting: 200 rpm

19.1.148 L_PosiShaftCtrlInterface_1

FB in preparation!

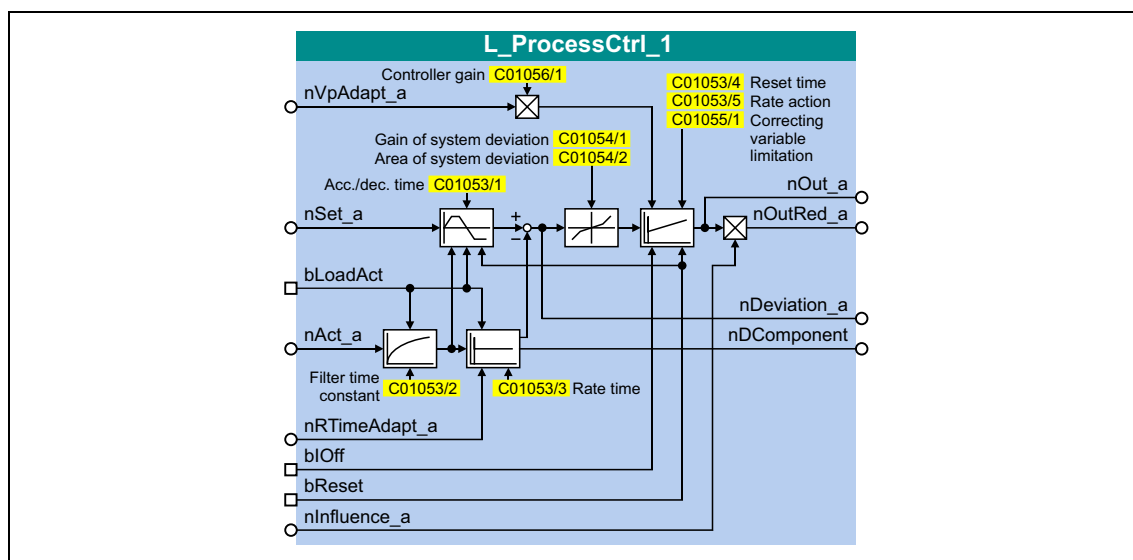


19.1.149 L_ProcessCtrl_1

This FB serves to implement a dancer position or tension control.

The FB is provided with the following functions:

- Adjustable control algorithm (P, PI, PID) with adaptable gain
- Reduced controller dynamics at low system deviation
- Setpoint ramp generator for preventing setpoint step-changes at the input
- Setpoint ramp generator can be loaded with actual value
- Low-pass filter and rate action in the actual value feedback
- Integral action component can be switched off
- Interruptible control



Inputs

Identifier	Data type	Information/possible settings	
nVpAdapt_a	INT	Proportional evaluation of the controller gain (Vp) <ul style="list-style-type: none">• Scaling: 16384 ≡ 100 %• Internal limitation to 0 ... 16384 (0 ... 100 %)	
nSet_a	INT	Controller setpoint	
bLoadAct	BOOL	Accept actual controller value	
		TRUE	The actual controller value <i>nAct_a</i> is taken over into the ramp generator, the low pass and the rate action.
nAct_a	INT	Actual controller value	
nRTimeAdapt_a	INT	Proportional evaluation of the rate time in the actual value path <ul style="list-style-type: none">• Scaling: 16384 ≡ 100 % rate time (C01053)• Internal limitation to 0 ... 16384 (0 ... 100 %)	
bIOff	BOOL	Reset controller I component	
		TRUE	The controller I component is reset.

Identifier	Data type	Information/possible settings
bReset	BOOL	Reset entire control
		TRUE All outputs are reset to 0.
nInfluence_a	INT	Proportional evaluation of the controller correcting variable <i>nOutRed_a</i> <ul style="list-style-type: none"> Scaling: 16384 \equiv 100 % controller correcting variable (<i>nOut_a</i>)

Outputs

Identifier	Data type	Value/meaning
nOut_a	INT	Controller correcting variable <ul style="list-style-type: none"> Internal limitation to ± 16384 (± 100 %)
nOutRed_a	INT	Controller correcting variable (evaluated by <i>nInfluence_a</i>)
nDeviation_a	INT	System deviation <ul style="list-style-type: none"> Internal limitation to ± 32767 (± 199.99 %)
nDComponent	INT	D component of the rate action <ul style="list-style-type: none"> Internal limitation to ± 16384 (± 100 %)

Parameter

Parameter	Possible settings			Info
C01053/1	0.000	s	30.000	Acceleration/deceleration time of the setpoint ramp generator • Lenze setting: 0.000 s
C01053/2	0.000	s	30.000	Filter time constant for actual controller value • Lenze setting: 0.000 s
C01053/3	0.000	s	30.000	Rate time for actual controller value • Lenze setting: 0.000 s
C01053/4	0.000	s	30.000	Controller reset time • Lenze setting: 1.000 s
C01053/5	0.000	s	30.000	Controller rate action • Lenze setting: 0.000 s
C01054/1	0.00	%	199.99	Gain of the system deviation in the range of reduced sensitivity • Lenze setting: 100.00 %
C01054/2	0.00	%	199.99	Area of system deviation with reduced gain/sensitivity • Lenze setting: 0.00 %
C01055/1				Limitation of the controller correcting variable to the positive area
	False	Limitation not active. (Lenze setting)		
	True	Limitation active.		
C01056/1	0.00		100.00	Controller gain • Lenze setting: 0.10

19.1.149.1 Control characteristic

The dancer position or tension controller can be optionally operated as P, PI or PID controller. In the Lenze setting, the PI algorithm is active.

Gain (P component)

The input value is controlled by a linear characteristic. The slope of the characteristic is determined by the controller gain V_p .

The controller gain V_p is set in [C01056/1](#).

- The controller gain can be adapted via the $nVpAdapt_a$ input (also possible in online mode).
- The $nVpAdapt_a$ input value has a direct effect on the controller gain:

$$P = nVpAdapt_a \cdot C01056/1$$

Example: With the parameterised controller gain $V_p = 2.0$ and $nVpAdapt_a = 75\%$, the resulting gain factor is as follows:

$$P = \frac{75 [\%]}{100 [\%]} \cdot 2.0 = 1.5$$

Reset time T_n (I component)

The adjustment time T_n is set under [C01053/4](#).

- The I component of the controller can be deactivated by setting the input $bIOff$ to TRUE.
- The I component can be switched on and off online.

Differential component K_d (D component)

The differential component K_d is set under [C01053/5](#).

- The setting "0.0 s" deactivates the D component (Lenze setting). In this way, the PID controller becomes a PI controller or P controller, if the I component has been deactivated as well.

Evaluation of the output signal (controller influence)

If the motor speed or motor torque is precontrolled, a low influence is sufficient for the controller to comply with the setpoint.

Use the $nInfluence_a$ input to select the influencing factor the controller correcting variable ($nOut_a$) is to be evaluated with. The evaluated controller correcting variable is output at $nOutRed_a$.

**Note!**

The controller influence evaluates the output signal multiplicatively. A change of the $nInfluence_a$ influencing factor also changes the dynamics of the controller!

Switching on/off the controller

By setting the $bReset$ input to TRUE, the process controller can be switched off.

Loading the setpoint ramp generator with the actual value

If the actual value is loaded into the setpoint ramp generator in switched-off state, it has the advantage that in the moment of the renewed controller enable, the system deviation is zero first. Thus, compensation processes can be mostly prevented.

When the *bLoadAct* input is set to TRUE, the setpoint ramp generator can be loaded with the actual value. This keeps the system deviation equal to zero and I component of the controller.

Low pass and rate action in the actual value path

In order to filter signal interferences more effectively, you can activate a low pass in the actual value path.

- The filter time constant for the low pass is set in [C01053/2](#).
- The rate time constant in the feedback path can be set in [C01053/3](#). This serves to compensate interfering decelerations.

Reduced controller dynamics at low system deviation

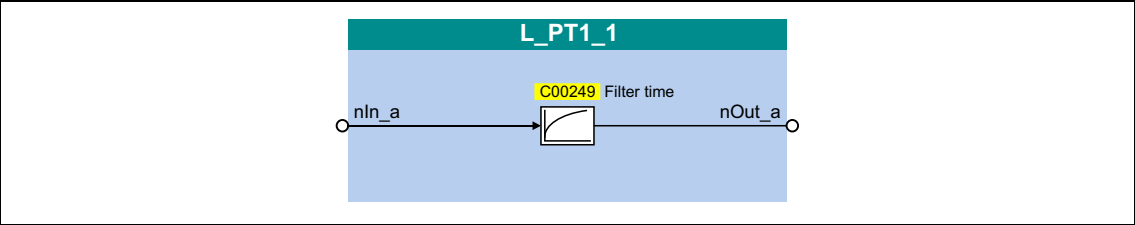
Due to a reduced controller dynamics with low system deviations, the dampening behaviour of the control loop is mostly influenced favourably.

- [C01054/2](#) serves to determine the tolerance zone in which the system deviation is transmitted to the controller with a slight gain.
- [C01054/1](#) serves to determine the amount of percent the gain in the defined tolerance zone is to be reduced to.

19.1.150 L_PT1_1

This FB filters and delays analog signals.

- The filter time constant T can be set under [C00249](#).
- The gain is defined with $V_p = 1$.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal

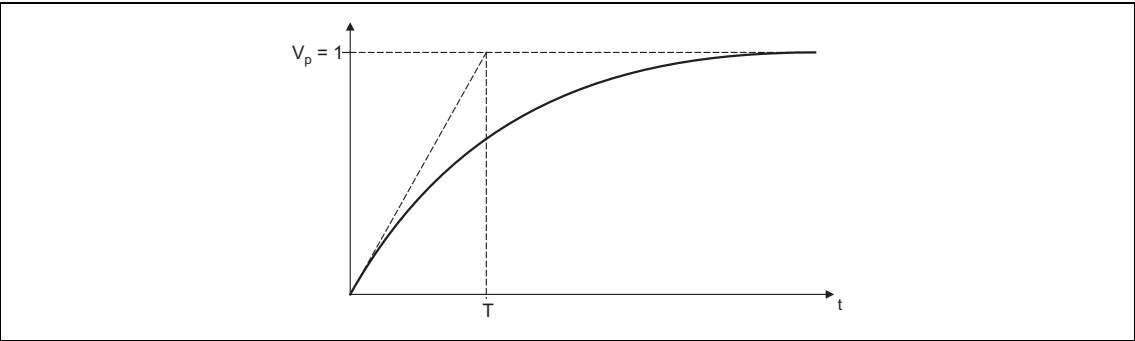
Outputs

Identifier	Data type	Value/meaning
nOut	INT	Output signal

Parameter

Parameter	Possible settings			Info
C00249	0	ms	5000	Filter time constant <ul style="list-style-type: none">• The filter is not active with a setting of "0 ms". The input signal is passed through one-to-one to the output.• Lenze setting: 2000 ms

Function

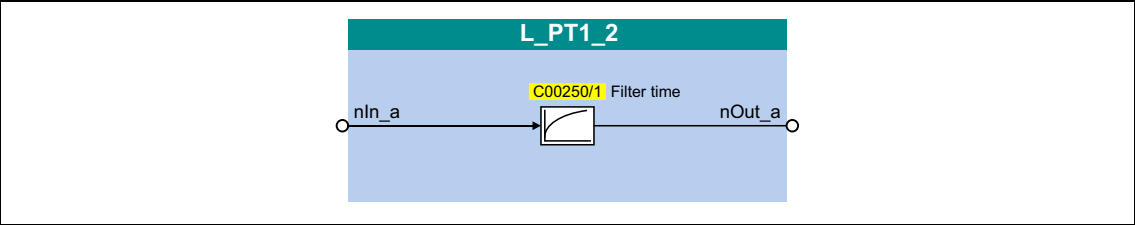


[19-66] Filter time constant T of the first-order delay element

19.1.151 L_PT1_2

This FB filters and delays analog signals.

- Filter time constant T can be set in [C00250/1](#).
- The gain is defined with $V_p = 1$.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal

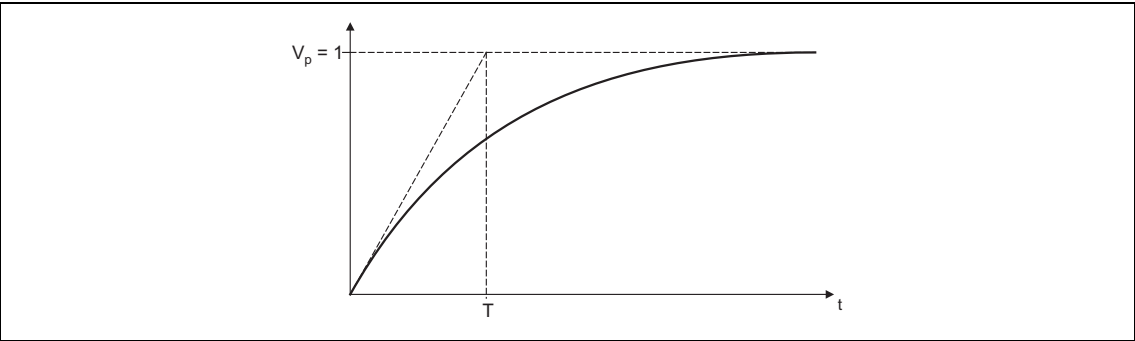
Outputs

Identifier	Data type	Value/meaning
nOut	INT	Output signal

Parameter

Parameter	Possible settings			Info
C00250/1	0	ms	5000	Filter time constant <ul style="list-style-type: none">• The filter is not active with a setting of "0 ms". The input signal is passed through one-to-one to the output.• Lenze setting: 2000 ms

Function

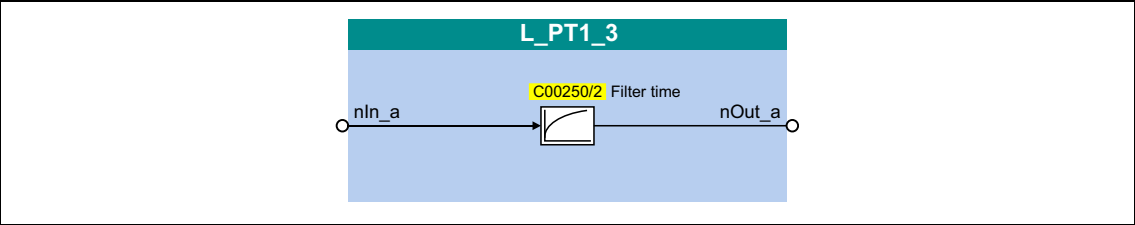


[19-67] Filter time constant T of the first-order delay element

19.1.152 L_PT1_3

This FB filters and delays analog signals.

- Filter time constant T can be set in [C00250/2](#).
- The gain is defined with $V_p = 1$.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal

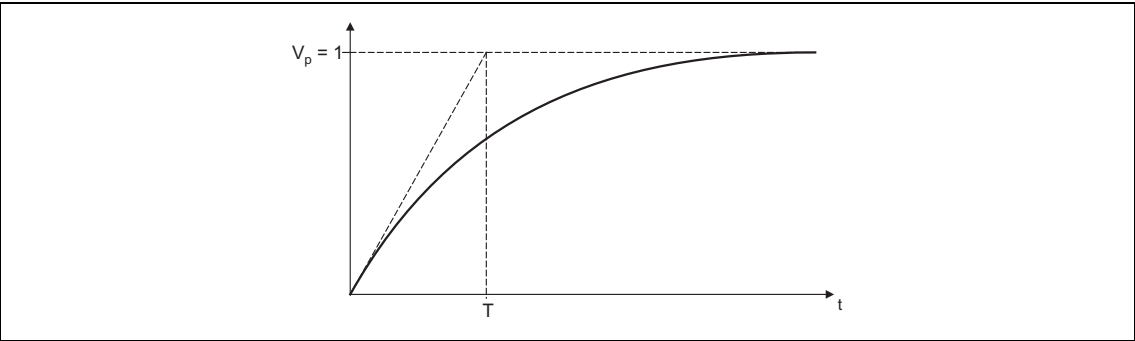
Outputs

Identifier	Data type	Value/meaning
nOut	INT	Output signal

Parameter

Parameter	Possible settings			Info
C00250/2	0	ms	5000	Filter time constant <ul style="list-style-type: none">• The filter is not active with a setting of "0 ms". The input signal is passed through one-to-one to the output.• Lenze setting: 2000 ms

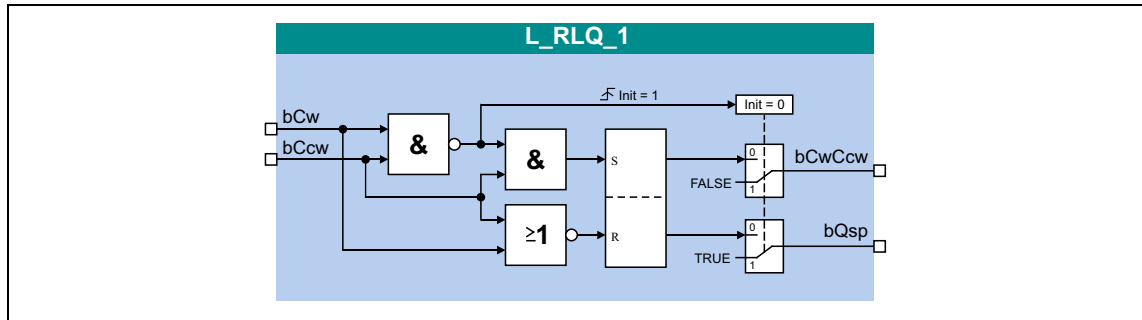
Function



[19-68] Filter time constant T of the first-order delay element

19.1.153 **L_RLO_1**

This FB links a selected direction of rotation to the quick stop function with wire-break protection.



Inputs

Identifier	Data type	Information/possible settings
bCw	BOOL	Input <ul style="list-style-type: none"> • TRUE = CW rotation
bCCw	BOOL	Input <ul style="list-style-type: none"> • TRUE = CCW rotation

Outputs

Identifier	Data type	Value/meaning
bQSP	BOOL	Output signal for quick stop (QSP)
bCwCcw	BOOL	Output signal for CW/CCW rotation • TRUE = CCW rotation

Function

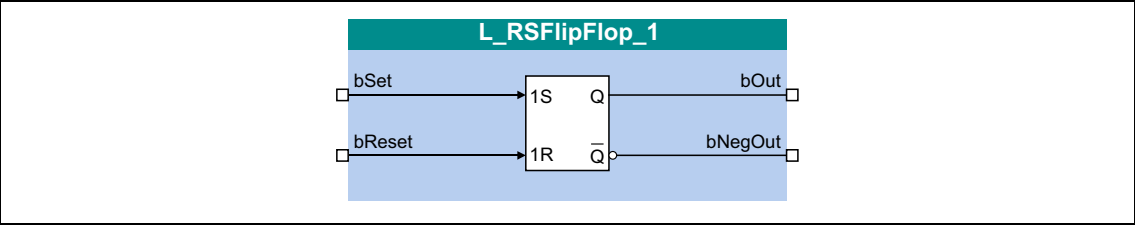
Inputs		Outputs		Notes
bCw	bCCw	bCwCcw	bQSP	
TRUE	TRUE	FALSE	TRUE	The inputs have this status only if a TRUE signal is being applied to <u>both</u> inputs at the moment of switch-on! See also FB illustration above, "Init" = 1.
If <i>one</i> of the inputs has the TRUE status, the following truth table applies:				
FALSE	FALSE	FALSE	TRUE	See also FB illustration above, "Init" = 0.
TRUE	FALSE	FALSE	FALSE	
FALSE	TRUE	TRUE	FALSE	
TRUE	TRUE	X (save)		

[19-69] Truth table of the FB L_RLQ, 0 = FALSE, 1 = TRUE

19.1.154 L_RSFlipFlop_1

The functionality of this FB corresponds to that of an RS flipflop:

- An input signal at *bSet* serves to set the *bOut* output permanently.
- An input signal at *bReset* serves to reset the output.
- Additional, inverted output *bNegOut*



Inputs

Identifier	Data type	Information/possible settings	
bSet	BOOL	Setting input	
		TRUE	<ul style="list-style-type: none">• The <i>bOut</i> output is set to TRUE.• The <i>bNegOut</i> output is set to FALSE.
bReset	BOOL	Reset input	
		TRUE	<ul style="list-style-type: none">• The <i>bOut</i> output is set to FALSE.• The <i>bNegOut</i> output is set to TRUE.

Outputs

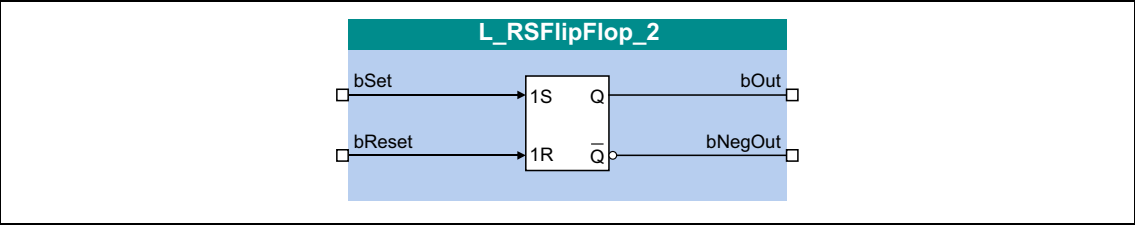
Identifier	Data type	Value/meaning
bOut	BOOL	Output signal
bNegOut	BOOL	Output signal, inverted

19.1.155

L_RSFlipFlop_2

The functionality of this FB corresponds to that of an RS flipflop:

- An input signal at *bSet* serves to set the *bOut* output permanently.
- An input signal at *bReset* serves to reset the output.
- Additional, inverted output *bNegOut*



Inputs

Identifier	Data type	Information/possible settings	
bSet	BOOL	Setting input	
		TRUE	<ul style="list-style-type: none">• The <i>bOut</i> output is set to TRUE.• The <i>bNegOut</i> output is set to FALSE.
bReset	BOOL	Reset input	
		TRUE	<ul style="list-style-type: none">• The <i>bOut</i> output is set to FALSE.• The <i>bNegOut</i> output is set to TRUE.

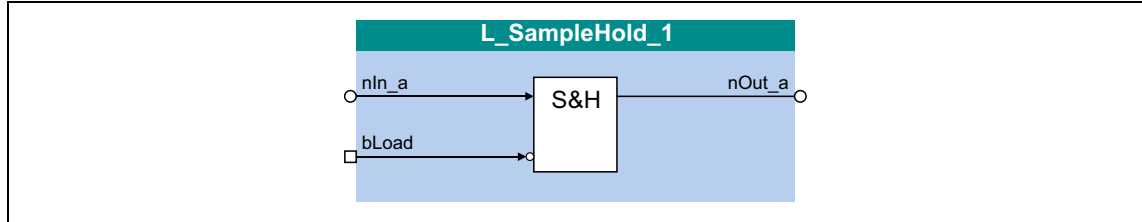
Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output signal
bNegOut	BOOL	Output signal, inverted

19.1.156 L_SampleHold_1

This FB can store a signal.

- The saved value is also available after mains switching.



Inputs

Identifier	Data type	Information/possible settings	
nIn_a	INT	Input signal	
bLoad	BOOL	Save input signal	
		FALSE	The last-valid value at <i>nIn</i> is saved and output to <i>nOut</i> . A signal change at <i>nIn</i> does not cause a change at <i>nOut</i> .
		TRUE	The <i>nOut</i> output provides <i>dnIn</i> .

Outputs

Identifier	Data type	Value/meaning
nOut	INT	Output signal

Function

- When *bLoad* = TRUE, the *nIn_a* signal is switched to *nOut_a*.
- When *bLoad* = FALSE, the last-valid value is saved and output at *nOut_a*. A signal change at *nIn_a* does not cause a change at *nOut_a*.

Behaviour after mains switching

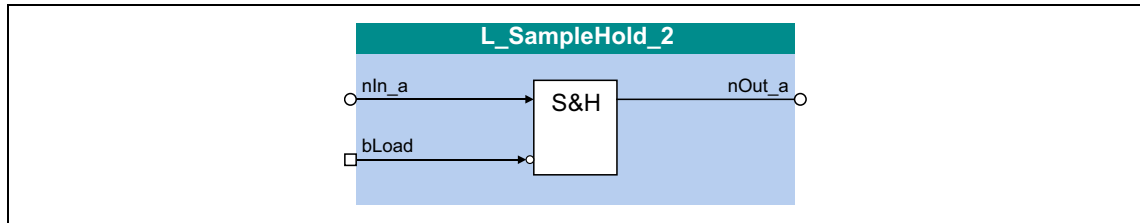
The last-loaded value is permanently stored after switching of the supply voltage and reloaded after restart.

- In order that the saved value is not immediately overwritten with the current input signal at *nIn* after restart, *bLoad* must be set to FALSE at restart.

19.1.157 L_SampleHold_2

This FB can store a signal.

- The saved value is also available after mains switching.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal
bLoad	BOOL	Save input signal
		FALSE The last-valid value at <i>nIn</i> is saved and output to <i>nOut</i> . A signal change at <i>nIn</i> does not cause a change at <i>nOut</i> .
		TRUE The <i>nOut</i> output provides <i>dnIn</i> .

Outputs

Identifier	Data type	Value/meaning
nOut	INT	Output signal

Function

- When *bLoad* = TRUE, the *nIn_a* signal is switched to *nOut_a*.
- When *bLoad* = FALSE, the last-valid value is saved and output at *nOut_a*. A signal change at *nIn_a* does not cause a change at *nOut_a*.

Behaviour after mains switching

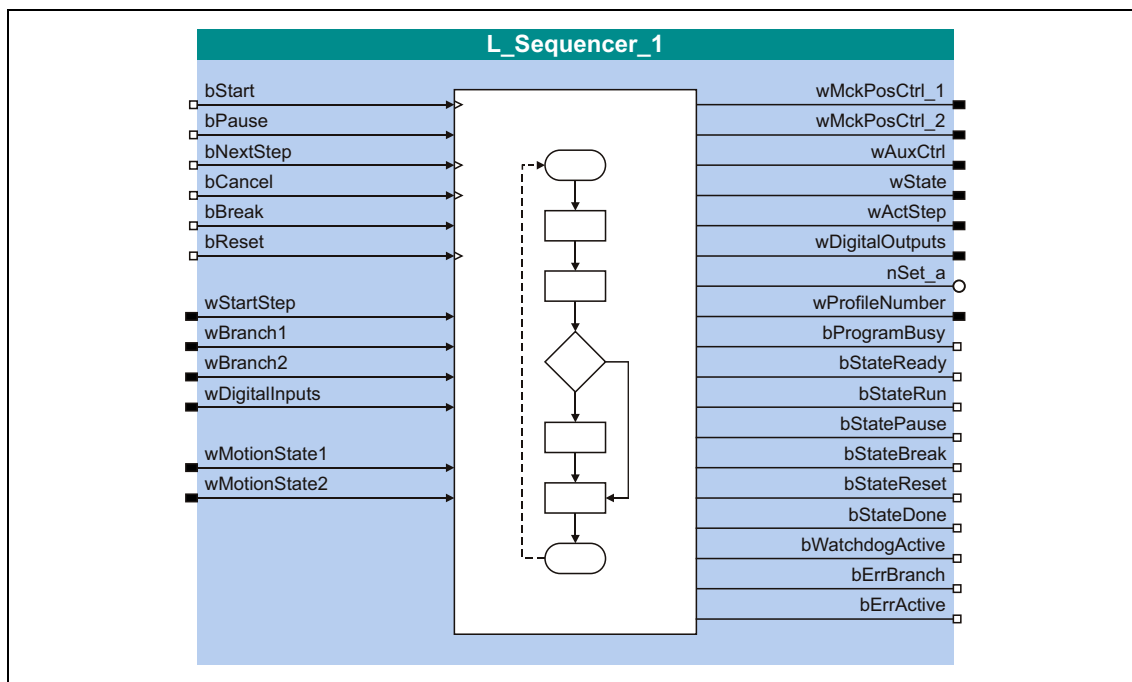
The last-loaded value is permanently stored after switching of the supply voltage and reloaded after restart.

- In order that the saved value is not immediately overwritten with the current input signal at *nIn* after restart, *bLoad* must be set to FALSE at restart.

19.1.158 L_Sequencer_1

This FB processes a positioning program by means of a sequence table.

- The sequence table is a central component of this FB and is represented by a code with 100 subcodes where each subcode references to a program segment which is called "action".
- Different action types are available which serve to realise, for instance, program branching, switching operation, waiting times and counters. The actions themselves are represented by codes as well.
 - The following action types are passive: "Branching", "variable branching", "switching", "setting the counter", "counting", "time waiting" and "program end". When these action types are being processed, the "Stop" operating mode is active and a brake, if available, will be applied.
 - The action types "positioning" and "homing", however, are active as these two action types trigger the execution of the respective basic function via the corresponding control inputs.
 - The "Stand-by" action type is active when a setpoint has been set for the speed follower or a setpoint position is transferred to the SB [LS_MotionControlKernel](#) when "position follower" has been selected.



Inputs

Identifier	Data type	Information/possible settings
bStart	BOOL	Start/continue positioning program FALSE → TRUE The positioning program is started/continued. <ul style="list-style-type: none"> • Counters and outputs are not reset automatically through this. • A positioning program previously interrupted by <i>bBreak</i> is continued with the sequence step. • The started positioning program is processed up to its program end even if <i>bStart</i> is reset to FALSE again.

Identifier	Data type	Information/possible settings	
bPause	BOOL	Interrupt the current step of the positioning program	
		TRUE	<ul style="list-style-type: none">• An active positioning is interrupted.• The drive is stopped with the current profile deceleration.• A deceleration override is considered.• The sequence of an active timing element is stopped.• An action of "Standby" type is not interrupted.
		FALSE	<ul style="list-style-type: none">• The interrupted positioning is completed.• The distance of the profile already covered is considered here.• Positionings with final speed are not continued when the final speed cannot be reached anymore.• The sequence of the stopped timing element is continued with the remaining time.
bNextStep	BOOL	Cancel the current step and go to the next step	
		FALSE↗TRUE	The current step of the positioning program is cancelled immediately and the positioning program is continued with the next step in the sequence table.
bCancel	BOOL	Cancel the current step and go to the step defined in C01404	
		FALSE↗TRUE	The current step of the positioning program is cancelled immediately and the positioning program is continued with the step defined in C01404 .
bBreak	BOOL	Interrupt positioning program <ul style="list-style-type: none">• This input is intended for being connected to drive-relevant status signals (e.g. for controller inhibit or quick stop).• If the interruption is deactivated again by a reset to FALSE, a new FALSE/TRUE edge is required at <i>bStart</i> in order that the positioning program is continued with the sequence step.	
		FALSE	Condition for program start via <i>bStart</i> .
		TRUE	<p>The active positioning program is interrupted.</p> <ul style="list-style-type: none">• If a positioning is active, the drive is brought to a standstill with the delay time for stop (C01251/1).• The MCK operating modes Speed follower, Homing, Positioning and Position follower are deactivated.• The digital output signals keep their states.
bReset	BOOL	Reset positioning program. <ul style="list-style-type: none">• Also possible with interrupted positioning program.	
		FALSE↗TRUE	<p>The positioning program is reset.</p> <ul style="list-style-type: none">• If a positioning is active, the drive is brought to a standstill with the delay time for stop (C01251/1) without considering an acceleration override.• The program flow is cancelled ("program end").• The digital output signals, counters and timing elements are reset.• If the "Stand-by" action is active, it is cancelled.
wStartStep	WORD	Step of the sequence table the positioning program is to start with.	
		0	Positioning program starts with step 1 of the sequence table.
		1 ... 100	First step
		Others	Positioning program does not start.
		not assigned	Positioning program starts with step 1 of the sequence table.

Identifier	Data type	Information/possible settings												
wBranch1	WORD	<div>Input signal for action 1 of "Variable branching" type</div> <div><ul style="list-style-type: none">When the positioning program contains an action 1 of "Variable branching" type, branching is carried out in the corresponding step depending on the value available at this input:</div> <table><tr><td>0</td><td>Branching to the next step.</td></tr><tr><td>1</td><td>Branching to the step defined in C01418/1.</td></tr><tr><td>2</td><td>Branching to the step defined in C01419/1.</td></tr><tr><td>...</td><td>...</td></tr><tr><td>20</td><td>Branching to the step defined in C01437/1.</td></tr><tr><td>>20</td><td>Branching to the next step.</td></tr></table>	0	Branching to the next step.	1	Branching to the step defined in C01418/1 .	2	Branching to the step defined in C01419/1	20	Branching to the step defined in C01437/1 .	>20	Branching to the next step.
0	Branching to the next step.													
1	Branching to the step defined in C01418/1 .													
2	Branching to the step defined in C01419/1 .													
...	...													
20	Branching to the step defined in C01437/1 .													
>20	Branching to the next step.													
wBranch2	WORD	<div>Input signal for action 2 of "Variable branching" type</div> <div><ul style="list-style-type: none">When the positioning program contains an action 2 of "Variable branching" type, branching is carried out in the corresponding step depending on the value available at this input:</div> <table><tr><td>0</td><td>Branching to the next step.</td></tr><tr><td>1</td><td>Branching to the step defined in C01418/2.</td></tr><tr><td>2</td><td>Branching to the step defined in C01419/2.</td></tr><tr><td>...</td><td>...</td></tr><tr><td>20</td><td>Branching to the step defined in C01437/2.</td></tr><tr><td>>20</td><td>Branching to the next step.</td></tr></table>	0	Branching to the next step.	1	Branching to the step defined in C01418/2 .	2	Branching to the step defined in C01419/2	20	Branching to the step defined in C01437/2 .	>20	Branching to the next step.
0	Branching to the next step.													
1	Branching to the step defined in C01418/2 .													
2	Branching to the step defined in C01419/2 .													
...	...													
20	Branching to the step defined in C01437/2 .													
>20	Branching to the next step.													
wDigitalInputs	WORD	<div>Sequencer inputs 1 ... 16 (bit coded)</div> <div><ul style="list-style-type: none">The action types "positioning", "branching", "waiting" and "stand-by" have the "Input for..." parameter. If this is non-zero, it names the number of the sequencer input where the positioning program expects the respectively defined level before action is executed.For the transfer of individual control signals, e.g. the converter FB L_ConvBitsToWorld_1 can be connected to this input.</div> <table><tr><td>Bit 0</td><td>Sequencer input 1</td></tr><tr><td>Bit 1</td><td>Sequencer input 2</td></tr><tr><td>...</td><td>...</td></tr><tr><td>Bit 15</td><td>Sequencer input 16</td></tr></table>	Bit 0	Sequencer input 1	Bit 1	Sequencer input 2	Bit 15	Sequencer input 16				
Bit 0	Sequencer input 1													
Bit 1	Sequencer input 2													
...	...													
Bit 15	Sequencer input 16													
wMotionState1 wMotionState2	WORD	<div>Interface to the basic drive functions (MCK)</div> <div><ul style="list-style-type: none">Connect these inputs to the outputs with the same name of the SB LS_MotionControlKernel.</div> <div>► Connection to the basic drive functions (MCK)</div>												

Outputs

Identifier	Data type	Value/meaning
wMckPosCtrl1 wMckPosCtrl2 wAuxCtrl	WORD	<p>Interface to the basic drive functions (MCK)</p> <ul style="list-style-type: none"> Connect the outputs <i>wMckPosCtrl1</i> and <i>wMckPosCtrl2</i> to the inputs <i>wInMckPosCtrl1</i> and <i>wInMckPosCtrl2</i> des FB L_MckCtrlInterface_1. Connect the <i>wAuxCtrl</i> output to the input with the same name of the SB LS_MotionControlKernel. <p>► Connection to the basic drive functions (MCK)</p>

Identifier	Data type	Value/meaning
wState	WORD	Status (bit-coded)
		Bit 1 Positioning program ready to start/program end reached.
		Bit 2 Positioning program is running.
		Bit 3 Positioning program started, break active.
		Bit 4 Positioning program stopped.
		Bit 5 Positioning program reset.
		Bit 6 Positioning program completed.
		Bit 7 Time monitoring for " positioning " action has been triggered.
		Bit 8 Wrong value at branch input.
wActStep	WORD	Current step being processed by the positioning program.
		0 Positioning program not started.
		1 ... 100 Current step
wDigitalOutputs	WORD	Sequencer outputs 1 ... 16 (bit coded)
		<ul style="list-style-type: none"> The sequencer outputs can be set to "0" or "1" by the "switching" action type during the runtime of the positioning program. For providing individual control signals, e.g. the converter FB L_ConvWordToBits_1 can be connected to this output.
		Bit 0 Sequencer output 1
		Bit 1 Sequencer output 2
	
nSet_a	INT	Speed setpoint which is output in the " Stand-by " action.
		• If no "Stand-by" action is active, the value "0" is output.
wProfileNumber	WORD	Display of the profile data set active in the current step
bProgramBusy	BOOL	Status signal "Positioning program is running"
		FALSE Positioning program not started or stopped.
		TRUE Positioning program is running.
bStateReady	BOOL	TRUE Positioning program ready to start/program end reached.
bStateRun	BOOL	TRUE Positioning program is running.
bStatePause	BOOL	TRUE Positioning program started, break active.
bStateBreak	BOOL	TRUE Positioning program stopped.
bStateReset	BOOL	TRUE Positioning program reset.
bStateDone	BOOL	TRUE Positioning program completed.
bWatchdogActive	BOOL	TRUE Time monitoring for " positioning " action has been triggered.
bErrBranch	BOOL	TRUE Wrong value at branch input.
bErrActive	BOOL	TRUE Fault is active.

General parameters

**Note!**

The parameters of the different actions for the sequence table are described in the corresponding action subchapter.

Parameter	Possible settings			Info
C01400/1...100				Action in sequence step n <ul style="list-style-type: none">• In the subcodes, the calls of the actions required for the positioning program are stored. In this way, the basic sequence (with the exception of the branches) is defined.
	0	Program end		
	xxyyy	Action call <ul style="list-style-type: none">• xx ≡ Action type• yyy ≡ Action number		
C01401	1		100	Current step <ul style="list-style-type: none">• Read only
C01402				Sequence control: Status <ul style="list-style-type: none">• Read only
	0	READY: Positioning program ready to start/program end reached.		
	1	RUN: Positioning program is running.		
	2	PAUSE: Current step interrupted, break is active.		
	3	BREAK: Positioning program interrupted.		
	4	RESET: Positioning program reset.		
C01403				Sequence control: Control word <ul style="list-style-type: none">• Bit coded code for controlling the sequencer by a PC or a master control via parameter channel.• By setting a bit to "1", the respective function is activated.
	Bit 0	Start		
	Bit 1	Break		
	Bit 2	Break		
	Bit 3	Cancel		
	Bit 4	Reset		
	Bit 5	NextStep		
C01404				Step takes place when <i>bCancel</i> = TRUE <ul style="list-style-type: none">• This step is processed if the <i>bCancel</i> input is set to TRUE.
	0	Sequence step		
	1...100	Step 1 ... 100		
	101	Program end		

19.1.158.1 Connection to the basic drive functions (MCK)

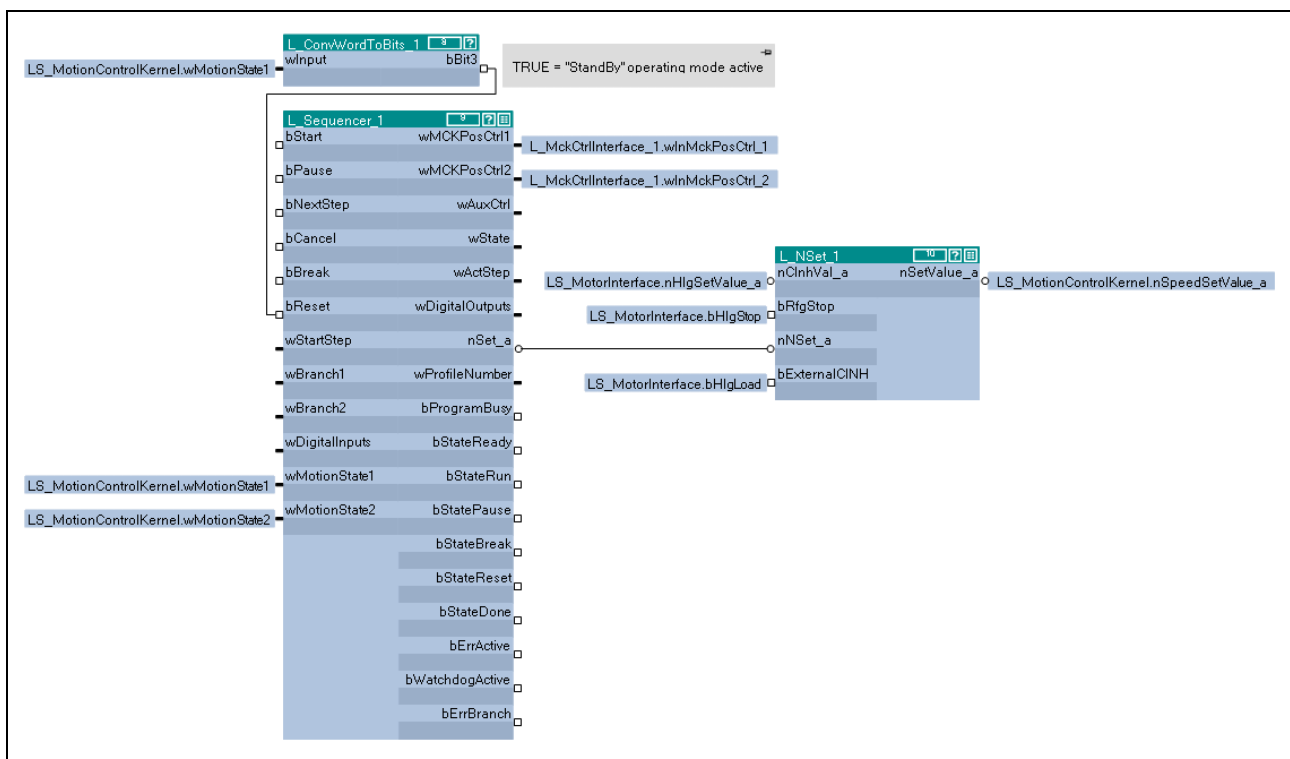
Required connections in the FB Editor

The recommended starting basis for a connection with the FB **L_Sequencer_1** is the use of the [TA "Table positioning"](#).

The following configuration shows the required connections in order that the execution of the prevailing basic function is triggered in **LS_MotionControlKernel** for the two action types "Positioning" and "Referencing".

With a corresponding parameter setting, the *nSet_a* output serves to transfer a speed setpoint to the basic function "speed follower" if an action of Standby type is active.

The process is reset in the MCK "Standby" operating mode. The internal "StandBy" operating mode is assumed implicitly if controller inhibit, pulse inhibit, quick stop and/or DC-injection braking are activated. ▶ ["StandBy" operating mode](#) (567)



[19-70] Basic integration of the sequence control into the application

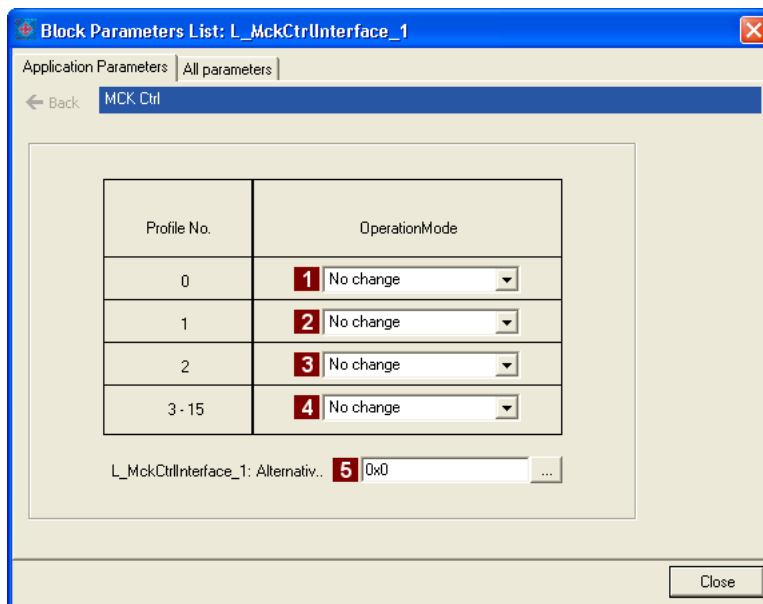


Note!

The FB **L_Sequencer_1** has to be called in the processing order before the FB **L_MckCtrlInterface_1**!

Required parameter settings

For an error-free function of the sequence control, the following parameter settings are required for the FB [L_MckCtrlInterface_1](#):



Parameter	Info
1 MCK operating mode at profile no. 0 (C01298/1)	Selection of the operating mode for profile 0 ... 15 at L_MckCtrlInterface_1. For these four parameters, set the selection "0: No change" (no assignment of an operating mode to a profile).
2 MCK operating mode at profile no. 1 (C01298/2)	
3 MCK operating mode at profile no. 2 (C01298/3)	
4 MCK operating mode at profile no. 3...15 (C01298/4)	
5 L_MckCtrlInterface_1: Alternative function (C01297)	Bit coded selection of the Alternative functions for the bit 16 (PosExecute) in the MCK control word. For this parameter, set the hexadecimal value "0x0" to deactivate all alternative functions.

19.1.158.2 Priorities of the control signals

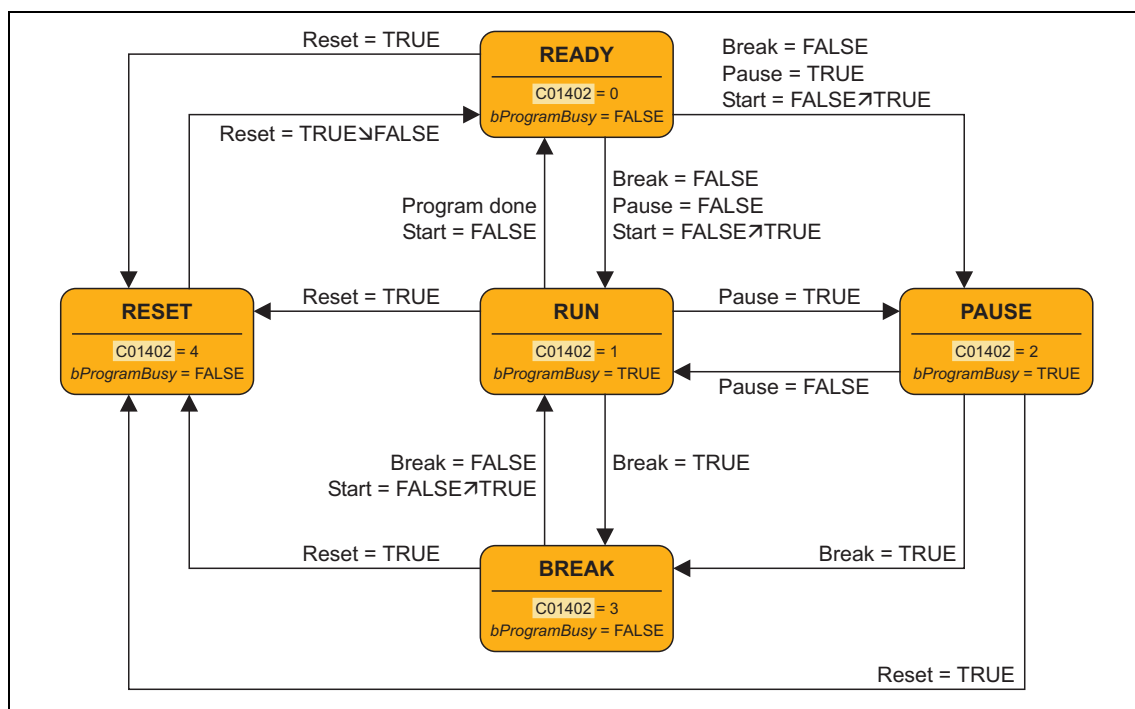
The boolean control signals have the following priorities (1 = highest priority):

1. *bReset*
2. *bBreak*
3. *bPause*
4. *bStart*
5. *bCancel*

19.1.158.3 States of the sequencer

The internal state machine of the sequencer distinguishes the following five states:

Status	Display C01402	Impact/meaning
Ready	0	When there is no interruption by <i>bBreak</i> , the program can be started.
RUN	1	The program is processed.
Break	2	The program is paused and the traversing of a profile is stopped. <ul style="list-style-type: none"> The outputs keep their states An active positioning is interrupted. <ul style="list-style-type: none"> The drive is stopped with the current profile deceleration. A acceleration override is not considered. After deactivating the break, the positioning program and a previously active positioning are continued at the same position.
Break	3	The traversing of a profile is cancelled. <ul style="list-style-type: none"> The drive with the delay time for stop (C01251/1) is brought to a standstill. The digital output signals keep their states. After the interruption has been deactivated (<i>bBreak</i> = FALSE), another start signal is required to continue the program with the sequence step.
Reset	4	The program is reset. <ul style="list-style-type: none"> An active positioning is cancelled. <ul style="list-style-type: none"> The drive with the delay time for stop (C01251/1) is brought to a standstill. A acceleration override is not considered. The program flow is cancelled ("program end"). The digital output signals and the counter are reset. If a standby operation is active, it will be cancelled.



[19-71] Internal state machine of the sequencer

19.1.158.4 Overview: Available action types

The program flow of the sequential positioning control is defined by means of a sequence table which can contain up to 100 references to "actions".



- An action comprises a clear functionality which is described with a few parameters.
- Different action types are available which serve to realise, for instance, program branching, switching operation, waiting times and counters.
- A certain number of actions are available from every action type which can be parameterised individually.
- An action can be called from several positions in the sequence table.
- After an action has been processed, the action entered in the sequence step of the sequence table is automatically processed unless a branching causes a jump to another step in the sequence table.
- Maximally one action can be processed per calculation cycle.
- The sequence table and the actions themselves are represented by parameters (codes with subcodes).
- Action calls are entered in the sequence table as a decimal number that contains the action type **A** and the action number **B**:



Overview

Action	Action type A	Action number B	Number of available actions	Parameter range
Program end	0	000	1	-
Positioning	1	001 ... 050	50	C01405 ... C01410
Switching	2	001 ... 016	16	C01411 ... C01414
Branching	3	001 ... 016	16	C01415 ... C01417
Variable branching	4	001 ... 002	2	C01418 ... C01437
Homing	5	000	1	-
Time waiting	7	001 ... 008	8	C01438 ... C01440
Counter setting	8	001 ... 005	5	C01441 ... C01442
Counting	9	001 ... 008	8	C01443 ... C01448
Stand-by	10	001 ... 005	5	C01449 ... C01452

You can find detailed information on the action types in the following subchapters.

19.1.158.5 Action type "Program end"

In order to define the program end within the sequence table, an action of "program end" type is available.

Action call (entry in the sequence table)**0**

(Leading zeros can be omitted.)

- When the *bStart* input is reset to FALSE while the positioning program is running, processing is only continued until program end is reached.
- In the Lenze setting, all entries of the sequence table are set to "0" and thus to "program end".

19.1.158.6 Action type "positioning"



For starting a positioning, 50 actions of "positioning" type are available. The [Profile entry](#) is made via the parameters of the basic function "[Positioning](#)".

Action call (entry in the sequence table)

1 **x** **x** **x** with action number xxx = 001 ... 050

Parameter

The available actions 1 ... 50 are represented via the subcodes 1 ... 50.

Parameter	Possible settings			Info
C01405/1...50				Pos. action n: Starting with
	0	Waiting function deactivated		In the default setting, the execution of the profile is started immediately.
	1	Sequencer input 1 (Bit 0 of <i>wDigitalInputs</i>)		"Wait for level": The execution of the profile is only started when the selected sequencer input has the polarity set in C01406/x .
	2	Sequencer input 2 (Bit 1 of <i>wDigitalInputs</i>)		
		
	16	Sequencer input 16 (Bit 15 of <i>wDigitalInputs</i>)		
C01406/1...50				Pos. action n: Polarity input
	0	Condition is bit state "0"		• State of the sequencer input required for starting the profile.
	1	Condition is bit state "1"		
C01407/1...50				Pos. action n: Profile number
	0	No profile executed		• A sequence profile can be set in the corresponding profile parameter.
	1...15	Execute profile no. 1 ... 15		
C01408/1...50				Pos. action n: Jump destination
	0	Sequence step		• Step within the sequence table which is processed after the profile has been executed.
	1...100	Step 1 ... 100		
C01409/1...50	0.000	s	2147480.000	Pos. action n: Monitoring time
	When "0.000 s" is set (Lenze setting), time monitoring is deactivated.			• If the positioning process lasts longer than the monitoring time set here, it is branched to the jump destination set in C01410/x .
C01410/1...50				Pos. action n: Jump destination monitoring
	0	Sequence step		• Step that is executed after the monitoring time has been exceeded.
	1...100	Step 1 ... 100		

19.1.158.7 Action type "switching"



For switching digital output signals, 16 actions of "switching" type are available. Every action can set two selectable bits of the *wDigitalOutputs* output signal to "0" or "1", independent of each other.

Action call (entry in the sequence table)

2 **x** **x** **x** with action number xxx = 001 ... 016

Parameter

The available actions 1 ... 16 are represented via the subcodes 1 ... 16.

Parameter	Possible settings	Info
C01411/1...16	0 Deactivated	Switching act. n: Output switching A • Selection of the sequencer output which is to be set to the polarity set in C01412/x .
	1 Sequencer output 1 (Bit 0 of <i>wDigitalOutputs</i>)	
	2 Sequencer output 2 (Bit 1 of <i>wDigitalOutputs</i>)	
	
	16 Sequencer output 16 (Bit 15 of <i>wDigitalOutputs</i>)	
C01412/1...16	0 Set output bit to "0"	Switching act. n: Pol. switching A • State to which the sequencer output selected in C01411/x is to be set.
	1 Set output bit to "1"	
C01413/1...16	0 Deactivated	Switching act. n: Output switching B • Selection of the sequencer output which is to be set to the polarity set in C01414/x .
	1 Sequencer output 1 (Bit 0 of <i>wDigitalOutputs</i>)	
	2 Sequencer output 2 (Bit 1 of <i>wDigitalOutputs</i>)	
	
	16 Sequencer output 16 (Bit 15 of <i>wDigitalOutputs</i>)	
C01414/1...16	0 Set output bit to "0"	Switching act. n: Pol. switching B • State to which the sequencer output selected in C01413/x is to be set.
	1 Set output bit to "1"	

19.1.158.8 Action type "Branching"



For conditional and unconditional branching (jumps), 16 actions of "Branching" Type are available.

Action call (entry in the sequence table)



with action number xxx = 001 ... 016

Parameter

The available actions 1 ... 16 are represented via the subcodes 1 ... 16.

Parameter	Possible settings	Info
C01415/1...16		Branching action n: Input for jump
	0 Unconditional branch	"Unconditional branch": It is always branched to the jump destination set in C01417/x .
	1 Sequencer input 1 (Bit 0 of <i>wDigitalInputs</i>)	"Conditional branch": It is only branched to the jump destination set in C01417/x if the selected sequencer input has the polarity set in C01416/x . • Otherwise, the following step in the sequence table will be processed.
	2 Sequencer input 2 (Bit 1 of <i>wDigitalInputs</i>)	
	
	16 Sequencer input 16 (Bit 15 of <i>wDigitalInputs</i>)	
C01416/1...16		Branching action n: Polarity input
	0 Condition is bit state "0"	• State of the selected sequencer input required for a conditional branch to the jump destination.
	1 Condition is bit state "1"	
C01417/1...16		Branching act. n: Jump destination
	0 Sequence step	• In case of unconditional branch, it is always branched to the jump destination set here.
	1...100 Step 1 ... 100	• In case of conditional branch, it is only branched to the jump destination set here if the sequencer input selected in C01415/x has the polarity set in C01416/x . Otherwise, the following step in the sequence table will be processed.

19.1.158.9 Action type "Variable branching"



For variable branching (jumps), two actions of "variable branching" type are available.

- Branching to one of 20 possible steps is carried out depending on the *wBranch1* input signal or *wBranch2* input signal at the time of processing.
 - *wBranch1* input signal defines branching for action 1.
 - *wBranch2* input signal defines branching for action 2.
- Example: If the *wBranch2* input signal has the value "15" at the time of processing of the action no. 2, it is branched to the step entered in the parameter "Var. branching n: Jump destination 15" for action no. 2 ([C01432/2](#)).

Action call (entry in the sequence table)



with action number xxx = 001 ... 002

Parameter

The available actions 1 ... 2 are represented via the subcodes 1 ... 2.

Parameter	Possible settings		Info
C01418/1...2			Var. branch n: Jump destination 1 ... 20 • Branch destinations 1 ... 20 for input values 1 ... 20 of <i>wBranch1...2</i> .
...	0	Branching deactivated (The following step in the sequence table is processed.)	
C01437/1...2	1...100	Step 1 ... 100	

19.1.158.10 Action type "Homing"

For starting a homing, an action of "homing" type is available.

- The settings for homing (e.g. homing mode) can be made via the parameters of the basic function "[Homing](#)".
- After homing is completed (*bHomingDone* = TRUE), the program flow is continued with the next step.

Action call (entry in the sequence table)

5	0	0	0
---	---	---	---

Parameter

The "homing" action has no own parameters.

19.1.158.11 Action type "Time waiting"



For inserting waiting times into the program flow, 8 actions of "Time waiting" are available. The sequence step will only be processed after a waiting time has elapsed or when a selectable sequencer input has a certain bit state ("0" or "1").

Action call (entry in the sequence table)

7 **x** **x** **x** with action number xxx = 001 ... 008

Parameter

The available actions 1 ... 8 are represented via the subcodes 1 ... 8.

Parameter	Possible settings			Info
C01438/1...8	0.000	s	2127480.000	Waiting act. n: Waiting time • Initialisation: 1.000 s
C01439/1...8				Waiting act. n: Input for "Next"
	0	Input deactivated		"Time waiting": Sequence step will only be processed after the set waiting time has elapsed.
	1	Sequencer input 1 (Bit 0 of <i>wDigitalInputs</i>)		"Wait for level": Sequence step will only be processed when the selected sequencer input has the polarity set in C01440/x . Note! With a waiting time set to > 0 s, however, the sequence step will be processed after the set waiting time has elapsed at the latest.
	2	Sequencer input 2 (Bit 1 of <i>wDigitalInputs</i>)		
		
	16	Sequencer input 16 (Bit 15 of <i>wDigitalInputs</i>)		
C01440/1...8				Waiting act. n: Polarity input • State of the selected sequencer input required for processing the sequence step.
	0	Condition is bit state "0"		
	1	Condition is bit state "1"		

19.1.158.12 Action type "Counter setting"



For setting one of the 5 available counters to a certain starting value, 5 actions of "Counter setting" type are available.

- The 5 actions of "counter setting" type are not permanently assigned to the 5 counters.
- You can, e.g., set a counter to a value using an action of "counter setting" type and at a later program time set the same counter to a different value using another action of "counter setting" type.
- The current counter content of the counters 1 ... 5 is displayed in [C01443/1...5](#).

Action call (entry in the sequence table)



with action number xxx = 001 ... 005

Parameter

The available actions 1 ... 5 are represented via the subcodes 1 ... 5.

Parameter	Possible settings			Info
C01441/1...5				Counter setting act. n: Counter no.
	0	Counter setting deactivated		
	1	Counter 1		
		
	5	Counter 5		
C01442/1...5	-2147483647		2147483647	Counter setting act. n: Starting value

19.1.158.13 Action type "Counting"



For counting processes, 8 actions of "counting" type are available.

- Every processing of the action causes an increase or decrease of the counter content of the corresponding counter by the set step value (counting up or down).
- If the comparison condition for comparing the counter content to an adjustable comparison value is fulfilled, it can be branched to any step.
- For setting a counter to a starting value, 5 actions of "[counter setting](#)" type are available.
- The current counter content of the counters 1 ... 5 is displayed in [C01443/1...5](#).

Action call (entry in the sequence table)

9 **x** **x** **x** with action number xxx = 001 ... 008

Parameter

The available actions 1 ... 8 are represented via the subcodes 1 ... 8.

Parameter	Possible settings			Info
C01443/1...5	-2147483647		2147483647	Counter n: Current counter content • Read only
C01444/1...8				Counting act. n: Counter no.
	0	Counting deactivated (Sequence step is processed.)		
	1	Counter 1		
		
	5	Counter 5		
C01445/1...8	-2147483647		2147483647	Counting act. n: Step value • Value by which the counter is increased or decreased. • Initialisation: 1
C01446/1...8	-2147483647		2147483647	Counting act. n: Comparison value • Value to which the counter is compared.
C01447/1...8				Counting act. n: Jump destination • If the set comparison condition is fulfilled, it is branched to the step set here. • If the condition is not fulfilled or "0" setting, the step followed in the sequence table is processed.
	0	Sequence step		
	1...100	Step 1 ... 100		
C01448/1...8				Counting act. n: Comparison operation
	1	Counter content = comparison value		
	2	Counter content > comparison value		
	3	Counter content ≥ comparison value		
	4	Counter content < comparison value		
	5	Counter content ≤ comparison value		

19.1.158.14 "Stand-by" action type

Standby

For a temporary activation of a setpoint follower, 5 actions of "stand-by" type are available.

- The corresponding setpoint follower remains enabled until the condition for completing stand-by is fulfilled.
- If the "stand-by" step is active, the setpoint set in [C01452](#) is provided at the *nSet_a* output (Lenze setting: 0 %).

Action call (entry in the sequence table)














1 **0** **x** **x** **x** with action number xxx = 001 ... 005

Parameter

The available actions 1 ... 5 are represented via the subcodes 1 ... 5.

Parameter	Possible settings			Info
C01449/1...5				Stand-by act. n: Input for "End" <ul style="list-style-type: none">The setpoint follower selected in C01451/x remains enabled until the sequencer input selected here has the polarity set in C01450/x.
	1	Sequencer input 1 (Bit 0 of <i>wDigitalInputs</i>)		
	2	Sequencer input 2 (Bit 1 of <i>wDigitalInputs</i>)		
		
	16	Sequencer input 16 (Bit 15 of <i>wDigitalInputs</i>)		
C01450/1...5				Stand-by act. n: Polarity input <ul style="list-style-type: none">State of the selected sequencer input required for ending the stand-by an processing the sequence step.
	0	Condition is bit state "0"		
	1	Condition is bit state "1"		
C01451/1...5				Stand-by act. n: Follower mode <ul style="list-style-type: none">Selection which follower in the stand-by mode is to be activated.
	0	Operation Speed follower		
	1	Operation Position follower		
C01452/1...5	-200	%	200	Stand-by act. n: Setpoint <ul style="list-style-type: none">Setpoint for the Speed follower (provided at the output <i>nSet_a</i>).Initialisation: 0 %

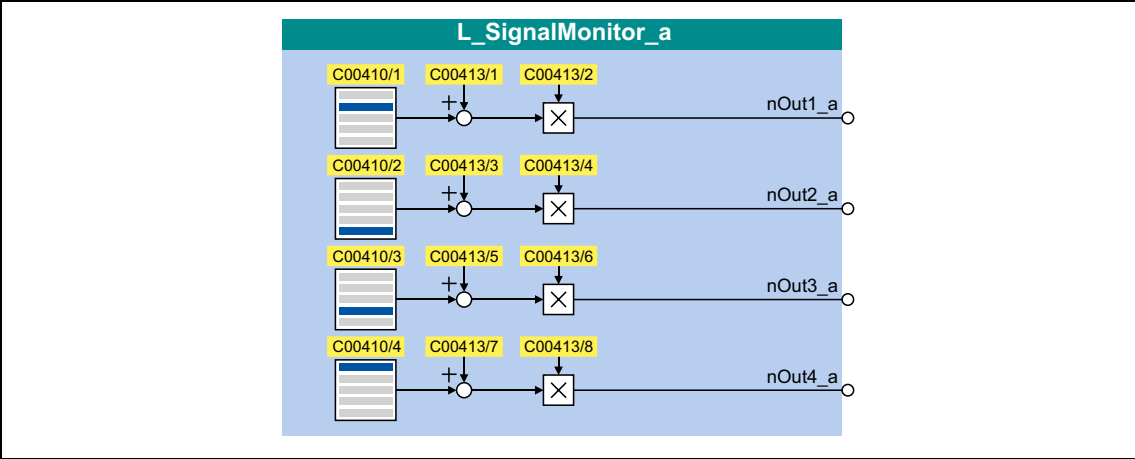
19.1.158.15 Example: Sequence table

Parameter	Entry	≡ Action type/action no.		Meaning
C01400/1	5000		-	Execute homing
C01400/2	3001		1	Process action 1 of "branching" (3) type
C01400/3	9005		5	Process action 5 of "Counting" type (9)
C01400/4	1001		1	Process action 1 of "positioning" type (1)
C01400/5	7003		3	Process action 3 of "Time waiting" type (7)
C01400/6	1002		2	Process action 2 of "positioning" type (1)
C01400/7	3002		2	Process action 2 of "branching" (3) type
C01400/8	9005		5	Process action 5 of "Counting" type (9)
C01400/9	3004		4	Process action 4 of "branching" (3) type
C01400/...	yyxxx	yy	xxx	Process action xxx of yy type
C01400/24	1003		3	Process action 3 of "positioning" type (1)
C01400/25	0		-	Program end
C01400/26	0		-	Program end
C01400/...
C01400/100	0		-	Program end

19.1.159 L_SignalMonitor_a

This FB outputs four analog signals which can be selected from a list of analog output signals of all function blocks provided in the device.

- Offset and gain of the source signals are adjustable.



Outputs

Identifier	Data type	Value/meaning
nOut1_a	INT	Output signal • Internal limitation to ± 32767
nOut2_a	INT	Output signal • Internal limitation to ± 32767
nOut3_a	INT	Output signal • Internal limitation to ± 32767
nOut4_a	INT	Output signal • Internal limitation to ± 32767

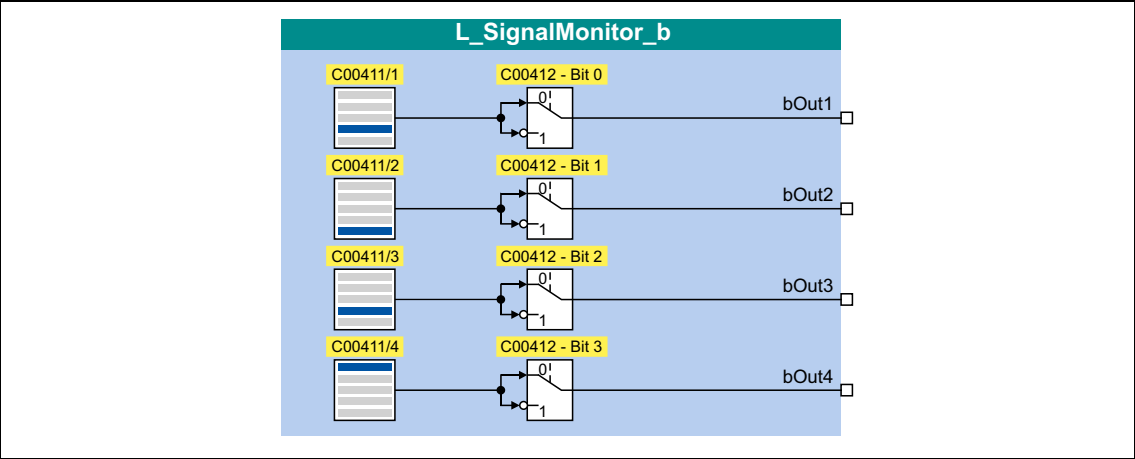
Parameter

Parameter	Possible settings			Info
C00410/1 ... C00410/4	See selection list - analog signals			Selection of the signal sources for <i>nOut1_a ... nOut4_a</i>
C00413/1 C00413/3 C00413/5 C00413/7	-199.99	%	+199.99	Offset
C00413/2 C00413/4 C00413/6 C00413/8	-199.99	%	+199.99	Gain

19.1.160 L_SignalMonitor_b

This FB outputs four binary signals which can be selected from a list of binary output signals of all function blocks provided in the device.

- Inversion of the output signals can be set.



Outputs

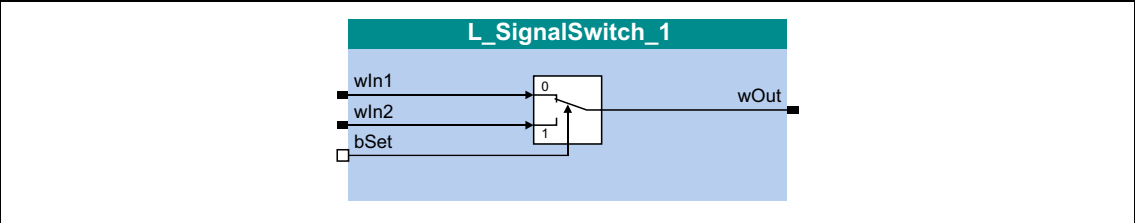
Identifier	Data type	Value/meaning
bOut1 ... bOut4	BOOL	Output signal FALSE / TRUE

Parameter

Parameter	Possible settings	Info																
C00411/1 ... C00411/4	See selection list - digital signals	Selection of the signal sources for <i>bOut1 ... bOut4</i>																
C00412	Value is bit-coded: <table><tr><td>Bit 0</td><td>bOut1 inverted</td></tr><tr><td>Bit 1</td><td>bOut2 inverted</td></tr><tr><td>Bit 2</td><td>bOut3 inverted</td></tr><tr><td>Bit 3</td><td>bOut4 inverted</td></tr><tr><td>Bit 4</td><td>Reserved</td></tr><tr><td>Bit 5</td><td>Reserved</td></tr><tr><td>Bit 6</td><td>Reserved</td></tr><tr><td>Bit 7</td><td>Reserved</td></tr></table>	Bit 0	bOut1 inverted	Bit 1	bOut2 inverted	Bit 2	bOut3 inverted	Bit 3	bOut4 inverted	Bit 4	Reserved	Bit 5	Reserved	Bit 6	Reserved	Bit 7	Reserved	Inversion <ul style="list-style-type: none">• Bit set = inversion active
Bit 0	bOut1 inverted																	
Bit 1	bOut2 inverted																	
Bit 2	bOut3 inverted																	
Bit 3	bOut4 inverted																	
Bit 4	Reserved																	
Bit 5	Reserved																	
Bit 6	Reserved																	
Bit 7	Reserved																	

19.1.161 L_SignalSwitch_1

This FB switches between two input signals of the "WORD" data type. The switch-over is controlled by means of a boolean input signal.



Inputs

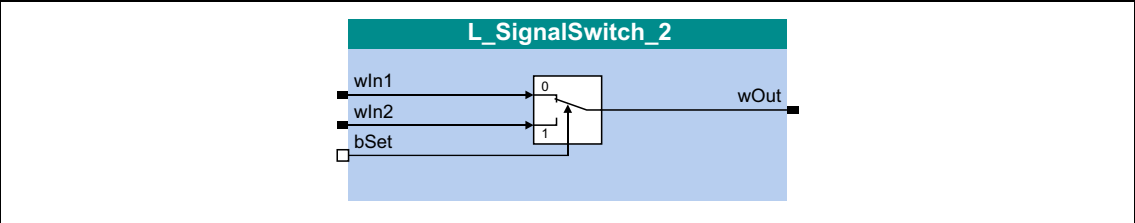
Identifier	Data type	Information/possible settings
wIn1	WORD	Input signal 1
wIn2	WORD	Input signal 2
bSet	BOOL	Selection of the input signal for the output at wOut
		FALSE wIn1
		TRUE wIn2

Outputs

Identifier	Data type	Value/meaning
wOut	WORD	Output signal

19.1.162 L_SignalSwitch_2

This FB switches between two input signals of the "WORD" data type. The switch-over is controlled by means of a boolean input signal.



Inputs

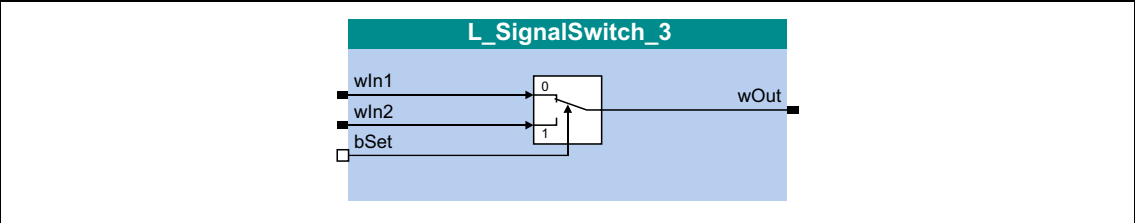
Identifier	Data type	Information/possible settings
wIn1	WORD	Input signal 1
wIn2	WORD	Input signal 2
bSet	BOOL	Selection of the input signal for the output at wOut
		FALSE wIn1
		TRUE wIn2

Outputs

Identifier	Data type	Value/meaning
wOut	WORD	Output signal

19.1.163 L_SignalSwitch_3

This FB switches between two input signals of the "WORD" data type. The switch-over is controlled by means of a boolean input signal.



Inputs

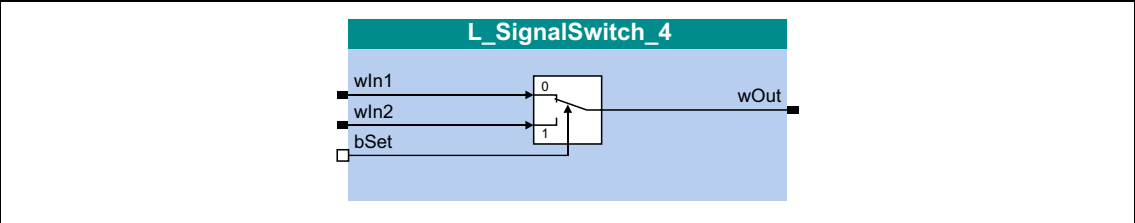
Identifier	Data type	Information/possible settings
wIn1	WORD	Input signal 1
wIn2	WORD	Input signal 2
bSet	BOOL	Selection of the input signal for the output at wOut
		FALSE wIn1
		TRUE wIn2

Outputs

Identifier	Data type	Value/meaning
wOut	WORD	Output signal

19.1.164 L_SignalSwitch_4

This FB switches between two input signals of the "WORD" data type. The switch-over is controlled by means of a boolean input signal.



Inputs

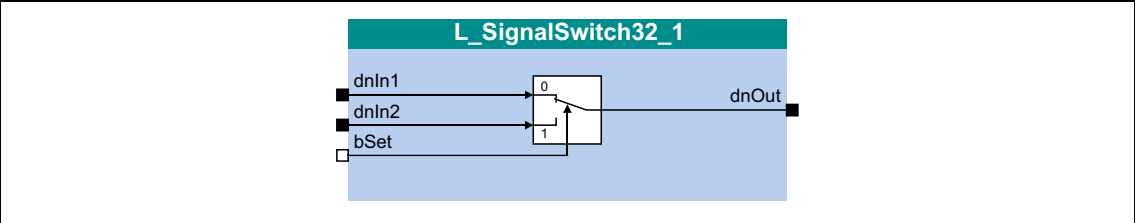
Identifier	Data type	Information/possible settings
wIn1	WORD	Input signal 1
wIn2	WORD	Input signal 2
bSet	BOOL	Selection of the input signal for the output at wOut
		FALSE wIn1
		TRUE wIn2

Outputs

Identifier	Data type	Value/meaning
wOut	WORD	Output signal

19.1.165 L_SignalSwitch32_1

This FB switches between two input signals of the "DINT" data type. The switch-over is controlled by means of a boolean input signal.



Inputs

Identifier	Data type	Information/possible settings
dnIn1	DINT	Input signal 1
dnIn2	DINT	Input signal 2
bSet	BOOL	Selection of the input signal for the output at <i>dnOut</i>
		FALSE <i>dnIn1</i>
		TRUE <i>dnIn2</i>

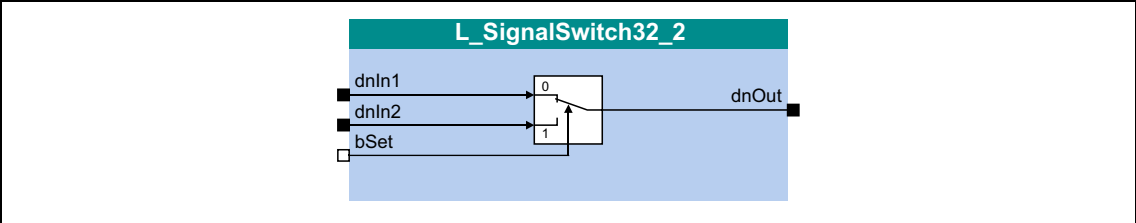
Outputs

Identifier	Data type	Value/meaning
dnOut	DINT	Output signal

19.1.166

L_SignalSwitch32_2

This FB switches between two input signals of the "DINT" data type. The switch-over is controlled by means of a boolean input signal.



Inputs

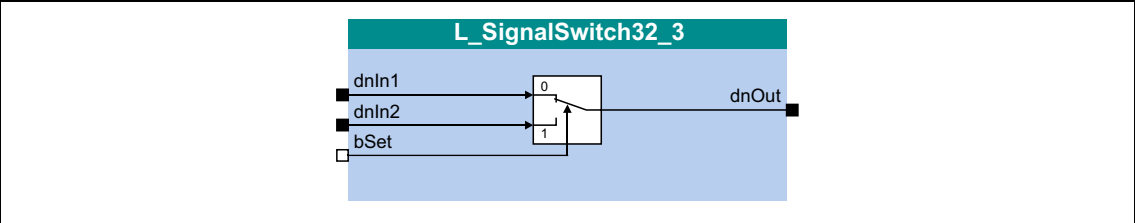
Identifier	Data type	Information/possible settings
dnIn1	DINT	Input signal 1
dnIn2	DINT	Input signal 2
bSet	BOOL	Selection of the input signal for the output at <i>dnOut</i>
		FALSE <i>dnIn1</i>
		TRUE <i>dnIn2</i>

Outputs

Identifier	Data type	Value/meaning
dnOut	DINT	Output signal

19.1.167 L_SignalSwitch32_3

This FB switches between two input signals of the "DINT" data type. The switch-over is controlled by means of a boolean input signal.



Inputs

Identifier	Data type	Information/possible settings
dnIn1	DINT	Input signal 1
dnIn2	DINT	Input signal 2
bSet	BOOL	Selection of the input signal for the output at <i>dnOut</i>
		FALSE <i>dnIn1</i>
		TRUE <i>dnIn2</i>

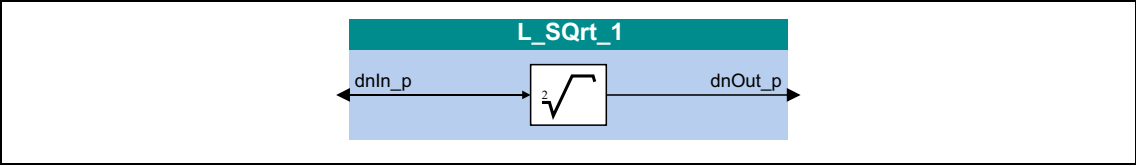
Outputs

Identifier	Data type	Value/meaning
dnOut	DINT	Output signal

19.1.168

L_Sqrt_1

This FB outputs the square root for the DINT input value.



Inputs

Identifier	Data type	Information/possible settings
dnIn_p	DINT	Input signal

Outputs

Identifier	Data type	Value/meaning
dnOut_p	DINT	Output signal

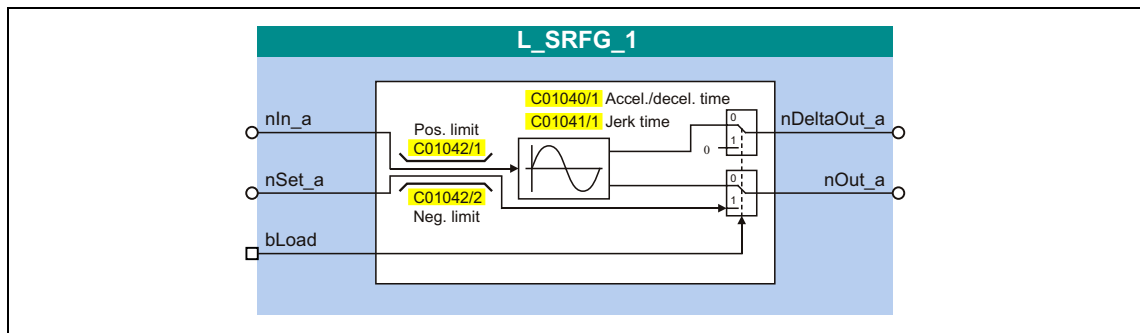
Function

$$\text{dnOut_p} = \sqrt{\text{dnIn_p}}$$

19.1.169 L_SRFG_1

This FB is a ramp function generator with S-shaped ramps for limiting the temporal rise of analog signals. The ramps are S-shaped due to trapezoidal acceleration.

- The ramp function generator is provided with a setting function so that a value can directly be loaded into the internal ramp generator.
- The balanced acceleration/deceleration time is set in [C01040](#).
- An S-ramp time can be set in [C01041](#) for jerk-free acceleration until maximum acceleration is reached.
- At the *nDeltaOut_a* output, the dy/dt slope of the *nOut_a* output signal is output.

**Inputs**

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal
nSet_a	INT	Starting value for the ramp function generator <ul style="list-style-type: none"> • Will be accepted if <i>bLoad</i> = TRUE
bLoad	BOOL	Initialise ramp function generator
		<div>FALSE</div> <div>With the set acceleration/deceleration time, the ramp function generator switches over from the value loaded via <i>nSet_a</i> to the value at <i>nIn_a</i>.</div>
		<div>TRUE</div> <div>At the <i>nOut_a</i> output, <i>nSet_a</i> is output. <ul style="list-style-type: none"> • <i>nDeltaOut_a</i> remains at 0 %. </div>

Outputs

Identifier	Data type	Value/meaning
nDeltaOut_a	INT	Acceleration of the ramp function generator <ul style="list-style-type: none"> • Internal limitation to $\pm 100\%$ ($100\% \equiv 16384$)
nOut_a	INT	Output signal <ul style="list-style-type: none"> • Internal limitation to $\pm 199\%$ ($100\% \equiv 16384$)

Parameter

Parameter	Possible settings			Info
C01040/1	0.001	s	999.999	Acceleration/Deceleration time <ul style="list-style-type: none"> • Initialisation: 100.000 s
C01041/1	0.001	s	50.000	S-ramp time <ul style="list-style-type: none"> • Initialisation: 0.200 s

Parameter	Possible settings			Info
C01042/1	-199.99	s	199.99	Pos. limit • Initialisation: 100.00 %
C01042/2	-199.99	s	199.99	Neg. limit • Initialisation: -100.00 %

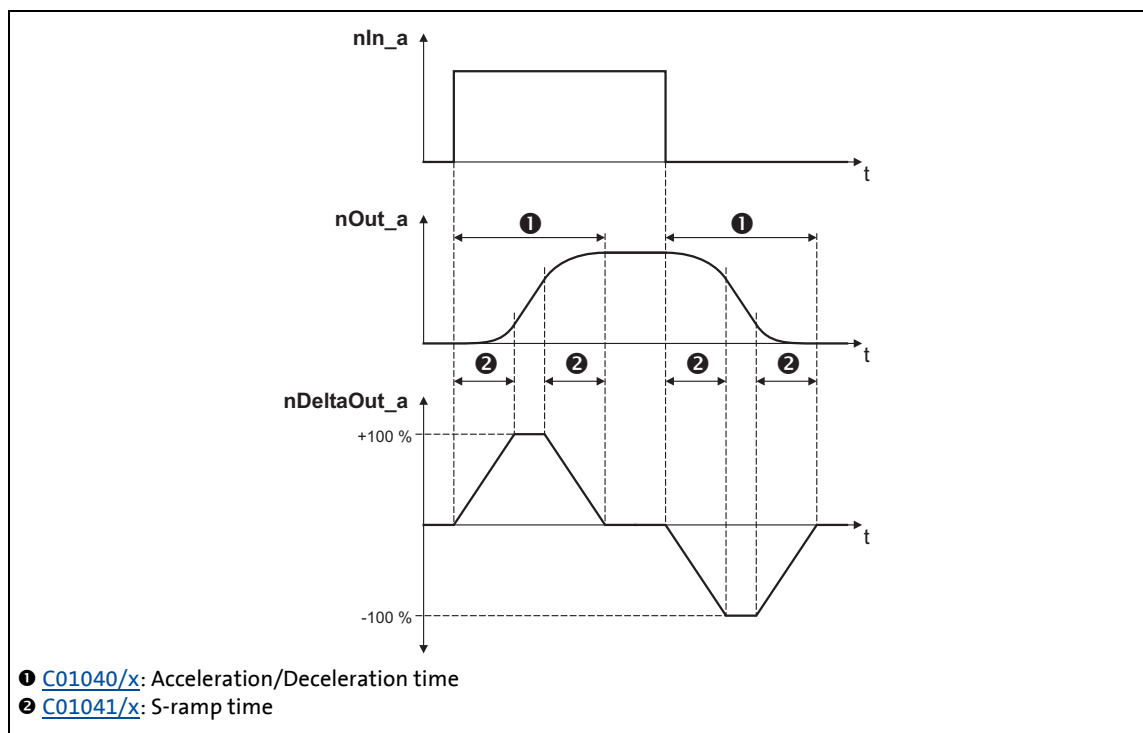
Loading the ramp function generator

When *bLoad* is set to TRUE, the ramp function generator is loaded with the signal at *nSet_a*. This value is accepted immediately and output at *nOut_a*. There is no acceleration or deceleration via an S shape. As long as *bLoad* = TRUE, the ramp function generator remains inhibited.

Acceleration/Deceleration time and S-ramp time

The acceleration/deceleration time and the S-ramp time for jerk-free acceleration can be set separately.

- Acceleration/Deceleration time = Time until the *nOut_a* output value has reached the *nIn_a* input value.
- S-ramp time = Time until the ramp function generator operates at maximum acceleration.

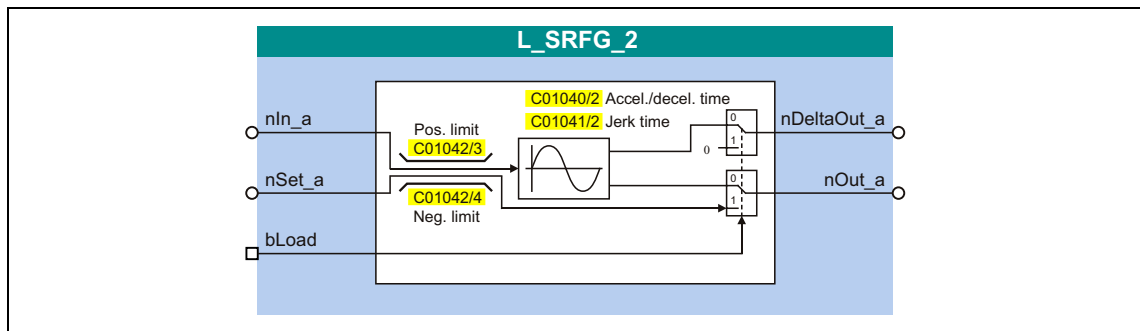


[19-72] Signal flow

19.1.170 L_SRFG_2

This FB is a ramp function generator with S-shaped ramps for limiting the temporal rise of analog signals. The ramps are S-shaped due to trapezoidal acceleration.

- The ramp function generator is provided with a setting function so that a value can directly be loaded into the internal ramp generator.
- The balanced acceleration/deceleration time is set in [C01040](#).
- An S-ramp time can be set in [C01041](#) for jerk-free acceleration until maximum acceleration is reached.
- At the *nDeltaOut_a* output, the dy/dt slope of the *nOut_a* output signal is output.



Inputs

Identifier	Data type	Information/possible settings
nIn_a	INT	Input signal
nSet_a	INT	Starting value for the ramp function generator <ul style="list-style-type: none"> • Will be accepted if <i>bLoad</i> = TRUE
bLoad	BOOL	Initialise ramp function generator
		<div>FALSE</div> <div>With the set acceleration/deceleration time, the ramp function generator switches over from the value loaded via <i>nSet_a</i> to the value at <i>nIn_a</i>.</div> <div>TRUE</div> <div>At the <i>nOut_a</i> output, <i>nSet_a</i> is output. <ul style="list-style-type: none"> • <i>nDeltaOut_a</i> remains at 0 %. </div>

Outputs

Identifier	Data type	Value/meaning
nDeltaOut_a	INT	Acceleration of the ramp function generator <ul style="list-style-type: none"> • Internal limitation to $\pm 100\%$ ($100\% \equiv 16384$)
nOut_a	INT	Output signal <ul style="list-style-type: none"> • Internal limitation to $\pm 199\%$ ($100\% \equiv 16384$)

Parameter

Parameter	Possible settings			Info
C01040/2	0.001	s	999.999	Acceleration/Deceleration time <ul style="list-style-type: none"> • Initialisation: 100.000 s
C01041/2	0.001	s	50.000	S-ramp time <ul style="list-style-type: none"> • Initialisation: 0.200 s

Parameter	Possible settings			Info
C01042/3	-199.99	s	199.99	Pos. limit • Initialisation: 100.00 %
C01042/4	-199.99	s	199.99	Neg. limit • Initialisation: -100.00 %

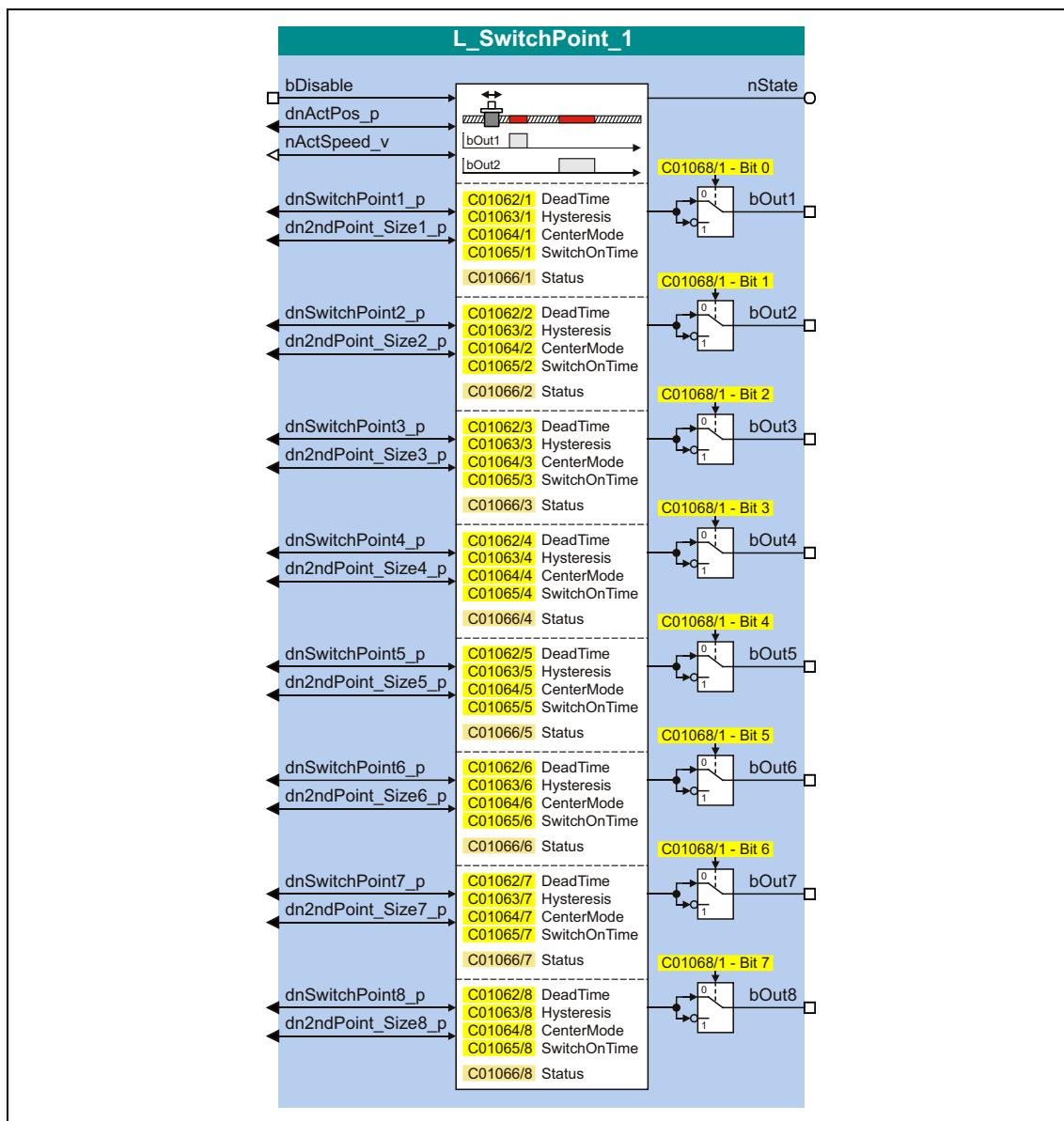


For a detailed functional description see [L_SRFG_1](#).

19.1.171 L_SwitchPoint_1

This FB provides position switch points, i.e. digital switches the binary statuses (FALSE/TRUE) of which depend on the actual position.

- From version 12.00.00, eight instead of four position switch points are available.
- A position switch point serves to start peripherals as paint nozzles or knives depending on the tool position.
- Moreover the FB supports the compensation of delay times of external switching elements (dead time compensation).
- By setting a running time, position/time-based cams can be realised as well.



Inputs

Identifier	Data type	Information/possible settings
bDisable	BOOL	Deactivate position switch points <ul style="list-style-type: none"> This input has the highest priority.
		TRUE Position switch points are deactivated. <ul style="list-style-type: none"> Outputs <i>bOut1</i> ... <i>bOut8</i> = FALSE
dnActPos_p	DINT	Actual position in [increments]
nActSpeed_v	INT	Actual speed in [increments/ms] <ul style="list-style-type: none"> Scaling: 16384 \equiv 15000 rpm
dnSwitchPointx_p	DINT	Position switch point x: Position of the first switching point in [increments]
dn2ndPoint_Sizex_p	DINT	Position switch point x: Position of the second switching point or size of the switching window depending on the CenterMode set in C01064/x :
		When CenterMode = FALSE: Position of the second switching point in [increments] <ul style="list-style-type: none"> <i>dn2ndPoint_Size_p</i> must be higher than <i>dnSwitchPoint_p</i>.
		When CenterMode = TRUE: Size of the switching window in [increments] <ul style="list-style-type: none"> Due to the symmetrical arrangement of the window around the first switching point, uneven values are rounded to even values. Only positive values are permissible.

Outputs

Identifier	Data type	Value/meaning
bOut1 ... bOut8	BOOL	Switching output 1 ... 8
		TRUE The actual position is inside the defined switching window.
nState	INT	Status
		1 FB is not active
		2 OK
		3 The data form resulting from the switching points are not plausible (<i>dnSwitchPoint_p</i> , <i>dn2ndPoint_Size_p</i> , parameterised hysteresis).

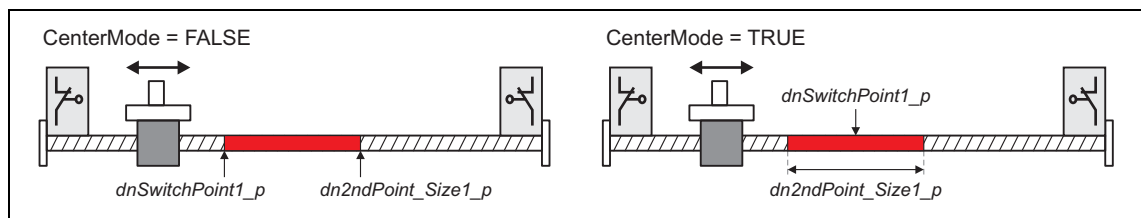
Parameter

Parameter	Possible settings	Info
C01062/1...8	0 μ s 65535	Dead time for dead time compensation <ul style="list-style-type: none"> The resulting switching position is not subject to a plausibility check. Lenze setting: 0 μs
C01063/1...8	0 Incr. 65535	Switching hysteresis <ul style="list-style-type: none"> Lenze setting: 0 incr.
C01064/1...8	False <i>dn2ndPoint_Size_p</i> defines the second switching point. (Lenze setting) True <i>dn2ndPoint_Size_p</i> defines the size of the switching window.	CenterMode <ul style="list-style-type: none"> Definition how the <i>dn2ndPoint_Size_p</i> selection is interpreted.

Parameter	Possible settings	Info
C01065/1...8	0 ms 60000 0 ms = position-based cam	Running time for position/time-based cams • Lenze setting: 0 ms
C01066/1...8	0 OK 10 FB is not active 100 Switching points not plausible	Status 1 ... 4 • Read only.
C01068/1 From version 12.00.00	Setting is bit coded: Bit 0 Inversion of output 1 Bit 1 Inversion of output 2 Bit 2 Inversion of output 3 Bit 3 Inversion of output 4 Bit 4 Inversion of output 5 Bit 5 Inversion of output 6 Bit 6 Inversion of output 7 Bit 7 Inversion of output 8 Bit 8 Reserved ... Bit 15	Inversion of outputs • Lenze setting: 0x0000

19.1.171.1 Definition of the switching range

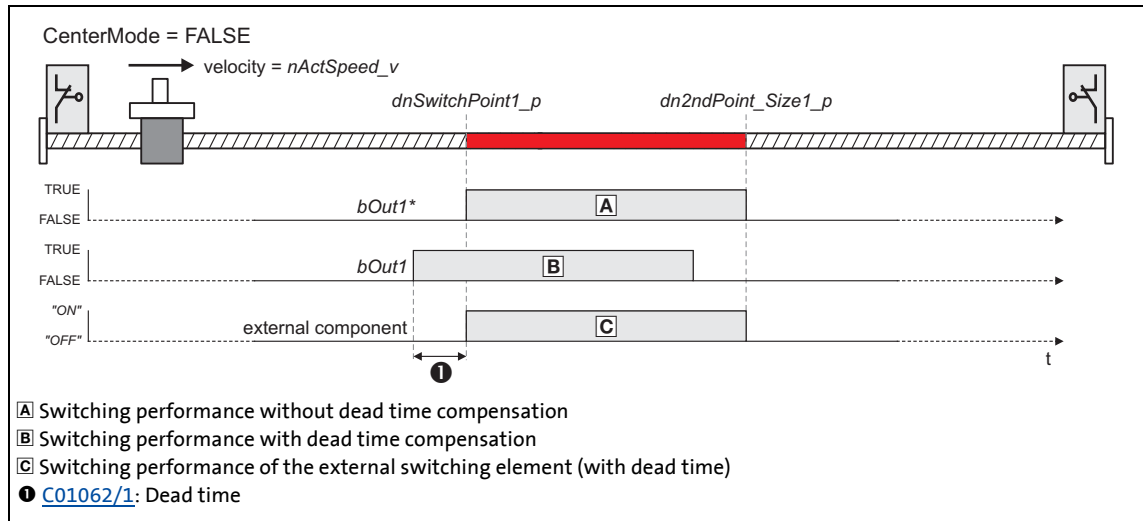
Depending on the setting of the CenterMode ([C01064/x](#)), the switching range can be defined via a start and end position or via the data of the center point/size of switching range:



[19-73] Definition of the switching range

19.1.171.2 Dead time compensation

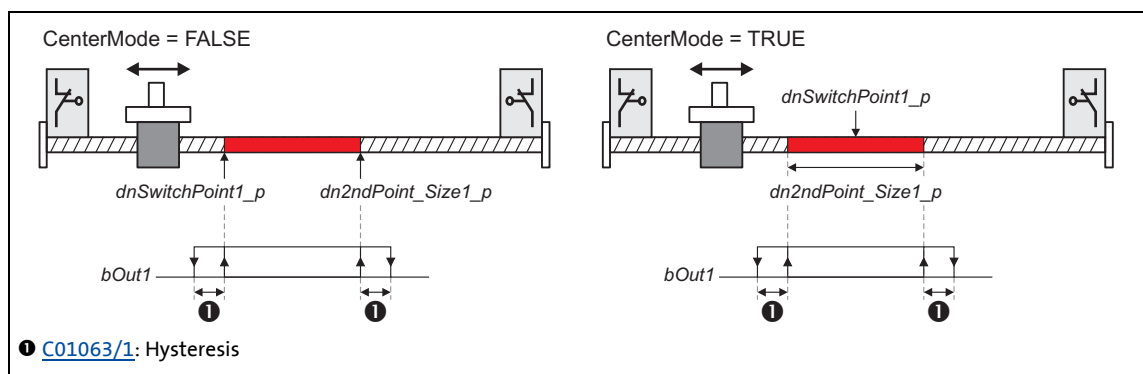
The delay time of external switching elements can be compensated by setting the corresponding delay time in [C01062/x](#). From this input and the current speed, the FB calculates a preliminary stop, i.e. the *bOut* switching output is set correspondingly earlier.



[19-74] Dead time compensation

19.1.171.3 Switching hysteresis

Setting a hysteresis in [C01063/x](#) serves to prevent a permanent state change of the *bOut* switching output that may be caused by actual position value changes due to a mechanical irregularity at the axis.



[19-75] Switching hysteresis

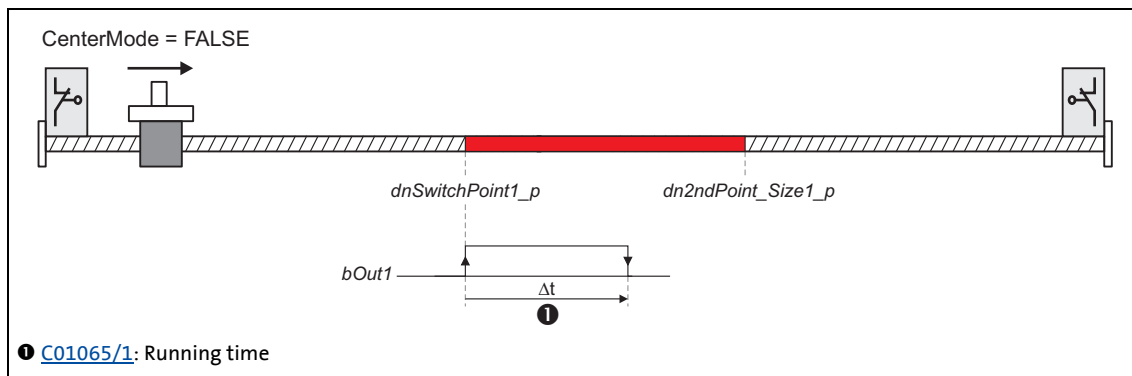


Tip!

Please note that a delay time set in [C01062/x](#) shifts the switching points including the hysteresis.

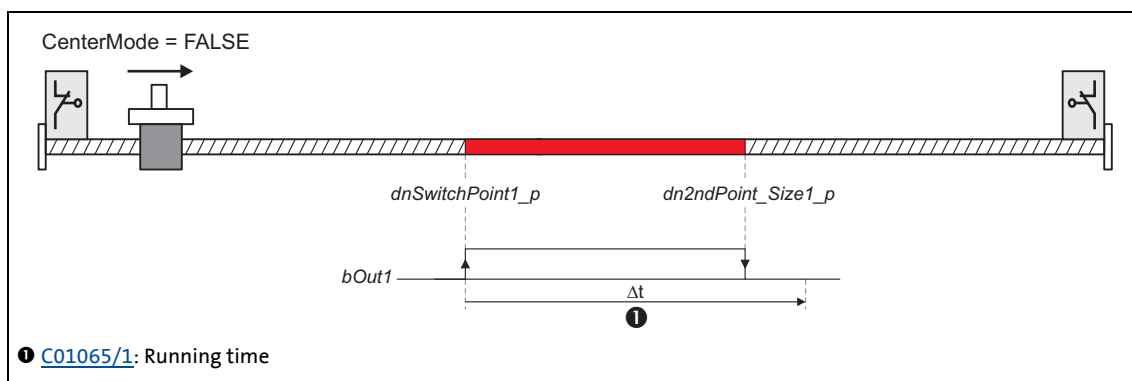
19.1.171.4 Position/time-based cams

The setting of a running time in [C01065/x](#) higher 0 ms serves to realise "position/time-based cams": If the drive reaches the switching range, the *bOut* switching output is set to TRUE and reset to FALSE after the set switching time has elapsed.



[19-76] Position/time-based cams (here without switching hysteresis and dead time compensation)

If the switching range is left before the running time has expired, the *bOut* switching output is reset to FALSE.



[19-77] Position/time-based cams: Behaviour when the switching range is left before the running time has expired



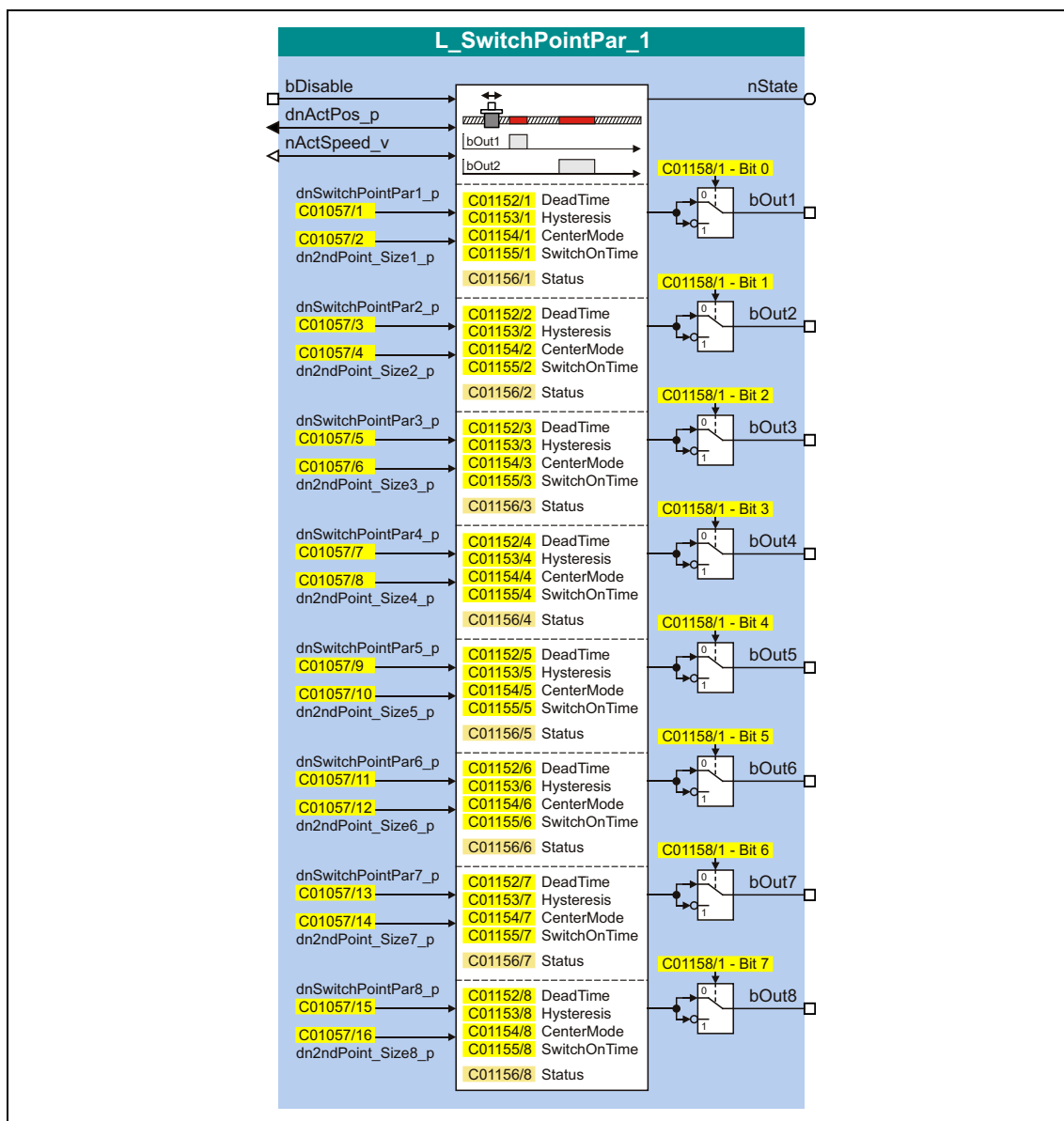
Tip!

Please note that for a resetting of the switching output the switching range must be left first.

19.1.172 L_SwitchPointPar_1

This FB provides position switch points, i.e. digital switches the binary statuses (FALSE/TRUE) of which depend on the actual position.

- This FB has the same function as the FB [L_SwitchPoint 1](#). However, for this FB the position switch point positions must be specified via parameters instead of FB inputs.
- A position switch point serves to start peripherals as paint nozzles or knives depending on the tool position.
- Moreover the FB supports the compensation of delay times of external switching elements (dead time compensation).
- By setting a running time, position/time-based cams can be realised as well.



Inputs

Identifier	Data type	Information/possible settings
bDisable	BOOL	Deactivate position switch points <ul style="list-style-type: none"> This input has the highest priority.
		TRUE Position switch points are deactivated. <ul style="list-style-type: none"> Outputs <i>bOut1</i> ... <i>bOut8</i> = FALSE
dnActPos_p	DINT	Actual position in [increments]
nActSpeed_v	INT	Actual speed in [increments/ms] <ul style="list-style-type: none"> Scaling: 16384 \equiv 15000 rpm

Outputs

Identifier	Data type	Value/meaning
bOut1 ... bOut8	BOOL	Switching output 1 ... 8
		TRUE The actual position is inside the defined switching window.
nState	INT	Status
		1 FB is not active
		2 OK
		3 The data form resulting from the switching points are not plausible (<i>dnSwitchPoint_p</i> , <i>dn2ndPoint_Size_p</i> , parameterised hysteresis).

Parameter

Parameter	Possible settings	Info
C01152/1...8	0 μ s 65535	Dead time for dead time compensation <ul style="list-style-type: none"> The resulting switching position is not subject to a plausibility check. Lenze setting: 0 μs
C01153/1...8	0 Incr. 65535	Switching hysteresis <ul style="list-style-type: none"> Lenze setting: 0 incr.
C01154/1...8	False <i>dn2ndPoint_Size_p</i> defines the second switching point. (Lenze setting) True <i>dn2ndPoint_Size_p</i> defines the size of the switching window.	CenterMode <ul style="list-style-type: none"> Definition how the <i>dn2ndPoint_Size_p</i> selection is interpreted.
C01155/1...8	0 ms 60000 0 ms = position-based cam	Running time for position/time-based cams <ul style="list-style-type: none"> Lenze setting: 0 ms
C01156/1...8	0 OK 10 FB is not active 100 Switching points not plausible	Status 1 ... 4 <ul style="list-style-type: none"> Read only.

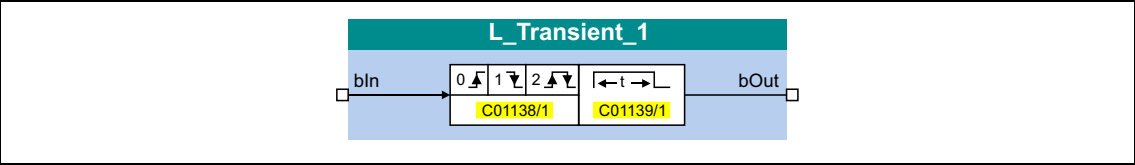
Parameter	Possible settings			Info
C01157/1...16	0.0000	units	214748.0000	Position switch point positions • Lenze setting: 0.0000 units
	dnSwitchPointx_p = position of the first switching point for position switch point x. dn2ndPoint_Size_x_p = position of the second switching point or size of the switching window for position switch point x, depending on the CenterMode set in C01154/x : <ul style="list-style-type: none">• When CenterMode = FALSE: Position of the second switching point<ul style="list-style-type: none">• dn2ndPoint_Size_x_p must be higher than dnSwitchPointx_p.• When CenterMode = TRUE: Size of the switching window<ul style="list-style-type: none">• Due to the symmetrical arrangement of the window around the first switching point, uneven values are rounded to even values.• Only positive values are permissible.			
C01158/1	Setting is bit coded:			Inversion of outputs • Lenze setting: 0x0000
	Bit 0	Inversion of output 1		
	Bit 1	Inversion of output 2		
	Bit 2	Inversion of output 3		
	Bit 3	Inversion of output 4		
	Bit 4	Inversion of output 5		
	Bit 5	Inversion of output 6		
	Bit 6	Inversion of output 7		
	Bit 7	Inversion of output 8		
	Bit 8	Reserved		
	...			
	Bit 15			



For a detailed functional description see [L SwitchPoint 1](#).

19.1.173 L_Transient_1

This FB serves to evaluate digital signal edges and convert them into timed, retriggerable pulses. Rising signal edges, falling signal edges or both signal edges can be evaluated.



Inputs

Identifier	Data type	Information/possible settings
bIn	BOOL	Input for edge evaluation • The function depends on the selection of edge evaluation in C01138/1 .

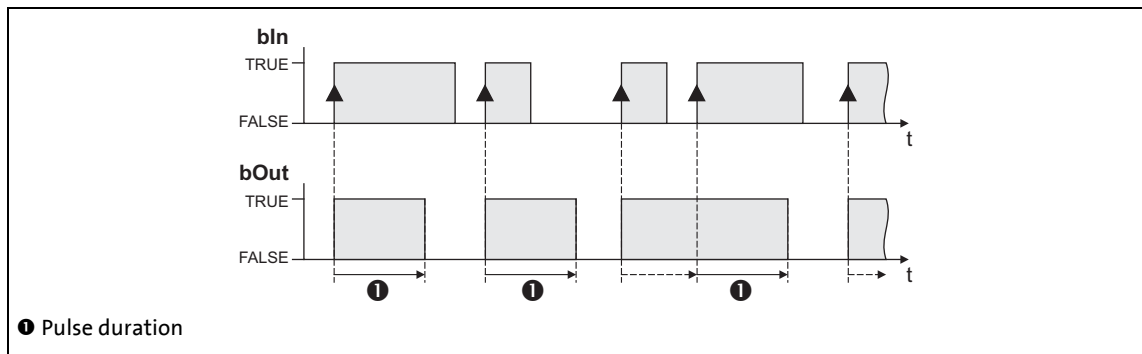
Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output (retriggerable)

Parameter

Parameter	Possible settings			Info
C01138/1				Function • Selection of edge evaluation
	0	High edge		Lenze setting
	1	Low edge		
	2	High and low edge		
C01139/1	0.001	s	60.000	Pulse duration • Lenze setting: 0.001 s

19.1.173.1 Function 0: Evaluate rising signal edges

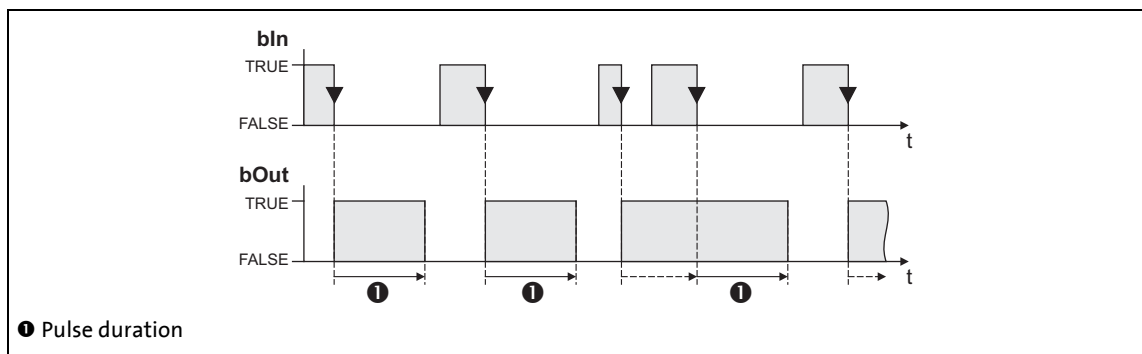


[19-78] Switching performance for function selection "0: High edge"

Functional sequence

1. A FALSE-TRUE edge at the bIn input sets the $bOut$ output to TRUE.
2. After the parameterised pulse duration has elapsed, the $bOut$ output is reset to FALSE unless another FALSE/TRUE edge has been set at the bIn input.
 - If an additional FALSE-TRUE edge occurs at the bIn input, the pulse duration starts again from the beginning, i.e. the $bOut$ output can be retriggered.

19.1.173.2 Function 1: Evaluate falling signal edges

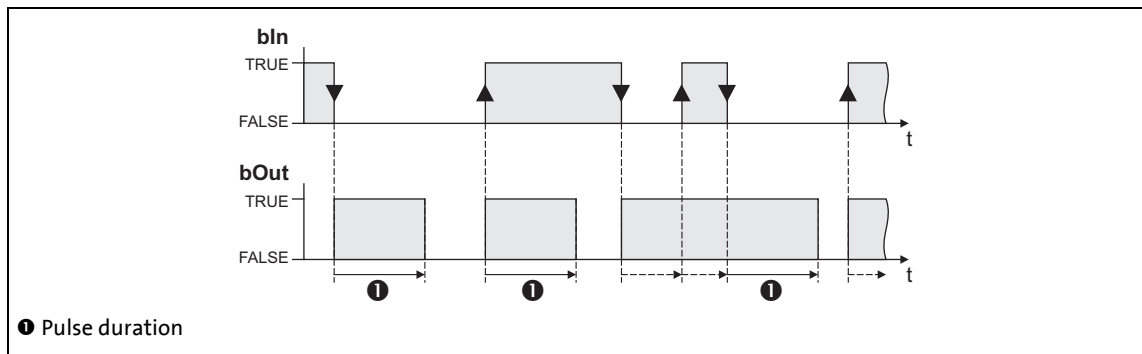


[19-79] Switching performance for function selection "1: Low edge"

Functional sequence

1. A TRUE-FALSE edge at the bIn inputs sets the $bOut$ output to TRUE.
2. After the parameterised pulse duration has elapsed, the $bOut$ output is reset to FALSE unless another TRUE/FALSE edge has been set at the bIn input.
 - If an additional TRUE-FALSE edge occurs at the bIn input, the pulse duration starts again from the beginning, i.e. the $bOut$ output can be retriggered.

19.1.173.3 Function 2: Evaluate rising and falling signal edges



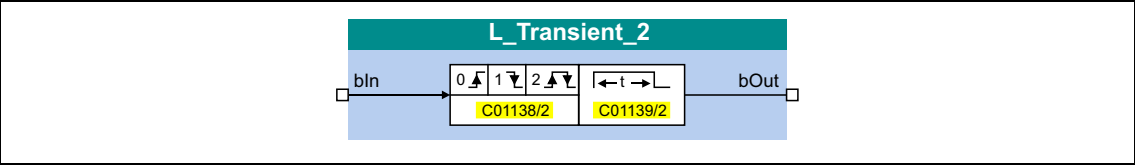
[19-80] Switching performance for function selection "2: High and low edge"

Functional sequence

1. A signal change (FALSE/TRUE edge or TRUE/FALSE edge) at the *bIn* input sets the *bOut* output to TRUE.
2. After the parameterised pulse duration has elapsed, the *bOut* output is reset to FALSE unless another signal change has taken place at the *bIn* input.
 - In case of another signal change at the input *bIn*, the pulse time restarts to elapse, i.e. the output *bOut* can be retriggered.

19.1.174 L_Transient_2

This FB serves to evaluate digital signal edges and convert them into timed, retriggerable pulses. Rising signal edges, falling signal edges or both signal edges can be evaluated.



Inputs

Identifier	Data type	Information/possible settings
bIn	BOOL	Input for edge evaluation • The function depends on the selection of edge evaluation in C01138/2 .

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output (retriggerable)

Parameter

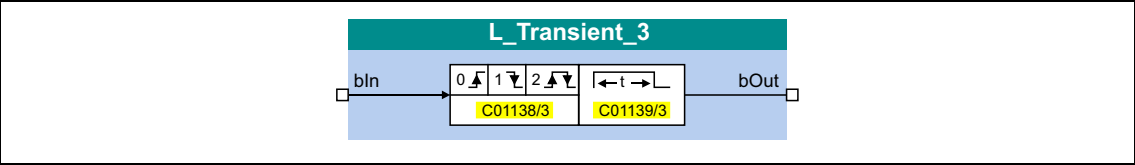
Parameter	Possible settings			Info
C01138/2				Function • Selection of edge evaluation
	0	High edge		Lenze setting
	1	Low edge		
	2	High and low edge		
C01139/2	0.001	s	60.000	Pulse duration • Lenze setting: 0.001 s



For a detailed functional description see [L_Transient_1](#).

19.1.175 L_Transient_3

This FB serves to evaluate digital signal edges and convert them into timed, retriggerable pulses. Rising signal edges, falling signal edges or both signal edges can be evaluated.



Inputs

Identifier	Data type	Information/possible settings
bIn	BOOL	Input for edge evaluation • The function depends on the selection of edge evaluation in C01138/3 .

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output (retriggerable)

Parameter

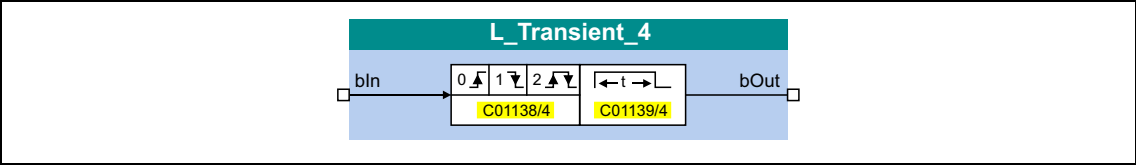
Parameter	Possible settings			Info
C01138/3				Function • Selection of edge evaluation
	0	High edge		Lenze setting
	1	Low edge		
	2	High and low edge		
C01139/3	0.001	s	60.000	Pulse duration • Lenze setting: 0.001 s



For a detailed functional description see [L_Transient_1](#).

19.1.176 L_Transient_4

This FB serves to evaluate digital signal edges and convert them into timed, retriggerable pulses. Rising signal edges, falling signal edges or both signal edges can be evaluated.



Inputs

Identifier	Data type	Information/possible settings
bIn	BOOL	Input for edge evaluation • The function depends on the selection of edge evaluation in C01138/4 .

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output (retriggerable)

Parameter

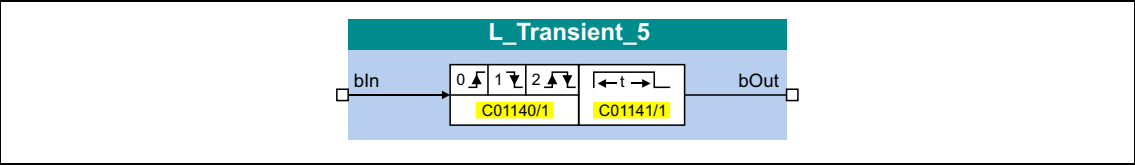
Parameter	Possible settings			Info
C01138/4				Function • Selection of edge evaluation
	0	High edge		Lenze setting
	1	Low edge		
	2	High and low edge		
C01139/4	0.001	s	60.000	Pulse duration • Lenze setting: 0.001 s



For a detailed functional description see [L_Transient_1](#).

19.1.177 L_Transient_5

This FB serves to evaluate digital signal edges and convert them into timed, retriggerable pulses. Rising signal edges, falling signal edges or both signal edges can be evaluated.



Inputs

Identifier	Data type	Information/possible settings
bIn	BOOL	Input for edge evaluation • The function depends on the selection of edge evaluation in C01140/1 .

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output (retriggerable)

Parameter

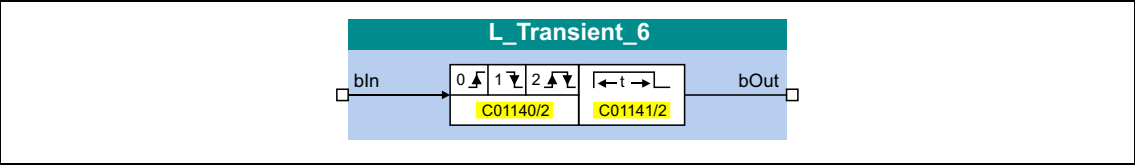
Parameter	Possible settings			Info
C01140/1				Function • Selection of edge evaluation
	0	High edge		Lenze setting
	1	Low edge		
	2	High and low edge		
C01141/1	0.001	s	60.000	Pulse duration • Lenze setting: 0.001 s



For a detailed functional description see [L_Transient_1](#).

19.1.178 L_Transient_6

This FB serves to evaluate digital signal edges and convert them into timed, retriggerable pulses. Rising signal edges, falling signal edges or both signal edges can be evaluated.



Inputs

Identifier	Data type	Information/possible settings
bIn	BOOL	Input for edge evaluation • The function depends on the selection of edge evaluation in C01140/2 .

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output (retriggerable)

Parameter

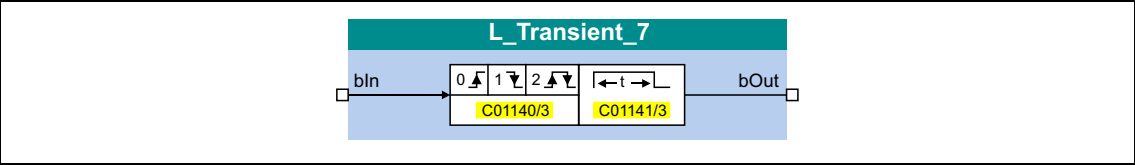
Parameter	Possible settings			Info
C01140/2				Function • Selection of edge evaluation
	0	High edge		Lenze setting
	1	Low edge		
	2	High and low edge		
C01141/2	0.001	s	60.000	Pulse duration • Lenze setting: 0.001 s



For a detailed functional description see [L_Transient_1](#).

19.1.179 L_Transient_7

This FB serves to evaluate digital signal edges and convert them into timed, retriggerable pulses. Rising signal edges, falling signal edges or both signal edges can be evaluated.



Inputs

Identifier	Data type	Information/possible settings
bIn	BOOL	Input for edge evaluation • The function depends on the selection of edge evaluation in C01140/3 .

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output (retriggerable)

Parameter

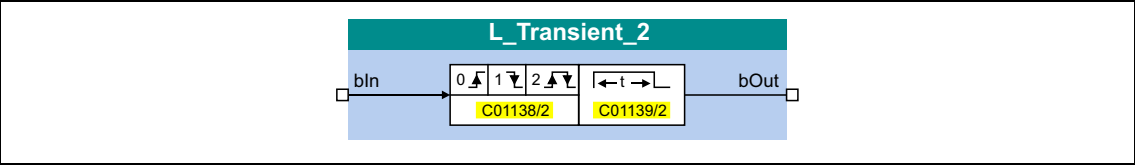
Parameter	Possible settings			Info
C01140/3				Function • Selection of edge evaluation
	0	High edge		Lenze setting
	1	Low edge		
	2	High and low edge		
C01141/3	0.001	s	60.000	Pulse duration • Lenze setting: 0.001 s



For a detailed functional description see [L_Transient_1](#).

19.1.180 L_Transient_8

This FB serves to evaluate digital signal edges and convert them into timed, retriggerable pulses. Rising signal edges, falling signal edges or both signal edges can be evaluated.



Inputs

Identifier	Data type	Information/possible settings
bIn	BOOL	Input for edge evaluation • The function depends on the selection of edge evaluation in C01140/4 .

Outputs

Identifier	Data type	Value/meaning
bOut	BOOL	Output (retriggerable)

Parameter

Parameter	Possible settings			Info
C01140/4				Function • Selection of edge evaluation
	0	High edge		Lenze setting
	1	Low edge		
	2	High and low edge		
C01141/4	0.001	s	60.000	Pulse duration • Lenze setting: 0.001 s



For a detailed functional description see [L_Transient_1](#).

19.2 System blocks

This chapter describes the system blocks which are available for the controller in the FB Editor.



The function blocks are described in the chapter "[Function blocks](#)". (1381)

Overview of system blocks available

System block	Function	can be inserted into level:	
		I/O	Appl.
LS_AnalogInput	Interface to the analog input terminals ▶ Analog terminals (401)	●	
LS_AnalogOutput	Interface to the analog output terminals ▶ Analog terminals (401)	●	
LS_AxisBusAux	Interface to the axis bus ▶ Axis bus (836)	●	●
LS_AxisBusIn		●	●
LS_AxisBusIO		●	●
LS_AxisBusOut		●	●
LS_CANManagement	Control of internal functions of the CAN driver and display of the "Operational" status as well as the node address ▶ System bus "CAN on board" (749)	●	●
LS_DataAccess	<i>Lenze internal only</i>		●
LS_DeviceMonitor	Motor control status signals ▶ Motor control (MCTRL) (134)		●
LS_DFOut	Interface to the digital frequency output (multi-encoder interface X8) • This SB is available from version 12.00.00. ▶ Digital frequency coupling (345)	●	
LS_DigitalInput	Interface to the digital input terminals ▶ Digital input terminals (377)	●	
LS_DigitalOutput	Interface to the digital output terminals ▶ Digital output terminals (398)	●	
LS_DisFree	Display of 8 arbitrary 16-bit signals of the application on display codes	●	●
LS_DisFree_a	Display of 8 arbitrary analog signals of the application on display codes	●	●
LS_DisFree_b	Display of 16 arbitrary digital signals of the application on a bit coded display code	●	●
LS_DisFree_p	Display of 8 arbitrary position signals of the application on display codes	●	●
LS_DriveInterface	Interface to drive control (DCTRL) ▶ Device control (DCTRL) (99)		●
LS_Keypad	Control via keypad	●	
LS_MotionControlKernel	Interface to the basic drive function implemented in the Motion Control Kernel (MCK) ▶ Basic drive functions (MCK) (552)		●
LS_MotorInterface	Interface to motor control (MCTRL) ▶ Motor control (MCTRL) (134)		●
LS_MultiEncoder	Interface to the Multi-Encoder ▶ Multi-Encoder (X8) (325)	●	●

System block	Function	can be inserted into level:	
		I/O	Appl.
LS_ParFix LS_ParFix_2	Output of frequently used constants (TRUE, FALSE, 100 %, etc.) to be used in the interconnection • LS_ParFix_2 is available from version 02.00.00.	●	●
LS_ParFree LS_ParFree_2	Output of 32 parameterisable 16-bit signals • LS_ParFree_2 is available from version 02.00.00.	●	●
LS_ParFree_a LS_ParFree_a_2	Output of 16 parameterisable analog signals • LS_ParFree_a_2 is available from version 02.00.00.	●	●
LS_ParFree_b	Output of 32 parameterisable digital signals	●	●
LS_ParFree_p	Output of 8 parameterisable position signals	●	●
LS_ParFree_v LS_ParFree_v_2	Output of 8 parameterisable speed signals • LS_ParFree_v_2 is available from version 02.00.00.	●	●
LS_ParFree32	Output of 8 parameterisable 32-bit signals • This SB is available from version 02.00.00.	●	●
LS_ParFreeUnit LS_ParFreeUnit_2	Output of 16 parameterisable position signals with internal conversion of [unit] in [increments] • These SBs are available from version 02.00.00.	●	●
LS_ParReadWrite_1 ... LS_ParReadWrite_6	Reading/Writing of local parameters	●	●
LS_PulseGenerator	Output of 9 fixed frequencies and 1 parameterisable frequency	●	●
LS_Resolver	Interface to the resolver ▶ Resolver (X7) (□ 319)	●	●
LS_RetainData	Selection and saving of retain data • This SB is available from version 02.00.00.	●	●
LS_SetError_1	Parameterisable responses to user-defined events are tripped ▶ Diagnostics & error management (□ 673)	●	●
LS_SetError_2		●	●
LS_SyncManagement	Output of status information for synchronising the internal time base ▶ Synchronisation of the internal time base (□ 857)	●	●
LS_TouchProbe	Interface for touch probe detection ▶ Touch probe detection (□ 411)	●	●
LS_WriteParamList	Interface to the basic "Parameter change-over" function ▶ Parameter change-over (□ 859)	●	

Related topics:

- ▶ [Overview of function blocks available](#) (□ 1381)
- ▶ [Working with the FB Editor](#) (□ 1329)

19.2.1 LS_AnalogInput

Interface to the analog input terminals.



For a detailed description see the main chapter "I/O terminals":

► [Internal interfaces | System block "LS_AnalogInput"](#) (📖 409)

19.2.2 LS_AnalogOutput

Interface to the analog output terminals.



For a detailed description see the main chapter "I/O terminals":

► [Internal interfaces | System block "LS_AnalogInput"](#) (📖 409)

19.2.3 LS_AxisBusAux

Interface to the axis bus.



For a detailed description see main chapter "Axis bus":

► [Internal interfaces | System block "LS_AxisBusAux"](#) (📖 849)

19.2.4 LS_AxisBusIn

Interface to the axis bus.



For a detailed description see main chapter "Axis bus":

► [Internal interfaces | System block "LS_AxisBusIn"](#) (📖 848)

19.2.5 LS_AxisBusIO

Interface to the axis bus.



For a detailed description see main chapter "Axis bus":

► [Internal interfaces | System block "LS_AxisBusIO"](#) (📖 856)

19.2.6 LS_AxisBusOut

Interface to the axis bus.



For a detailed description see main chapter "Axis bus":

► [Internal interfaces | System block "LS_AxisBusOut"](#) (📖 847)

19.2.7 LS_CANManagement

Control of internal functions of the CAN driver and display of the "Operational" status as well as the node address.



For a detailed description see the main chapter "System bus CAN on board":

► [Internal interfaces | System block "LS_CANManagement"](#) (📖 828)

19.2.8 LS_DataAccess

Only for Lenze-internal use.

19.2.9 LS_DeviceMonitor

Motor control status signals.



For a detailed description see the main chapter "Motor control (MCTRL)":

► [Internal status signals | System block "LS_DeviceMonitor"](#) (📖 311)

19.2.10 LS_DFOut

Interface to the digital frequency output (multi-encoder interface X8).




For a detailed description see main chapter "Encoder-/feedback system":

► [Internal interfaces | System block "LS_DFOut"](#) (📖 348)

19.2.11 LS_DigitalInput


Interface to the digital input terminals.



For a detailed description see the main chapter "I/O terminals":
▶ [Internal interfaces | System block "LS_DigitalInput"](#) (📖 390)

19.2.12 LS_DigitalOutput

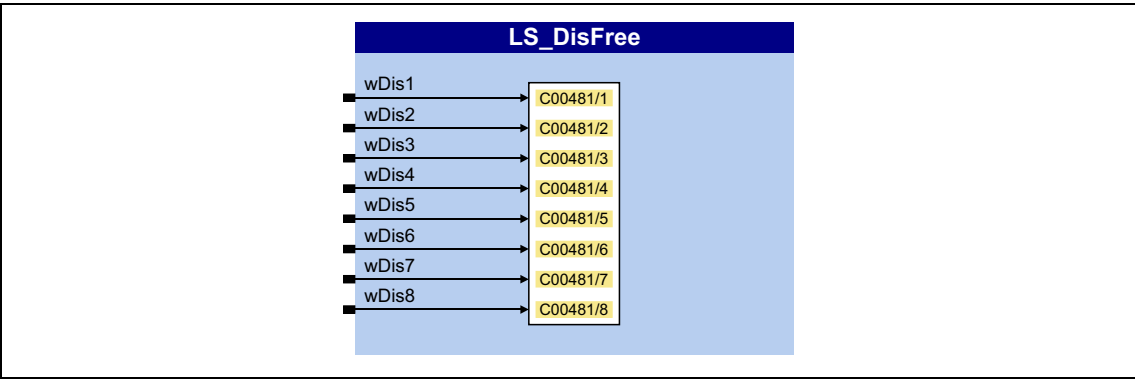
Interface to the digital output terminals.



For a detailed description see the main chapter "I/O terminals":
▶ [Internal interfaces | System block "LS_DigitalOutput"](#) (📖 400)

19.2.13 LS_DisFree

This system block displays 8 arbitrary 16-bit signals of the application on display codes.



Inputs

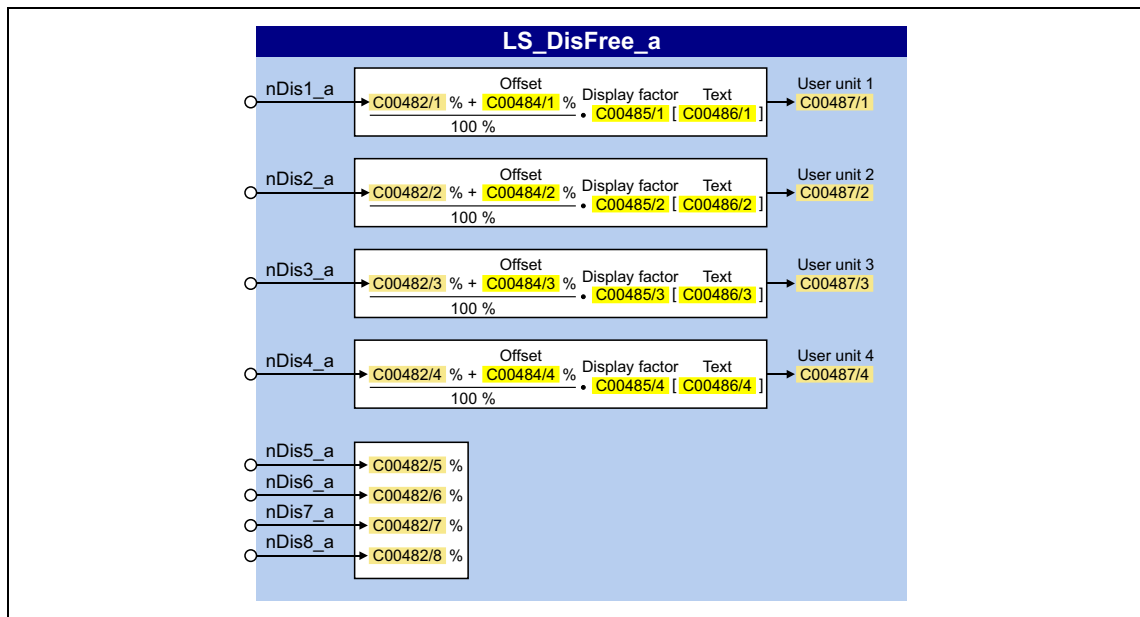
Identifier	Information/possible settings
<div>From version 02.00.00: wC481_1 ... wC481_8_a</div> <div>WORD</div>	Inputs for any 16-bit signals of the application Note: From version 02.00.00 the inputs are named according to the display parameter for an easier allocation.

Parameter

Parameter	Possible settings	Info
C00481/1...8	0x0000	0xFFFF Display of the 16-bit signals which are applied at the wDis1 ... wDis8 inputs

19.2.14 LS_DisFree_a

This system block displays 8 arbitrary analog signals of the application on display codes.



Inputs

Identifier	Information/possible settings
nDis1_a ... nDis8_a <small>From version 02.00.00:</small> nC482_1_a ... nC482_8_a	Inputs for arbitrary analog signals of the application Note: From version 02.00.00 the inputs are named according to the display parameter for an easier allocation.

Parameter

Parameter	Possible settings	Info
C00482/1...8	-199.99 % 199.99	Display of the analog signals which are applied at the nDis1_a ... nDis8_a inputs
C00484/1...4 ... C00487/1...4	► Display of internal process variables in application units	

19.2.14.1 Display of internal process variables in application units

In addition to the display in percent in [C00482/1...8](#), for the first four analog signals $nDis1_a$... $nDis4_a$ the configurable display parameters [C00487/1...4](#) are provided. Via these display parameters, internal process variables can be displayed, e.g. on the keypad, with an individual scaling and an individual unit (from keypad version 02.01).

Configuration of the display parameters ([C00487/1...4](#)):

Parameter	Possible settings			Info
C00484/1...4	-199.99	%	199.99	Offset 1 ... 4 • See formula [19-81] . • Lenze setting: 0.00 %
C00485/1...4	-65536.0000		65536.0000	Display factor 1 ... 4 • Scaling of the input variable for the display. • See formula [19-81] . • Lenze setting: 1.0000
C00486/1...4	String of digits (max. 7 digits)			Text 1 ... 4 • For each display value, an individual unit (e.g. "parts") can be set.

$$\text{User unit 1} = \frac{nDis1_a [\%] + \text{Offset 1} [\%]}{100 [\%]} \cdot \text{Display factor 1 [text 1]}$$

[19-81] Formula for scaling the display

Example 1:

- Input variable $nDis1_a$ = 100 %
- Offset 1 ([C00484/1](#)) = 0 %
- Display factor 1 ([C00485/1](#)) = 123.45
- Text 1 ([C00486/1](#)) = "parts"

$$\text{User unit 1} = \frac{100 [\%] + 0 [\%]}{100 [\%]} \cdot 123.45 [\text{parts}] = 123.45 \text{ parts}$$

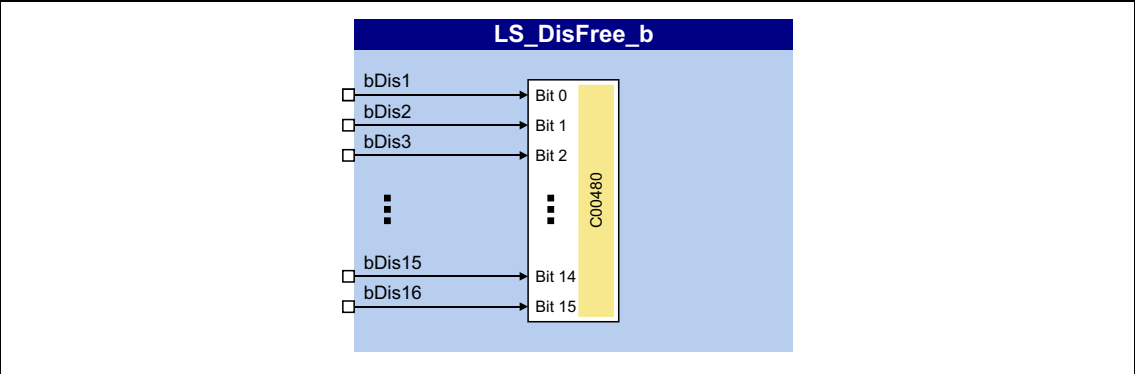
Example 2:

- Input variable $nDis2_a$ = 40 %
- Offset 2 ([C00484/2](#)) = 35 %
- Display factor 2 ([C00485/2](#)) = 20
- Text 2 ([C00486/2](#)) = "kg"

$$\text{User unit 2} = \frac{40 [\%] + 35 [\%]}{100 [\%]} \cdot 20 [\text{kg}] = 15.00 \text{ kg}$$

19.2.15 LS_DisFree_b

This system block displays 16 arbitrary digital signals of the application on a bit coded display code.



Inputs

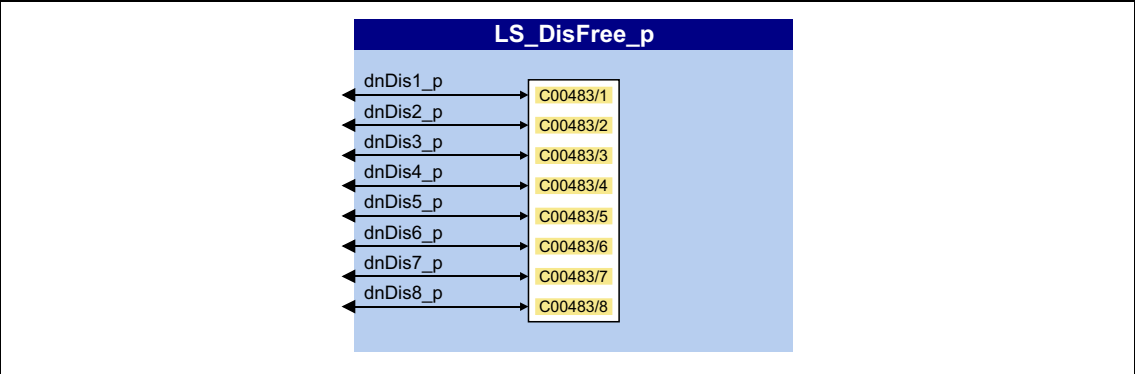
Identifier	Data type	Information/possible settings
bDis1 ... bDis16	BOOL	Inputs for arbitrary digital signals of the application
From version 02.00.00: bC480_B0 ... bC480_B16		Note: From version 02.00.00 the inputs are named according to the display parameter for an easier allocation.

Parameter

Parameter	Possible settings	Info
C00480	0x0000	Display of the digital signals as hexadecimal values which are applied at the <i>bDis1</i> ... <i>bDis16</i> inputs
	Bit 0	
	Bit 1	
	Bit 2	
	...	
	Bit 15	

19.2.16 LS_DisFree_p

This system block displays 8 arbitrary position signals of the application on display codes.



Inputs


Identifier	Data type	Information/possible settings
dnDis1_p ... dnDis8_p	DINT	Inputs for arbitrary position signals of the application
From version 02.00.00: dnC483_1_p ... dnC483_8_p		Note: From version 02.00.00 the inputs are named according to the display parameter for an easier allocation.

Parameter


Parameter	Possible settings	Info
C00483/1...8	-2147483647 Incr. 2147483647	Display of the position signals which are applied at the <i>dnDis1_p ... dnDis8_p</i> inputs

19.2.17 LS_DriveInterface

Interface to internal device control.



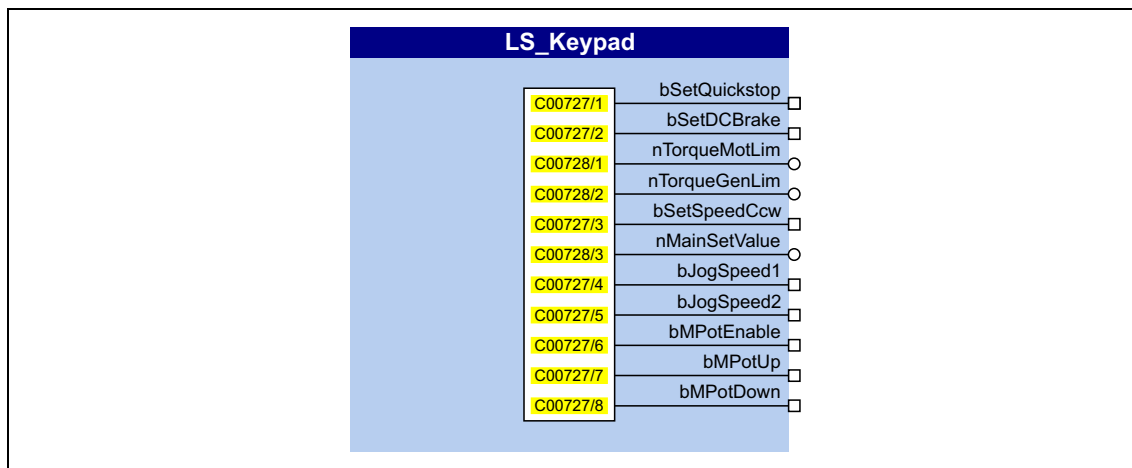
For a detailed description see main chapter "Device control (DCTRL)":

▶ [Internal interfaces | "LS_DriveInterface" system block](#)  127

19.2.18 LS_Keypad

This system block is used on I/O interconnection level if the "Keypad" control mode has been selected in [C00007](#).

In the "Keypad" control mode, the **LS_Keypad** system block passes on various setpoints and control commands to the technology application which can be selected/activated via codes using the keypad.



Outputs

Identifier	Data type	Value/meaning
bSetQuickstop	BOOL	C00727/1 = "1" ≡ Request quick stop
bSetDCBrake	BOOL	C00727/2 = "1" ≡ Request DC-injection braking
nTorqueMotLim	INT	Torque limit in motor mode set in C00728/1 • Lenze setting: 100.00 %
nTorqueGenLim	INT	Torque limit in generator mode set in C00728/2 • Lenze setting: 100.00 %
bSetSpeedCcw	BOOL	C00727/3 = "1" ≡ Request reversal
nMainSetValue	INT	Setpoint speed set in C00728/3 • Lenze setting: 0.00 %
bJogSpeed1	BOOL	C00727/4 = "1" ≡ Request fixed speed setpoint 1
bJogSpeed2	BOOL	C00727/5 = "1" ≡ Request fixed speed setpoint 2
bMPotEnable	BOOL	C00727/6 = "1" ≡ Motor potentiometer: Request activation
bMPotUp	BOOL	C00727/7 = "1" ≡ Motor potentiometer: Request positive acceleration
bMPotDown	BOOL	C00727/8 = "1" ≡ Motor potentiometer: Request negative acceleration

Parameter

Parameter	Possible settings			Info
C00727/1...8	0		1	Keypad digital values <ul style="list-style-type: none"> • Execution of control commands for keypad operation • See the "Outputs" table for the meaning of the individual subcodes
C00728/1...3	-199.99	%	199.99	Analog values - keypad <ul style="list-style-type: none"> • Selection of various setpoints for operation via keypad • See the "Outputs" table for the meaning of the individual subcodes

19.2.19 LS_MotionControlKernel

Interface to the basic drive functions implemented in **Motion Control Kernel** (MCK).



For a detailed description see the main chapter "Basic drive functions":

► [Internal interfaces | System block "LS_MotionControlKernel"](#) (📖 554)

19.2.20 LS_MotorInterface

Interface to internal motor control.



For a detailed description see the main chapter "Motor control (MCTRL)":

► [Internal interfaces | System block "LS_MotorInterface"](#) (📖 305)

19.2.21 LS_MultiEncoder

Interface to the Multi-Encoder.



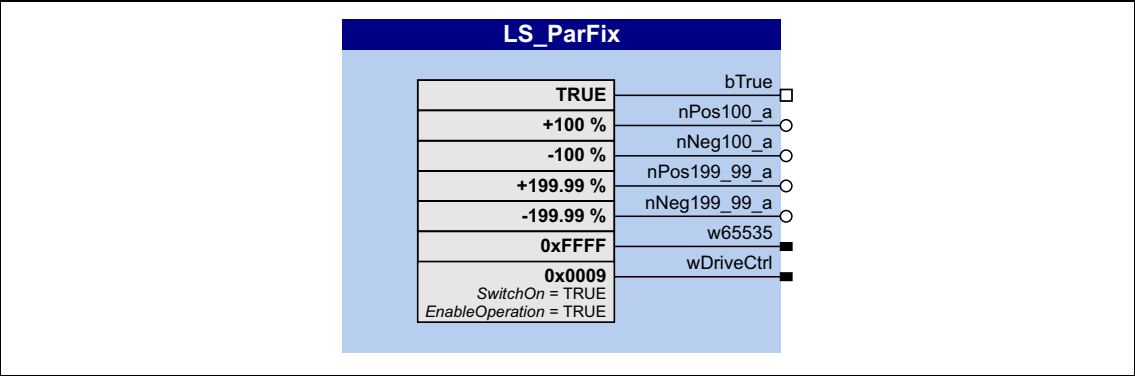
For detailed information please see the main chapter "Encoder/Feedback system":

► [Internal interfaces | System block "LS_MultiEncoder"](#) (📖 349)

19.2.22 LS_ParFix

This system block outputs various fixed values (constants) to be used in the interconnection.

- From version 02.00.00, another LS_ParFix_2 system block is available which can be used e.g. in the application level.

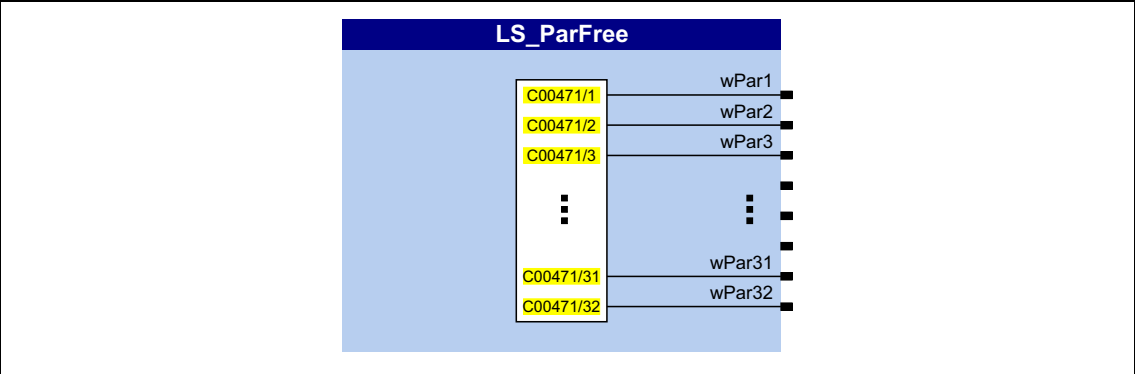


Outputs

Identifier	Data type	Value/meaning
bTrue	BOOL	1 ≡ TRUE
nPos100_a	INT	16384 ≡ + 100 %
nNeg100_a	INT	-16384 ≡ - 100 %
nPos199_99_a	INT	32767 ≡ + 199.99 %
nNeg199_99_a	INT	-32767 ≡ - 199.99 %
w65535	WORD	65535 ≡ 0xFFFF
wDriveCtrl	WORD	9 ≡ 0x0009 <ul style="list-style-type: none">• Bit 0, SwitchOn = TRUE• Bit 3, EnableOperation = TRUE• All others: FALSE See also: ▶ wCANControl/wMCIControl control words (130)

19.2.23 LS_ParFree

This system block outputs 32 parameterisable 16-bit signals.



Outputs

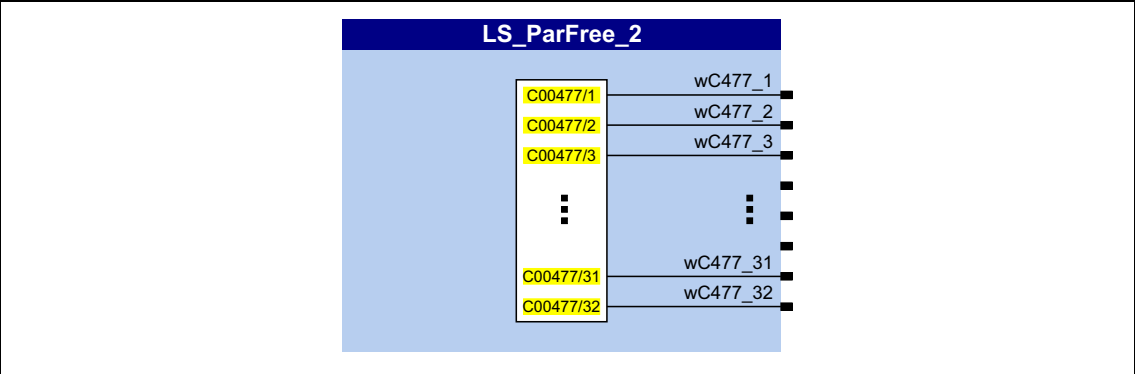
Identifier	Data type	Value/meaning
wPar1 ... wPar32	WORD	Output of the 16-bit signals parameterised in C00471/1...32
From version 02.00.00: wC471_1 ... wC471_32		Note: From version 02.00.00 the outputs are named according to the respective setting parameter for an easier allocation.

Parameter

Parameter	Possible settings			Info
C00471/1...32	0x0000		0xFFFF	Setting of the 16-bit signals to be output

19.2.24 LS_ParFree_2

This system block outputs 32 parameterisable 16-bit signals.



Outputs

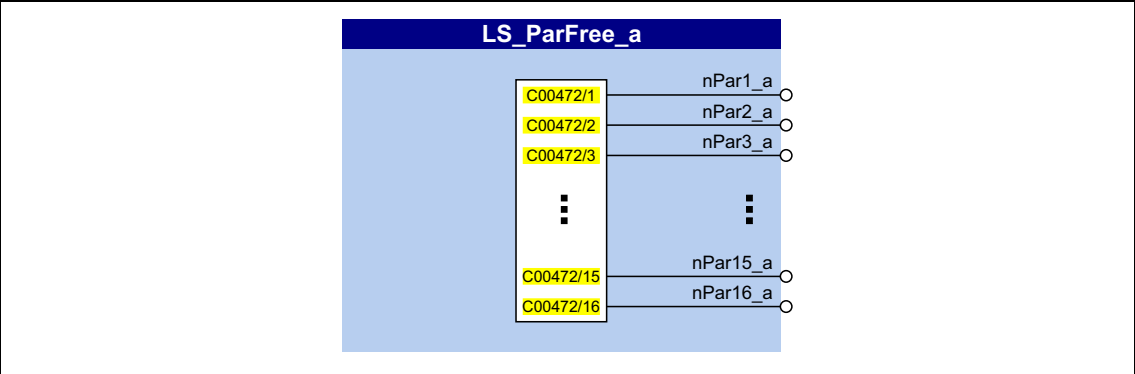
Identifier	Data type	Value/meaning
wC477_1 ... wC477_32	WORD	Output of the 16-bit signals parameterised in C00477/1...32

Parameter

Parameter	Possible settings			Info
C00477/1...32	0x0000		0xFFFF	Setting of the 16-bit signals to be output

19.2.25 LS_ParFree_a

This system block outputs 16 parameterisable analog signals.



Outputs

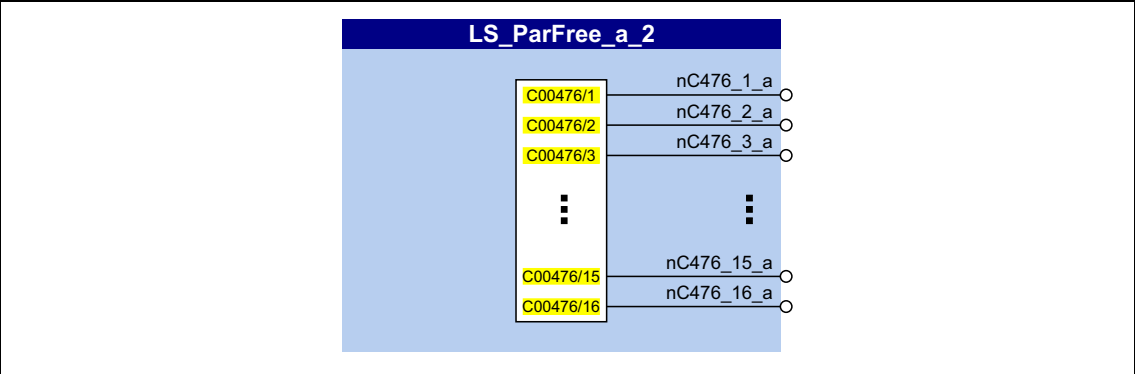
Identifier	Data type	Value/meaning
nPar1_a ... nPar16_a	INT	Output of the analog signals parameterised in C00472/1...16
From version 02.00.00: nC472_1_a ... nC472_16_a		Note: From version 02.00.00 the outputs are named according to the respective setting parameter for an easier allocation.

Parameter

Parameter	Possible settings			Info
C00472/1...16	-199.99	%	+199.99	Selection of analog signals to be output

19.2.26 LS_ParFree_a_2

This system block outputs 16 parameterisable analog signals.



Outputs

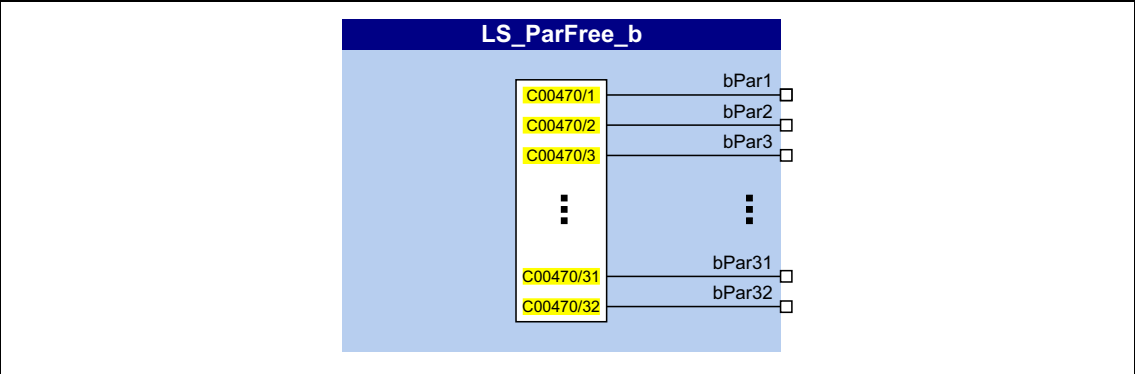
Identifier	Data type	Value/meaning
nC476_1_a ... nC476_16_a	INT	Output of the analog signals parameterised in C00476/1...16

Parameter

Parameter	Possible settings			Info
C00476/1...16	-199.99	%	+199.99	Selection of analog signals to be output

19.2.27 LS_ParFree_b

This system block outputs 32 parameterisable digital signals.



Outputs

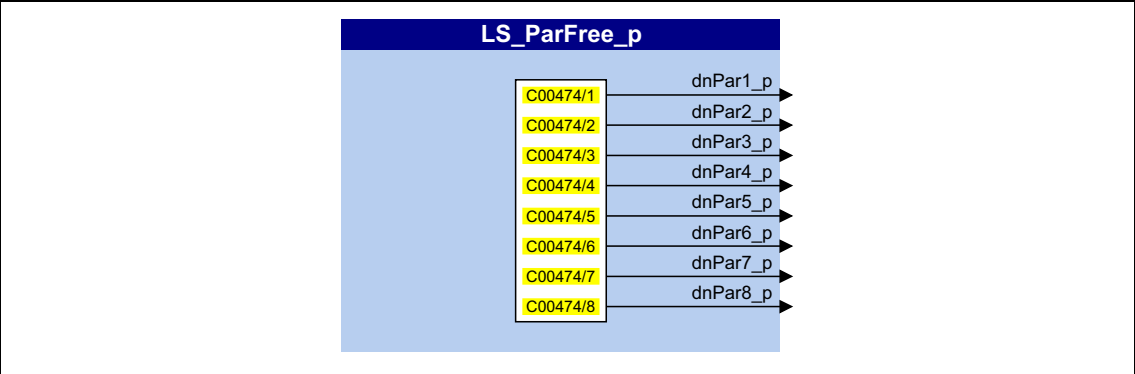
Identifier	Data type	Value/meaning
bPar1 ... bPar32 <small>From version 02.00.00: bC470_1 ... bC470_32</small>	BOOL	Output of the signal levels (FALSE/TRUE) parameterised in C00470/1...32 Note: From version 02.00.00 the outputs are named according to the respective setting parameter for an easier allocation.

Parameter

Parameter	Possible settings	Info
C00470/1...32		Selection of signal levels to be output • Bit 0 ... 31 = <i>bPar1</i> ... <i>bPar32</i>
	0 "FALSE" signal is output	
	1 "TRUE" signal is output	

19.2.28 LS_ParFree_p

This system block outputs 8 parameterisable position signals.



Outputs

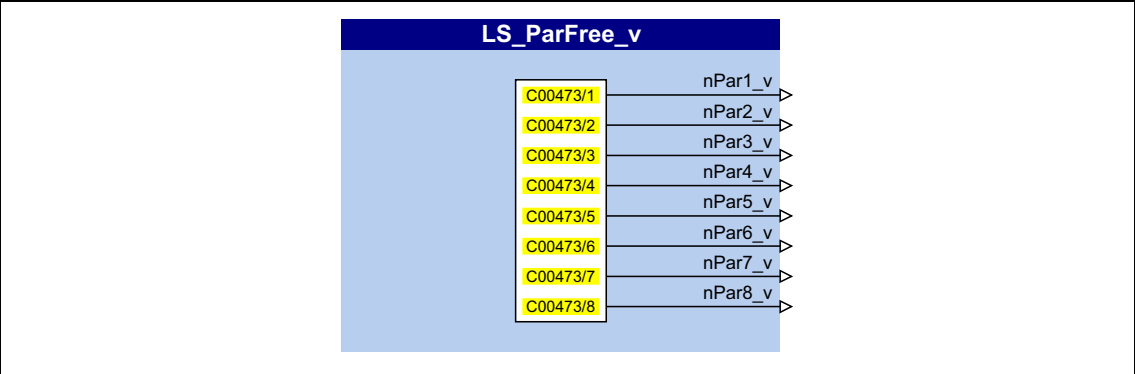
Identifier	Data type	Value/meaning
dnPar1_p ... dnPar8_p	DINT	Output of the position signals parameterised in C00474/1...8
From version 02.00.00: dnC474_1_p ... dnC474_8_p		Note: From version 02.00.00 the outputs are named according to the respective setting parameter for an easier allocation.

Parameter

Parameter	Possible settings			Info
C00474/1...8	-2147483647	Incr.	2147483647	Setting of the position signals to be output

19.2.29 LS_ParFree_v

This system block outputs 8 parameterisable speed signals.



Outputs

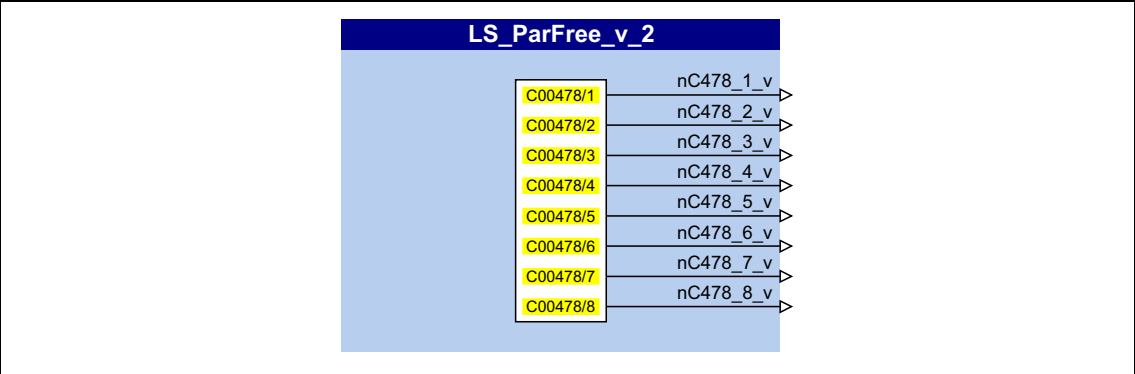
Identifier	Data type	Information/possible settings
nPar1_v ... nPar8_v	INT	Output of the speed signals parameterised in C00473/1...8
From version 02.00.00: nC473_1_v ... nC473_8_v		Note: From version 02.00.00 the outputs are named according to the respective setting parameter for an easier allocation.

Parameter

Parameter	Possible settings			Info
C00473/1...8	-32767	Incr/ms	+32767	Selection of speed signals to be output

19.2.30 LS_ParFree_v_2

This system block outputs 8 parameterisable speed signals.



Outputs

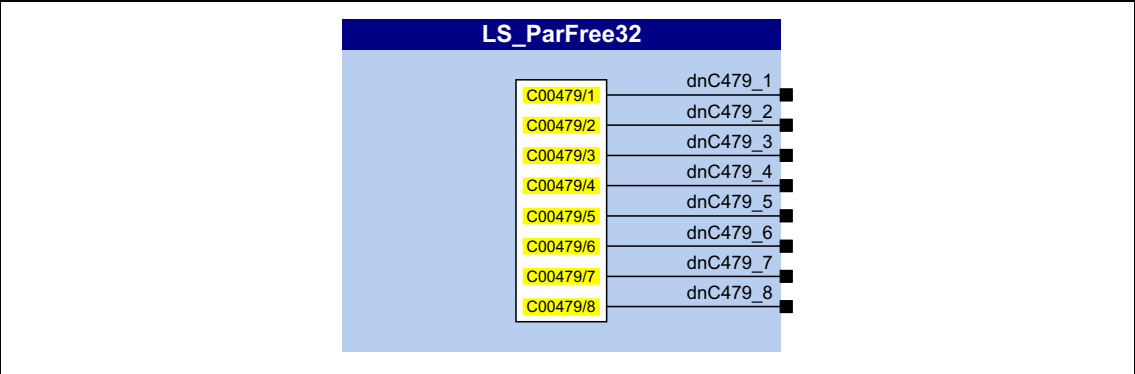
Identifier	Data type	Information/possible settings
nC478_1_v ... nC478_8_v	INT	Output of the speed signals parameterised in C00478/1...8

Parameter

Parameter	Possible settings			Info
C00478/1...8	-32767	Incr/ms	+32767	Selection of speed signals to be output

19.2.31 LS_ParFree32

This system block outputs 8 parameterisable 32-bit signals.



Outputs

Identifier	Data type	Value/meaning
dnC479_1 ... dnC479_8	DINT	Output of the 32-bit signals parameterised in C00479/1...8

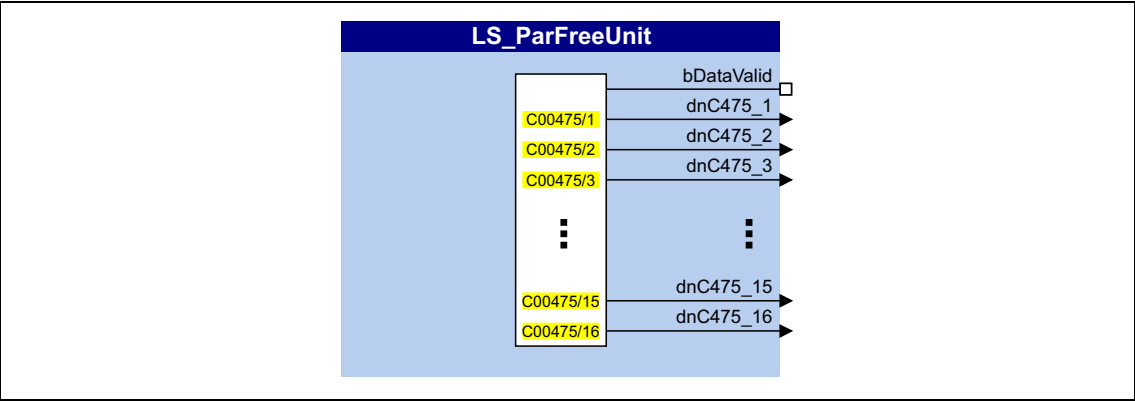
Parameter

Parameter	Possible settings			Info
C00479/1...8	-2147483647		2147483647	Setting of the 32-bit signals to be output

19.2.32 LS_ParFreeUnit

This system block outputs 16 parameterisable position signals.

- In contrast to the SB [LS_ParFree_p](#), the positions are set in the application unit [unit] instead of in [increments].
- The *bDataValid* status signal indicates that the internal position conversion is completed and the output data are consistent.



Outputs

Identifier	Data type	Value/meaning
bDataValid	BOOL	Status signal "Position conversion completed, data consistent"
		TRUE The conversion of the positions from [unit] to [increments] is completed.
dnC475_1 ... dnC475_16	DINT	Output of the position signals parameterised in C00475/1...16 in [increments] • Observe <i>bDataValid</i> status signal!

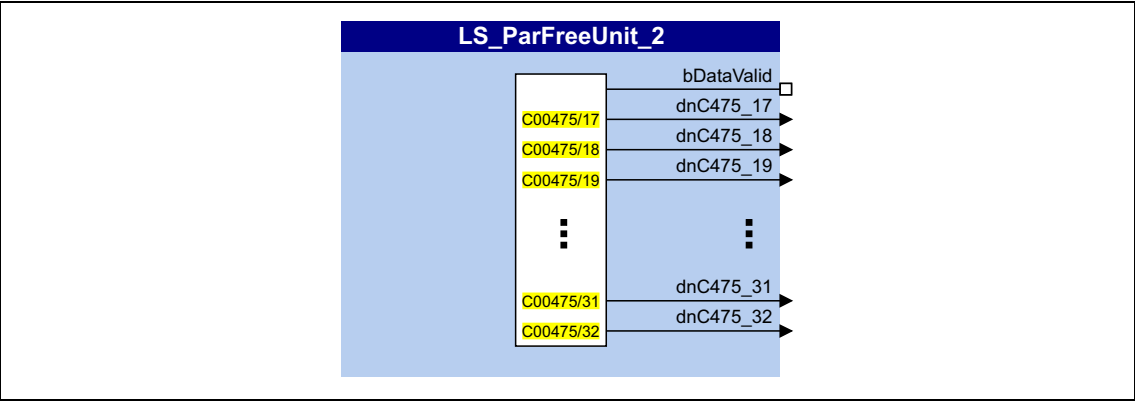
Parameter

Parameter	Possible settings			Info
C00475/1...16	-214748.3647	unit	214748.3647	Setting of the position signals to be output

19.2.33 **LS_ParFreeUnit_2**

This system block outputs 16 parameterisable position signals.

- In contrast to the SB [LS_ParFree_p](#), the positions are set in the application unit [unit] instead of in [increments].
- The *bDataValid* status signal indicates that the internal position conversion is completed and the output data are consistent.



Outputs

Identifier	Data type	Value/meaning
bDataValid	BOOL	Status signal "Position conversion completed, data consistent"
		TRUE The conversion of the positions from [unit] to [increments] is completed.
dnC475_17 ... dnC475_32	DINT	Output of the position signals parameterised in C00475/17...32 in [increments] • Observe <i>bDataValid</i> status signal!

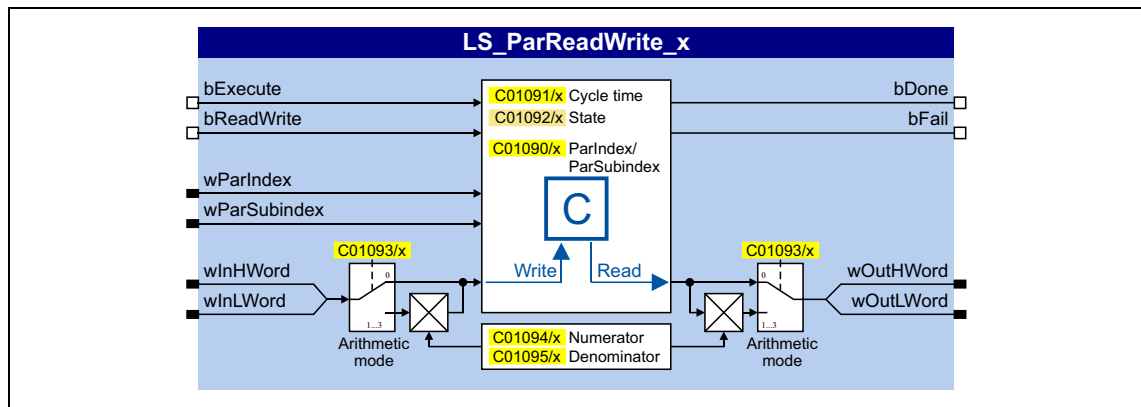
Parameter

Parameter	Possible settings			Info
C00475/17...32	-214748.3647	unit	214748.3647	Setting of the position signals to be output

19.2.34 LS_ParReadWrite_1-6

The **LS_ParReadWrite_1 ... LS_ParReadWrite_6** system blocks are used for reading and writing local parameters.

- If several system blocks are activated at the same time, the blocks will be processed one at a time every time the main program is executed.
- The SB supports one-time and cyclic reading/writing in an adjustable time interval.



Inputs

Identifier	Data type	Information/possible settings
bExecute	BOOL	Trip read/write request
		FALSE → TRUE: If cycle time (C01091) = "0 ms": <u>One-time</u> reading/writing of the parameter value which has been addressed via the <i>wParIndex</i> and <i>wParSubindex</i> inputs.
		If cycle time (C01091) > "0 ms": <u>Cyclic</u> reading/writing of the parameter value which has been addressed via the <i>wParIndex</i> and <i>wParSubindex</i> inputs.
		TRUE → FALSE: Deactivate cyclic reading/writing again.
bReadWrite	BOOL	Selection: Read or write request
		FALSE: Read request
		TRUE: Write request
wParIndex	WORD	Code to be read or written. • The selection can be made alternatively via C01090.
wParSubindex	WORD	Subcode to be read or written. • The selection can be made alternatively via C01090.
wInHWord wInLWord	WORD	Value to be written (DataHigh/DataLow portion)

Outputs

Identifier	Data type	Value/meaning
bDone	BOOL	"Read/Write request successfully completed" status signal <ul style="list-style-type: none"> The output is automatically reset to FALSE if a new request is activated via <i>bExecute</i> or the cycle time (C01091) expires.
		TRUE Read/Write request successfully completed.
		FALSE The FALSE status can have the following meanings: <ol style="list-style-type: none"> There is no active read/write request. The read/write request has not been completed yet. An error has occurred (if <i>bFail</i> = TRUE).
bFail	BOOL	"Error" status
		TRUE An error has occurred (group signal). <ul style="list-style-type: none"> See display parameter (C01092) for details.
wOutHWord wOutLWord	WORD	Value which was read (DataHigh/DataLow portion) after read request

Parameter

Parameter	Possible settings			Info
C01090/1...6	0,000		16000,000	Parameter to be read or written. <ul style="list-style-type: none">For a setting of "0,000", inputs <i>wParIndex</i> and <i>wParSubindex</i> are effective for addressing purposes instead.Lenze setting: 0.000
	Format: <Code number>,<subcode number>			
C01091/1...6				Cycle time <ul style="list-style-type: none">Subcode 1 = LS_ParReadWrite_1Subcode 2 = LS_ParReadWrite_2...Subcode 6 = LS_ParReadWrite_6Lenze setting: 0
	0	One-time reading/writing at <i>bExecute</i> in case of a FALSE/TRUE edge		
	Cyclic reading/writing:			
	20	20 ms		
	50	50 ms		
	100	100 ms		
	200	200 ms		
	500	500 ms		
	1000	1 s		
	2000	2 s		
	5000	5 s		
	10000	10 s		

Parameter	Possible settings			Info
C01092/1...6				Error status <ul style="list-style-type: none">• If <i>bFail</i> = TRUE: Error status is displayed.• Subcode 1 = LS_ParReadWrite_1 Subcode 2 = LS_ParReadWrite_2 ... Subcode 6 = LS_ParReadWrite_6
	0	No error		
	33803	Invalid data type (e.g. STRING)		
	33804	Limit violation		
	33806	Invalid code		
	33813	No element of the selection list		
	33815	Writing of the parameter not permitted		
	33816	Writing of the parameter only permitted if controller is inhibited		
	33829	Invalid subcode		
	33865	No parameter with subcodes		
C01093/1...6				Arithmetic mode <ul style="list-style-type: none">• Lenze setting: "0: No arithmetic"▶ Arithmetic function
	0	No arithmetic		
	1	In16Bit: LW=+/-32767		
	2	In16Bit: HW=+/-; LW=0..65535		
	3	In32Bit: HW_LW=+/-2147483647		
C01094/1...6	-32767		32767	Counter <ul style="list-style-type: none">• For internal conversion in arithmetic modes 1 ... 3.• Lenze setting: 1
C01095/1...6	1		32767	Denominator <ul style="list-style-type: none">• For internal conversion in arithmetic modes 1 ... 3.• Lenze setting: 1

19.2.34.1 Arithmetic function

The implemented arithmetic function enables easy arithmetic conversion of the process values to be written or read via parameterisable factors into the format of the target parameter without the need of an additional arithmetic function block.

- In [C01093](#), the interpretation of the *wInHWord* and *wInLWord* inputs can be set to be able to write to parameters:

Arithmetic mode		wInHWord	wInLWord	Internal conversion
0	No arithmetic (Lenze setting)	INTEGER_32 (4 bytes with sign)		No (same behaviour as before)
		DataHigh portion	DataLow portion	
1	In16Bit: LW=+/-32767	-	INTEGER_16 (2 bytes with sign)	Yes (see the following section)
2	In16Bit: HW=+/-; LW=0..65535	Sign (0 ≡ positive value)	UNSIGNED_16 (2 bytes without sign)	
3	In32Bit: HW_LW= +/-2147483647	INTEGER_32 (4 bytes with sign)		
		DataHigh portion	DataLow portion	

Internal conversion

If arithmetic modes 1 ... 3 are selected in [C01093](#), the input value / read parameter value is internally converted via parameterisable factors.

- Division is not remainder considered.

$$\text{parameter value to be written} = \text{Input value}_{[32]} \cdot \frac{\text{Counter}_{[16]}}{\text{Denominator}_{[16]}}$$

[C01094](#): Numerator
[C01095](#): Denominator

[19-82] Internal conversion with write access

$$\text{Output value}_{[32]} = \text{Read parameter value} \cdot \frac{\text{Counter}_{[16]}}{\text{Denominator}_{[16]}}$$

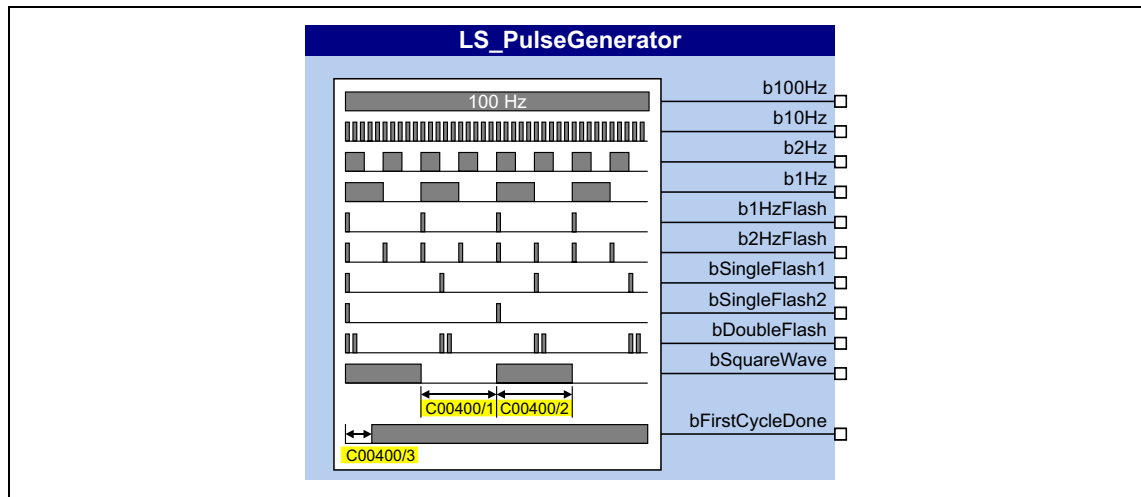
[C01094](#): Numerator
[C01095](#): Denominator

[19-83] Internal conversion with read access

19.2.35 LS_PulseGenerator

This system block outputs 9 different fixed frequencies and 1 frequency with parameterisable pulse/dead time.

The SB provides a TRUE signal at the *bFirstCycleDone* output when the first 1-ms processing cycle is completed and the time set in [C00400/3](#) has expired. This status signal can e.g. be used for the delayed enable of peripheral devices or motor control setpoints so that all required initial values are calculated first after the controller switch-on.



Outputs

Identifier	Data type	Value/meaning
b100Hz	BOOL	Rectangular signal 100 Hz
b10Hz	BOOL	Rectangular signal 10 Hz
b2Hz	BOOL	Rectangular signal 2 Hz
b1Hz	BOOL	Rectangular signal 1 Hz
b1HzFlash	BOOL	80 ms-pulse, repetition rate every second
b2HzFlash	BOOL	80 ms-pulse, repetition rate every 0.5 seconds
bSingleFlash1	BOOL	80 ms pulse, repetition rate every 1.25 seconds
bSingleFlash2	BOOL	80 ms pulse, repetition rate every 3 seconds
bDoubleFlash	BOOL	80 ms-double pulse, repetition rate every 1.25 seconds
bSquareWave	BOOL	Output frequency with pulse/dead time set in C00400/1...2
bFirstCycleDone	BOOL	Status signal "First processing cycle completed"
	TRUE	The first 1-ms processing cycle has been completed and the time set in C00400/3 has expired (i.e. all FBs have been called at least once).

Parameter

**Note!**

The real length of the low or high level at the *bSquareWave* output is always 1 ms higher than set in [C00400/1](#) or [C00400/2](#). If "0 ms" is set, a level with a length of 1 ms is created length, for instance, and if "1000 ms" is set, a level with a length of 1001 ms is created.

Parameter	Possible settings			Info
C00400/1	0	ms	60000	Length of the low level (break) + 1 ms • For output <i>bSquareWave</i> • Lenze setting: 1000 ms
C00400/2	0	ms	60000	Length of the high level + 1 ms • For output <i>bSquareWave</i> • Lenze setting: 1000 ms
C00400/3	0	ms	60000	Delay of the status <i>bFirstCycleDone</i> • Lenze setting: 100 ms

19.2.36 LS_Resolver

Interface to the resolver.



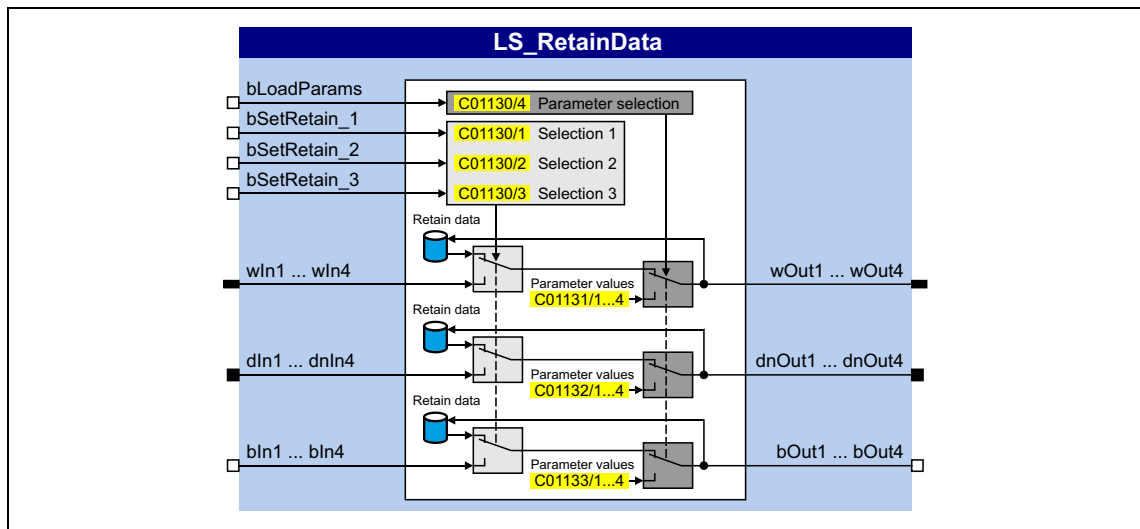
For detailed information please see the main chapter "Encoder/Feedback system":

► [Internal interfaces | "LS_Resolver" system block](#) (📖 324)

19.2.37 LS_RetainData

This system block serves to select and save retain data similar to the FBs [L_SampleHold_1](#) and [L_SampleHold_2](#).

- Retain data are values that are saved automatically at mains disconnection or disconnection of the 24-V supply in the controller and are restored when the 24-V supply is switched on again.
- A total of 12 retain data can be stored in the retain memory:
 - 4 WORD signals (16 bits, 0 ... 65535)
 - 4 DINT signals (32 bits, -2147483647 ... 2147483647)
 - 4 BOOL signals (FALSE or TRUE)



Inputs

Identifier	Data type	Information/possible settings
bLoadParams	BOOL	Set selected outputs & retain values to parameter values. <ul style="list-style-type: none"> • This input has priority over the <i>bSetRetain</i> inputs. • Typical application: Initialisation of the outputs & retain values.
		FALSE The input or retain values are output, depending on the <i>bSetRetain</i> input.
		TRUE The outputs selected in C01130/4 and the respective retain values are set to the parameter values and held as long as <i>bLoadParams</i> is TRUE. If the parameter values change during this time, the respective outputs and retain values change as well.
bSetRetain_1...3	BOOL	Transfer selected input values to the retain memory ("latch")
		FALSE No transfer. Retain values or parameter values (when <i>bLoadParams</i> = TRUE) are provided at the outputs.
		TRUE The input values selected in C01130/1...3 are stored in the retain memory and provided at the outputs.
wIn1 ... wIn4	WORD	Input values
dnIn1 ... dnIn4	DINT	
bIn1 ... bIn4	BOOL	

Outputs

Identifier	Data type	Value/meaning
wOut1 ... wOut4	WORD	Output of the input or retain values, depending on the <i>bSetRetain</i> input
dnOut1 ... dnOut4	DINT	
bOut1 ... bOut4	BOOL	

Parameter

Parameter	Possible settings			Info
C01130/1...4	Setting is bit coded:			Subcodes 1 ... 3: Selection 1 ... 3 <ul style="list-style-type: none">Select which input values are to be stored in the retain memory when setting the respective <i>bSetRetain</i>-input to TRUE.Lenze setting: 0x0000 Subcode 4: Parameter selection <ul style="list-style-type: none">Select which parameter values are to be stored in the retain memory when setting <i>bLoadParams</i> to TRUE.Lenze setting: 0x0000
		Subcodes 1 ... 3:	Subcode 4:	
	Bit 0	wIn1	C01131/1	
	Bit 1	wIn2	C01131/2	
	Bit 2	wIn3	C01131/3	
	Bit 3	wIn4	C01131/4	
	Bit 4	dnIn1	C01132/1	
	Bit 5	dnIn2	C01132/2	
	Bit 6	dnIn3	C01132/3	
	Bit 7	dnIn4	C01132/4	
	Bit 8	bln1	C01133/1	
	Bit 9	bln2	C01133/2	
	Bit 10	bln3	C01133/3	
	Bit 11	bln4	C01133/4	
	Bit 12	Reserved		
	Bit 13			
Bit 14				
Bit 15				
C01131/1...4	0		65536	Parameter value for retain memory (outputs <i>wOut1</i> ... <i>wOut4</i>) <ul style="list-style-type: none">Lenze setting: 0
C01132/1...4	-2147483647		2147483647	Parameter values for retain memory (outputs <i>dnOut1</i> ... <i>dnOut4</i>) <ul style="list-style-type: none">Lenze setting: 0
C01133/1...4				Parameter values for retain memory (outputs <i>bOut1</i> ... <i>bOut4</i>) <ul style="list-style-type: none">Lenze setting: 0: FALSE
	0	FALSE		
	1	TRUE		

19.2.38 LS_SetError_1

Parameterisable responses to user-defined events are tripped.



For a detailed description see the main chapter "Diagnostics & error management":

▶ ["LS_SetError_1" system block](#) (📖 731)

19.2.39 LS_SetError_2

Parameterisable responses to user-defined events are tripped.



For a detailed description see the main chapter "Diagnostics & error management":

▶ ["LS_SetError_2" system block](#) (📖 732)

19.2.40 LS_SyncManagement

Output of status information for synchronising the internal time base.



For a detailed description see main chapter "Synchronisation of the internal time base of the controller":

▶ [Internal interfaces | System block "LS_SyncManagement"](#) (📖 858)

19.2.41 LS_TouchProbe

Interface for touch probe detection.



For a detailed description see the main chapter "I/O terminals":

▶ [Touch probe detection](#) (📖 411)

19.2.42 LS_WriteParamList

Writing to a configurable list which contains up to 32 local parameters.



For a detailed description see the main chapterl "[Parameter change-over](#)". (📖 859)

Symbols

"DRV-ERR" LED [675](#)

"DRV-RDY" LED [675](#)

»Engineer« motor catalogue [139](#)

Numbers

120 % operation [260](#)

16-bit inputs (C00831) [1078](#)

16-bit inputs (Set2) (C00836) [1091](#)

16-bit inputs [%] (C00830) [1076](#)

16-bit inputs [%] (Set2) (C00835) [1087](#)

16-bit inputs [rpm] (C00832) [1081](#)

16-bit inputs [rpm] (Set2) (C00837) [1095](#)

16-bit inputs I/O level (C00841) [1109](#)

16-bit inputs I/O level [%] (C00840) [1106](#)

24 V supply voltage (C00065) [900](#)

32-bit inputs [incr] (C00834) [1087](#)

32-bit inputs [incr] (Set2) (C00839) [1104](#)

32-bit inputs I/O level [incr] (C00844) [1117](#)

87-Hz operation [165](#)

A

Ab01: Axis bus timeout (error message) [718](#)

Ab02: Axis bus IO error (error message) [718](#)

AB-STATE (LED) [837](#)

Accel. time - main setpoint (C00012) [889](#)

Acceleration override [653](#)

Access protection [43](#)

Accessories for commissioning [34](#)

ACDrive

Control word (C01351) [1203](#)

Drive mode (C01350) [1203](#)

Setpoint scaling (C01353) [1205](#)

Status word (C01352) [1204](#)

Acknowledgement error [797](#), [845](#)

Activating the bus terminating resistor [753](#), [840](#)

Active COBID (C00355) [959](#)

Actual values (C00055) [897](#)

Adapting keypad menus [37](#)

Add. accel. time x (C00101) [907](#)

Add. decel. time x (C00103) [908](#)

Additive speed specification [280](#)

AIN1

Characteristic (C00010) [889](#)

AIN2

Characteristic (C00020) [892](#)

AINx

Configuration (C00034) [895](#)

Gain (C00027) [893](#)

Input current (C00029) [894](#)

Input voltage (C00028) [893](#)

Offset (C00026) [893](#)

Output value (C00033) [894](#)

An01: AIN1_I < 4 mA (error message) [717](#)

An02: AIN2_I < 4 mA (error message) [717](#)

Analog terminals [401](#)

For electrical data see the hardware manual

User-defined terminal assignment [421](#)

Angle controller [280](#)

Angle controller overflow [1509](#)

Angle correction in case of transmission errors [1541](#)

Angular drift monitoring (encoder) [371](#)

AOutx

Decoupling value (C00442) [979](#)

Appl.

Reference frequency C11 (C00059) [898](#)

Reference speed (C00011) [889](#)

Application (C00005) [883](#)

Application block "LA_NCtrl" [433](#), [462](#)

Application block "LA_SwitchPos" [522](#)

Application block "LA_TabPos" [494](#)

Application notes [27](#)

Application units

Configuration of the display parameters [1704](#)

Display factor (C00485) [995](#)

Offset (C00484) [995](#)

Text (C00486) [995](#)

Application units (C00487) [996](#)

Assignment of the process data objects [765](#)

Auto-DCB [268](#)

Hold time (C00106) [910](#)

Threshold (C00019) [891](#)

AutoFailReset configuration (C00188) [934](#)

AutoFailReset function [692](#)

AutoFailReset repetition time (C00184) [933](#)

AutoFailReset residual runtime (C00185) [933](#)

Automatic DC-injection braking (auto DCB) [268](#)

Automatic motor data identification [141](#)

Auto-start option [124](#)

Auto-start option (C00142) [918](#)

Axis bus [836](#)

Axis bus address and no. of nodes (C02430) [1263](#)

Axis bus error status (C02436) [1264](#)

Axis bus MessageError (C02437) [1265](#)

Axis bus status (C02435) [1264](#)

Axis bus time settings (C02431) [1264](#)

AxisBusIO slave/master (C02440) [1265](#)

B

Basic drive functions [552](#)

Basic functions [552](#)

Behaviour after mains connection [124](#)

Binary inputs (C00833) [1083](#)

Binary inputs (Set2) (C00838) [1099](#)

Binary inputs I/O level (C00843) [1112](#)

Binding ID [48](#)

Bit error [797](#), [845](#)

Brake chopper [281](#)
 Master-slave operation [289](#)
Brake control [655](#)
Brake energy management (C00175) [931](#)
Brake resistance value (C00129) [913](#)
Brake resistor [281](#)
Brake resistor monitoring (I2xt) [298](#)
Brake resistor overload threshold (C00572) [1011](#)
Brake resistor utilisation (C00133) [914](#)
Braking operation/brake energy management [281](#)
Braking procedures [284](#)

C

C1 [879](#)
C10 [889](#)
C100 [907](#)
C1000 [1138](#)
C1001 [1138](#)
C101 [907](#), [1580](#)
C1010 [1139](#), [1403](#), [1404](#), [1405](#)
C1011 [1139](#), [1406](#), [1407](#), [1408](#)
C1012 [1139](#), [1622](#)
C1020 [1140](#), [1590](#)
C1021 [1140](#), [1590](#)
C1022 [1140](#), [1590](#)
C1023 [1140](#), [1590](#)
C1025 [1141](#), [1480](#)
C1026 [1141](#), [1480](#)
C1028 [1141](#), [1481](#)
C1029 [1142](#), [1481](#)
C103 [908](#), [1580](#)
C1030 [1142](#), [1483](#)
C1031 [1142](#), [1483](#)
C1033 [1143](#), [1483](#)
C1034 [1143](#), [1483](#)
C1035 [1143](#), [1484](#)
C104 [909](#)
C1040 [1144](#), [1676](#)
C1041 [1144](#), [1676](#)
C1042 [1144](#), [1677](#)
C1045 [1145](#), [1435](#), [1436](#), [1437](#)
C1046 [1145](#), [1444](#), [1445](#), [1446](#)
C1047 [1145](#), [1536](#)
C1048 [1146](#), [1536](#)
C1049 [1146](#), [1410](#)
C105 [910](#)
C1050 [1146](#), [1411](#), [1412](#)
C1051 [1146](#), [1410](#), [1411](#), [1412](#)
C1052 [1147](#), [1411](#), [1412](#)
C1053 [1147](#), [1635](#)
C1054 [1147](#), [1635](#)
C1055 [1147](#), [1635](#)
C1056 [1148](#), [1635](#)
C1057 [1148](#), [1411](#)
C1058 [1148](#), [1628](#), [1631](#)
C1059 [1148](#), [1629](#), [1632](#)
C106 [910](#)
C1060 [1149](#), [1629](#), [1632](#)
C1061 [1149](#), [1629](#), [1632](#)
C1062 [1149](#), [1681](#)
C1063 [1150](#), [1681](#)
C1064 [1150](#), [1681](#)
C1065 [1151](#), [1682](#)
C1066 [1151](#), [1682](#)
C1067 [1152](#), [1411](#), [1500](#), [1624](#)
C1068 [1152](#), [1682](#)
C1069 [1153](#), [1500](#)
C107 [910](#)
C1070 [1153](#), [1500](#), [1501](#)
C1071 [1153](#), [1500](#)
C1072 [1153](#), [1500](#)
C1073 [1154](#)
C1074 [1154](#), [1501](#)
C1075 [1155](#), [1502](#)
C1076 [1155](#), [1490](#)
C1077 [1155](#), [1490](#)
C1078 [1156](#), [1490](#)
C1079 [1156](#), [1490](#)
C1080 [1156](#), [1490](#)
C1081 [1156](#), [1491](#)
C1082 [870](#), [1157](#)
C1083 [1157](#)
C1084 [1157](#)
C1085 [1157](#)
C1086 [1158](#)
C1087 [1158](#)
C1088 [1158](#)
C1089 [1159](#)
C1090 [1159](#), [1722](#)
C1091 [1160](#), [1722](#)
C1092 [1160](#), [1723](#)
C1093 [1161](#), [1723](#)
C1094 [1161](#), [1723](#)
C1095 [1162](#), [1723](#)
C11 [889](#)
C1100 [1162](#), [1471](#), [1473](#), [1475](#)
C1101 [1162](#), [1471](#), [1473](#), [1475](#)
C1108 [1163](#)
C1109 [1163](#)
C1110 [1164](#)
C1111 [1164](#)
C1112 [1164](#)
C1119 [1165](#)
C1120 [1165](#)
C1121 [1165](#)
C1122 [1166](#)

Index

C1123	1166	C1229	1185
C1124	1166	C123	913
C1130	1167 , 1727 , 1728	C1230	1185
C1131	1167 , 1728	C1231	1186
C1132	1168 , 1728	C1232	1186
C1133	1168 , 1728	C1233	1186
C1138	1168 , 1688 , 1691 , 1692 , 1693	C1234	1187
C1139	1169 , 1688 , 1691 , 1692 , 1693	C1235	1187
C114	911	C1236	1187
C1140	1169 , 1694 , 1695 , 1696 , 1697	C1237	1188
C1141	1169 , 1694 , 1695 , 1696 , 1697	C1238	1188
C115	911	C1239	1188
C1150	1170 , 1615 , 1619	C1240	1189
C1151	1170 , 1615 , 1619	C1241	1191
C1152	1170 , 1686	C1242	1192
C1153	1171 , 1686	C1243	1192
C1154	1171 , 1686	C1244	1193
C1155	1172 , 1686	C1245	1193
C1156	1172 , 1686	C1246	1194
C1157	1173 , 1687	C1247	1194
C1158	1174 , 1687	C1251	1195
C117	912	C1252	1196
C118	912	C129	913
C1190	1174	C1294	1196 , 1450 , 1451 , 1452 , 1454
C1191	1175	C1295	1196
C1192	1175	C1296	493 , 499 , 502 , 513 , 514 , 575 , 576 , 580 , 581 , 1197
C1193	1175	C1297	1197
C12	889 , 1580	C1298	644 , 1198
C120	912	C1299	1198
C1201	1175	C13	890 , 1580
C1202	1176	C130	914
C1203	1176	C1300	1199
C1204	1176	C1301	1200
C1205	1176	C1302	1200
C1206	1177	C1303	1200
C121	913	C1304	1201
C1210	1177	C1305	1201
C1211	1178	C1306	1201
C1213	1178	C1307	1202
C1215	1178	C1308	1202
C1216	1179	C1309	1202
C1218	1180	C131	914
C1219	1180	C133	914
C122	913	C134	914 , 1580
C1220	1181	C1350	1203
C1221	1182	C1351	1203
C1222	1182	C1352	1204
C1223	1183	C1353	1205
C1224	1183	C136	915
C1225	1183	C137	916
C1226	1184	C138	917
C1227	1184	C1400	1205 , 1650
C1228	1184	C1401	1205 , 1650

Index

C1402	1206 , 1650	C1453	1224
C1403	1206 , 1650	C1454	1224
C1404	1206 , 1650	C1455	1225
C1405	1207 , 1656	C1460	1225 , 1433
C1406	1207 , 1656	C1461	1225 , 1433
C1407	1208 , 1656	C1462	1226 , 1433
C1408	1208 , 1656	C1463	1226 , 1433
C1409	1208 , 1656	C1464	1226 , 1433
C1410	1209 , 1656	C1465	1226 , 1433
C1411	1209 , 1657	C1466	1227 , 1433
C1412	1210 , 1657	C1467	1227 , 1433
C1413	1210 , 1657	C1468	1227 , 1433
C1414	1211 , 1657	C1469	1227 , 1550
C1415	1211 , 1658	C1470	1228 , 1550
C1416	1212 , 1658	C148	919
C1417	1212 , 1658	C15	890
C1418	1212 , 1659	C150	920
C1419	1213	C1501	1228
C142	918	C155	921
C1420	1213	C158	922
C1421	1213	C159	923
C1422	1213	C16	890
C1423	1214	C160	923
C1424	1214	C161	924
C1425	1214	C162	924
C1426	1214	C163	924
C1427	1215	C164	927
C1428	1215	C165	929
C1429	1215	C166	929
C1430	1215	C167	929
C1431	1216	C1670	1229 , 1423 , 1428 , 1429 , 1430 , 1431
C1432	1216	C1671	1229 , 1423 , 1428 , 1429 , 1430 , 1431
C1433	1216	C1672	1230 , 1423 , 1428 , 1429 , 1430 , 1431
C1434	1216	C168	929
C1435	1217	C169	930
C1436	1217	C170	930
C1437	1217 , 1659	C171	930
C1438	1218 , 1661	C173	931
C1439	1218 , 1661	C174	931
C144	918	C175	931
C1440	1219 , 1661	C1751	1230
C1441	1219 , 1662	C1752	1230
C1442	1219 , 1662	C1755	1230
C1443	1220 , 1663	C176	931
C1444	1220 , 1663	C1763	1230
C1445	1220 , 1663	C1764	1230
C1446	1221 , 1663	C1765	1230
C1447	1221 , 1663	C177	932
C1448	1221 , 1663	C1770	1231
C1449	1222 , 1664	C1771	1231
C1450	1222 , 1664	C1772	1231
C1451	1223 , 1664	C1773	1231
C1452	1223 , 1664	C1774	1231

Index

C1775	1231	C2226	1239
C178	932	C2227	1239
C179	932	C2228	1239
C18	891	C2229	1240
C180	932	C223	939 , 1607
C181	933	C2230	1240
C182	933 , 1580	C2231	1241
C184	933	C2232	1241
C185	933	C2233	1241
C186	933	C2234	1242
C187	934	C2236	1242
C188	934	C2237	1242
C189	934	C2238	1243
C19	891	C2239	1243
C190	935 , 1580	C224	939 , 1607
C1902	1232	C2240	1243
C1903	1232	C2241	1244
C1905	1232	C2242	1244
C191	935	C2244	1244
C192	935	C2245	1245
C193	936	C2246	1245
C199	936	C2249	1245
C2	879	C225	940 , 1607
C20	892	C2250	1246
C200	936	C2251	1246
C201	937	C2252	1246
C203	937	C2256	1247
C204	938	C226	940 , 1607
C205	938	C2260	1247
C206	938	C2261	1247
C21	892	C2262	1248
C210	938	C2263	1248
C219	938	C2264	1248
C22	892	C227	940 , 1607
C220	939 , 1580	C2272	1249
C2200	1232	C2273	1249
C221	939 , 1581	C2274	1250
C2210	1233	C2275	1250
C2212	1233	C2276	1250
C2213	1234	C2278	1251
C2214	1234	C2279	1251
C2215	1235	C228	940 , 1607
C2216	1235	C2280	1251
C2217	1235	C2281	1252
C2218	1236	C2284	1252
C2219	1236	C2285	1252
C222	939 , 1607	C2286	1253
C2220	1236	C2287	1253
C2221	1237	C2288	1253
C2222	1237	C2289	1254
C2223	1238	C2290	1254
C2224	1238	C2291	1254
C2225	1238	C2292	1255

Index

C2293	1255	C2589	1271
C2294	1255	C2593	1272
C2295	1256	C26	893
C2296	1256	C2607	1273
C2297	1256	C2610	1274
C2298	1257	C2611	1274
C2299	1257	C265	944
C23	892	C2652	1275
C2300	1257	C27	893
C2301	1258	C270	944
C2302	1258	C271	945
C2303	1258	C272	945
C2304	1259	C273	945
C2305	1259	C274	945
C2306	1261	C275	945
C2307	1261	C276	946
C231	940 , 1607	C28	893
C2311	1261	C280	946
C2312	1262	C2810	1276
C2313	1262	C2811	1276
C2314	1263	C2812	1277
C2315	1263	C2813	1277
C233	941 , 1608	C2814	1278
C234	941	C2815	1278
C235	941	C2816	1279
C236	941	C2817	1279
C24	893	C2830	1280
C241	941 , 1581	C2840	1281
C242	942 , 1608	C2841	1281
C243	942 , 1608	C2842	1281
C2430	1263	C2843	1282
C2431	1264	C2844	394 , 1282
C2435	1264	C2845	394 , 1282
C2436	1264	C2853	1283
C2437	1265	C2855	1283
C2438	1265	C2859	1283
C244	942 , 1608	C2862	1284
C2440	1265	C2863	1284
C2442	1266	C2864	1284
C2443	1267	C2865	1286
C2444	1268	C2866	1287
C245	942 , 1608	C2867	1288
C246	943 , 1608	C2870	1288
C247	943 , 1608	C2871	1288
C249	943 , 1638	C2872	1289
C250	943 , 1639 , 1640	C2873	1289
C251	943 , 1524	C2874	1290
C252	944 , 1524	C2875	1290
C253	944 , 1524	C2876	1291
C254	944	C2877	1291
C2580	1268	C2878	1292
C2581	1269	C2879	1293
C2582	1270	C29	894

Index

C290	946	C359	960
C291	946	C36	895
C295	946	C360	961
C296	946	C364	961
C297	946	C366	962
C2993	1293	C367	962
C2994	1293	C368	963
C2995	1293	C369	963
C2996	1294	C370	964
C2998	1294	C371	964
C3	882	C372	964
C30	894	C381	964
C301	947	C385	965
C302	947	C386	965
C304	947	C387	965
C305	947	C39	896 , 1580
C306	947	C400	966 , 1726
C307	947	C401	966
C308	947	C407	967
C309	947	C408	967
C310	947	C409	968
C311	948	C410	968 , 1666
C312	948	C411	969 , 1667
C313	948	C412	969 , 1667
C314	948	C413	969 , 1666
C315	948	C417	970
C316	948	C420	970
C317	948	C421	970
C320	948	C422	971
C321	949	C423	971
C322	949	C424	971
C323	950	C425	972
C324	950	C426	973
C33	894	C427	973
C338	951 , 1398	C428	974
C339	951 , 1399	C430	974
C34	895	C431	975
C341	952	C432	976
C342	953	C434	976
C343	954	C435	977
C344	955	C436	977
C345	955	C437	977
C347	956	C439	978
C349	956	C440	978
C350	957	C441	979
C351	957	C442	979
C352	957	C443	980
C353	958	C444	981
C354	958	C445	981
C355	959	C446	982
C356	959	C447	982
C357	960	C448	983
C358	960	C449	983

Index

C451 [984](#)
C452 [985](#)
C453 [985](#)
C455 [985](#)
C456 [986](#)
C458 [986](#)
C459 [986](#)
C460 [986](#)
C461 [986](#)
C462 [986](#)
C463 [987](#)
C464 [988](#)
C465 [988](#)
C466 [988](#)
C467 [988](#)
C468 [988](#)
C469 [989](#)
C470 [989](#), [1714](#)
C471 [989](#), [1710](#)
C472 [990](#), [1712](#)
C473 [990](#), [1716](#)
C474 [991](#), [1715](#)
C475 [991](#), [1719](#), [1720](#)
C476 [992](#), [1713](#)
C477 [992](#), [1711](#)
C478 [993](#), [1717](#)
C479 [993](#), [1718](#)
C480 [993](#), [1705](#)
C481 [994](#), [1702](#)
C482 [994](#), [1703](#)
C483 [994](#), [1706](#)
C484 [995](#), [1704](#)
C485 [995](#), [1704](#)
C486 [995](#), [1704](#)
C487 [996](#), [1704](#)
C488 [996](#)
C490 [997](#)
C491 [997](#)
C492 [997](#)
C493 [998](#)
C494 [998](#)
C495 [998](#)
C496 [999](#)
C497 [999](#)
C498 [1000](#)
C499 [1001](#)
C5 [883](#)
C50 [896](#)
C505 [1001](#)
C506 [1002](#)
C507 [1003](#)
C508 [1004](#)
C509 [1005](#)

C51 [896](#)
C510 [1006](#)
C516 [1006](#)
C517 [1007](#)
C52 [897](#)
C53 [897](#)
C54 [897](#)
C540 [1008](#)
C545 [1008](#)
C55 [897](#)
C56 [898](#)
C560 [1008](#)
C561 [1009](#)
C565 [1009](#)
C566 [1009](#)
C567 [1009](#)
C569 [1010](#)
C57 [898](#)
C570 [1010](#)
C571 [1011](#)
C572 [1011](#)
C574 [1011](#)
C576 [1011](#)
C577 [1012](#)
C578 [1012](#)
C579 [1012](#)
C58 [898](#)
C580 [1012](#)
C581 [1013](#)
C582 [1013](#)
C583 [1014](#)
C585 [1014](#)
C586 [1014](#)
C588 [1015](#)
C59 [898](#)
C590 [1015](#)
C591 [1015](#)
C592 [1016](#)
C593 [1016](#)
C594 [1017](#)
C595 [1018](#)
C597 [1019](#)
C598 [1019](#)
C599 [1019](#)
C6 [883](#)
C60 [898](#)
C600 [1020](#)
C601 [1020](#)
C602 [1020](#)
C603 [1021](#)
C604 [1021](#)
C605 [1022](#)
C606 [1022](#)

Index

C607	1022	C685	1046 , 1419
C608	1022	C686	1046 , 1419
C609	1023	C687	1046 , 1419
C61	899	C690	1047 , 1420
C610	1023	C691	1047 , 1420
C611	1023	C692	1047 , 1420
C612	1023	C693	1047 , 1421 , 1422
C613	1023	C694	1048 , 1421 , 1422
C615	1023	C695	1048 , 1421 , 1422
C617	1023	C696	1048 , 1594
C62	899	C697	1048 , 1595
C620	1024	C698	1048 , 1596
C621	1028	C699	1049 , 1564
C622	1035	C7	885
C63	899	C70	901
C630	1036 , 1544 , 1545	C700	1049
C631	1037 , 1546 , 1547 , 1548	C701	1050
C632	1037 , 1581	C705	1052
C633	1037 , 1581	C706	1053
C634	1038 , 1581	C71	901
C635	1038 , 1581	C710	1053
C636	1038 , 1581	C711	1054
C637	1039 , 1581	C712	1057
C638	1039 , 1581	C715	1057
C639	1039 , 1581	C716	1057
C64	900	C717	1057
C640	1039 , 1581	C72	901
C643	1039	C720	1058 , 1510
C644	1040	C721	1058 , 1512 , 1513
C645	1040	C725	1059
C646	1040	C726	1059
C647	1040	C727	1060 , 1708
C65	900	C728	1060 , 1708
C650	1041 , 1400 , 1401 , 1402	C729	1060
C653	1041	C73	901
C654	1042	C730	1060
C658	1042	C731	1061
C659	1042	C732	1061
C66	900	C734	1061
C660	1042 , 1525	C735	1061
C661	1043 , 1526	C736	1061
C662	1043 , 1527	C74	902
C670	1043 , 1594	C740	1061
C671	1043 , 1595	C741	1061
C672	1044 , 1596	C742	1061
C673	1044 , 1597 , 1598	C743	1061
C674	1044 , 1597 , 1598	C744	1062
C677	1044 , 1531 , 1532 , 1533	C746	1062
C678	1045 , 1534 , 1535	C747	1062
C679	1045 , 1565	C748	1062
C680	1045 , 1414	C749	1062
C681	1045 , 1414	C75	902
C682	1046 , 1414	C750	1062

Index

C751	1062	C843	1112
C753	1062	C844	1117
C76	902	C85	904
C760	1063	C866	1118
C761	1064	C868	1119
C762	1066	C87	905
C765	1066	C876	1120
C766	1066	C877	1121
C767	1066	C88	905
C77	902	C89	905
C78	903	C890	1121
C79	903	C90	905
C8	887	C905	1122
C80	903	C909	1122
C800	1066 , 1561	C91	906
C801	1067 , 1561	C910	1122
C802	1067 , 1561	C915	1123
C803	1067 , 1561	C916	1123
C804	1067 , 1561	C917	1123
C805	1067	C918	1123
C806	1068 , 1561	C919	1124
C807	1068 , 1570	C92	906
C808	1068 , 1570	C922	1124
C809	1069 , 1573	C925	1124
C81	904	C926	1124
C810	1069 , 1573	C927	1124
C811	1069	C93	906
C812	1070	C937	1125
C82	904	C938	1125
C820	1070 , 1514	C939	1125
C821	1071 , 1515	C940	1125 , 1456 , 1458 , 1459 , 1460
C822	1071 , 1516	C941	1126 , 1456 , 1458 , 1459 , 1460
C823	1072 , 1517	C942	1126 , 1456 , 1458 , 1459 , 1460
C824	1072 , 1520	C95	906
C825	1072 , 1520	C950	1126 , 1539
C826	1073 , 1522	C951	1127 , 1539
C827	1073 , 1522	C952	1127 , 1539
C828	1074 , 1518	C953	1127 , 1539
C829	1075 , 1519	C959	1127 , 1476 , 1480 , 1483
C83	904	C960	1128 , 1476
C830	1076	C961	1128 , 1476
C831	1078	C963	1128 , 1477
C832	1081	C964	1129 , 1477
C833	1083	C965	1129
C834	1087	C966	1129
C835	1087	C967	1130
C836	1091	C968	1130
C837	1095	C969	1131
C838	1099	C97	906
C839	1104	C971	1131
C84	904	C972	1131
C840	1106	C973	1131
C841	1109	C975	1132

- C976 [1132](#)
- C977 [1132](#)
- C978 [1132](#)
- C979 [1132](#)
- C98 [907](#)
- C980 [1133](#)
- C981 [1133](#)
- C982 [1133](#)
- C983 [1133](#)
- C985 [1134](#)
- C986 [1134](#)
- C987 [1134](#)
- C988 [1134](#)
- C989 [1134](#)
- C99 [907](#)
- C990 [1135](#)
- C991 [1135](#)
- C992 [1135](#)
- C993 [1135](#)
- C994 [1136](#)
- C995 [1136](#)
- C996 [1136](#)
- C997 [1136](#)
- C998 [1137](#)
- C999 [1137](#)
- CA06: CAN CRC error (error message) [719](#)
- CA07: CAN bus warning (error message) [719](#)
- CA08: CAN bus stopped (error message) [719](#)
- CA0b: CAN HeartBeatEvent (error message) [719](#)
- CA0F: CAN control word (error message) [720](#)
- CAB configuration (C02444) [1268](#)
- CAB decoupling inputs (C02442) [1266](#)
- CAB decoupling value (C02443) [1267](#)
- CAB_Tx_Rx_diagnosis (C02438) [1265](#)
- Calculating mass inertia (SC) [241](#)
- Calculating mass inertia (SLVC) [203](#)
- CAN baud rate (C00351) [957](#)
- CAN data telegram [757](#)
- CAN decoupling PDOInOut (C00342) [953](#)
- CAN error status (C00345) [955](#)
- CAN ErrorCode (C00371) [964](#)
- CAN HeartBeat ConsumerTime (C00386) [965](#)
- CAN Heartbeat producer time (C00381) [964](#)
- CAN IN/OUT COBID source (C00353) [958](#)
- CAN input words (C00866) [1118](#)
- CAN management - error configuration (C00341) [952](#)
- CAN MessageError (C00364) [961](#)
- CAN monitoring times (C00357) [960](#)
- CAN node addr. HeartBeat producer (C00385) [965](#)
- CAN node address (C00350) [957](#)
- CAN on board [749](#)
- CAN output words (C00868) [1119](#)
- CAN reset node [756](#)
- CAN setting - DIP switch (C00349) [956](#)
- CAN slave/master (C00352) [957](#)
- CAN start remote node [763](#)
- CAN status (C00359) [960](#)
- CAN status HeartBeat producer (C00347) [956](#)
- CAN SYNC Rx identifier (C00367) [962](#)
- CAN sync transmission cycle time (C00369) [963](#)
- CAN SYNC Tx identifier (C00368) [963](#)
- CAN telegram counter (C00360) [961](#)
- CAN time settings (C00356) [959](#)
- CAN transmission blocking time (C00324) [950](#)
- CAN_Tx_Rx_Error (C00372) [964](#)
- CAN-ERR (LED) [755](#)
- CAN-GatewayAddr (C00387) [965](#)
- CAN-RUN (LED) [755](#)
- CANx_OUT data length (C00358) [960](#)
- CANxInOut
 - Inversion (C00401) [966](#)
- Cause of controller inhibit (C00158) [922](#)
- Cause of quick stop QSP (C00159) [923](#)
- CE04: MCI communication error (error message) [718](#)
- CE0F: MCI control word (error message) [718](#)
- CE1: CAN RPDO1 (error message) [720](#)
- CE2: CAN RPDO2 (error message) [720](#)
- CE3: CAN RPDO3 (error message) [720](#)
- CE4: CAN bus off (error message) [719](#)
- Change of the operating mode [566](#)
- CI01: Module missing/incompatible (error message) [721](#)
- Ck01: Pos. HW limit switch (error message) [724](#)
- Ck02: Neg. HW limit switch (error message) [725](#)
- Ck03: Pos. SW limit position (error message) [725](#)
- Ck04: Neg. SW limit position (error message) [725](#)
- Ck05: Following error 1 (error message) [726](#)
- Ck06: Following error 1 (error message) [726](#)
- Ck07: Travel range limit exceeded (error message) [726](#)
- Ck08: Home position unknown (error message) [726](#)
- Ck09: Positioning mode invalid (error message) [726](#)
- Ck10: Implausible profile data (error message) [727](#)
- Ck11: Invalid operating mode (error message) [727](#)
- Ck12: Invalid profile number (error message) [727](#)
- Ck13: Error - MCKCtrlInterface function block (error message) [727](#)
- Ck14: Target position outside SW limit position (error message) [725](#)
- Ck15: Error status sign. brake (error message) [725](#)
- Ck16: Time overflow - manual operation (error message) [726](#)
- COB-ID [757](#)
- COBID (C00354) [958](#)
- COB-ID EMCY (I-1014) [808](#)
- COB-ID SYNC message (I-1005) [807](#)
- Commissioning wizard 8400 [56](#)
- Communication control words (C00136) [915](#)
- Communication cycle period (I-1006) [808](#)
- Communication time [752](#)

Comparing applications [1376](#)
Comparing FB interconnections [1376](#)
Comparing interconnections [1376](#)
Comparison L_Counter 1-3 (C01101) [1162](#)
Configuring exception handling of the CAN PDOs [783](#)
Configuring exception handling of the output terminals [420](#)
Consumer heartbeat time (I-1016) [809](#)
Control mode (C00007) [885](#)
Control type [149](#)
Control USER-LED [400](#)
Control word (MCK) [560](#)
Conventions used [24](#)
Conventions used for variable identifiers [1334](#)
Copying a complete interconnection [1379](#)
Copying an FB interconnection [1379](#)
Copying an interconnection [1379](#)
Copying elements [1370](#)
Copying interconnection elements [1370](#)
Copying objects [1370](#)
Correction of the leakage inductance [262](#)
Cosine phi (C00979) [1132](#)
CountInx
 Counter content (C02841) [1281](#)
 Parameter (C02840) [1281](#)
CP04: CAN RPDO4 (error message) [720](#)
CRC error [797](#), [845](#)
Current AutoFailReset processes (C00187) [934](#)
Current error (C00170) [930](#)
Current password protection (C00507) [1003](#)
Current setpoint filter (band-stop filter) [244](#)
Current switching frequency (C00725) [1059](#)

D

Data type [874](#)
Data type entry [1334](#)
DC braking
 Current (C00036) [895](#)
 Hold time (C00107) [910](#)
DCB (DC-injection braking) [268](#)
DC-bus system
 Control of multiple brake choppers [289](#)
DC-bus voltage (C00053) [897](#)
DC-injection braking [267](#)
Deactivate resolver error comp. (C00417) [970](#)
Decel. time - main setpoint (C00013) [890](#)
Decel. time - quick stop (C00105) [910](#)
Decoupling AnalogOut (C00441) [979](#)
Defining a user-defined V/f characteristic [172](#)
Defining the current limits [154](#)
Defining the speed limits [154](#)
Del.resp. to fault
 DC-bus overvoltage (C00601) [1020](#)
Delay (C00983) [1133](#)
Description data (C00199) [936](#)

Device access protection [43](#)
Device commands (C00002) [879](#)
Device overload monitoring (Ixt) [293](#)
Device personalisation [48](#)
Device search function [112](#)
Device status (C00137) [916](#)
Device statuses (LED status display) [675](#)
Device type (I-1000) [805](#)
Device utilisat. threshold (Ixt) (C00123) [913](#)
Device utilisation (Ixt) (C00064) [900](#)
dF10: AutoTrip reset (error message) [724](#)
dF14: SW-HW invalid (error message) [723](#)
dF15: DCCOM CU2 error (error message) [723](#)
dF18: BU RCOM error (error message) [723](#)
dF21: BU watchdog (error message) [723](#)
dF22: CU watchdog (error message) [723](#)
dF25: CU RCOM error (error message) [723](#)
dF26: Appl. watchdog (error message) [723](#)
dF50: Retain error (error message) [724](#)
dF51: CuCcr error (error message) [724](#)
dF52: BuCcr error (error message) [724](#)
dH09: EEPROM power section (error message) [728](#)
dH10: Fan failure (error message) [728](#)
dH68: Adjustment data error CU (error message) [728](#)
dH69: Adjustment data error BU (error message) [728](#)
dH70: ControlUnit is unequal to BaseUnit (error message) [728](#)
DI 1/2 & 6/7
 Function (C00115) [911](#)
Diagnosis terminal X400 [34](#)
Diagnostic interface (DIAG) [36](#)
Diagnostics X6
 Change baud rate (C01903) [1232](#)
 Current baud rate (C01905) [1232](#)
 Max. baud rate (C01902) [1232](#)
DigInX
 Inversion (C00114) [911](#)
Digital frequency coupling [345](#)
Digital terminals
 For electrical data see the hardware manual
 Input terminals [377](#)
 Output terminals [398](#)
 Touch probe detection [411](#)
 User-defined terminal assignment [421](#)
DigOut decoupling (C00447) [982](#)
DigOut decoupling value (C00448) [983](#)
DigOutX
 Inversion (C00118) [912](#)
DIP switch settings [753](#)
Direction of rotation check (manual control) [58](#)
Display details of the current error [678](#)
Display error details [678](#)
Display of internal process factors in application units [1704](#)
Display process factors on the keypad [1704](#)

Dlx

- Debounce time (C02830) [1280](#)
- Level (C00443) [980](#)

DOx

- Delay times (C00423) [971](#)
- Level (C00444) [981](#)

Drifting of the motor shaft [567](#)

Drive interface [99](#)

Drive-based safety [568](#)

DRV-ERR (LED) [675](#)

DRV-RDY (LED) [675](#)

E

EASY Starter [33](#)

Elapsed-hour meter (C00178) [932](#)

Electrical data

- see hardware manual

E-mail to Lenze [1758](#)

Emergency [801](#)

Emergency operation in case of encoder open circuit [186](#), [226](#), [313](#)

Encoder [355](#), [357](#)

Encoder - angular drift monitoring [371](#)

Encoder evaluation method [355](#)

Encoder evaluation method DigIn12 (C00496) [999](#)

Encoder scanning time (C00425) [972](#)

Encoder/feedback system [314](#)

Energy display (C00981) [1133](#)

Energy-saving V/f characteristic control (VFCplusEco) [176](#)

Engineer [33](#)

Error detection [797](#)

Error ID [698](#), [700](#)

Error information (C00165) [929](#)

Error information text (C00166) [929](#)

Error messages [696](#)

Error messages (short overview) [702](#)

Error messages (system bus) [790](#)

Error number [696](#), [699](#)

- xx.0111.00002 [705](#)
- xx.0111.00003 [705](#)
- xx.0111.00004 [706](#)
- xx.0111.00006 [706](#)
- xx.0119.00000 [706](#)
- xx.0119.00001 [706](#)
- xx.0119.00002 [706](#)
- xx.0119.00003 [707](#)
- xx.0119.00012 [707](#)
- xx.0119.00015 [707](#)
- xx.0119.00020 [707](#)
- xx.0119.00021 [707](#)
- xx.0119.00022 [708](#)
- xx.0119.00050 [708](#)
- xx.0123.00001 [708](#)
- xx.0123.00007 [708](#)
- xx.0123.00014 [709](#)

xx.0123.00015 [709](#)

xx.0123.00016 [709](#)

xx.0123.00017 [710](#)

xx.0123.00024 [710](#)

xx.0123.00026 [710](#)

xx.0123.00027 [710](#)

xx.0123.00028 [711](#)

xx.0123.00029 [711](#)

xx.0123.00030 [711](#)

xx.0123.00031 [711](#)

xx.0123.00032 [711](#)

xx.0123.00033 [712](#)

xx.0123.00056 [712](#)

xx.0123.00057 [712](#)

xx.0123.00058 [712](#)

xx.0123.00059 [712](#)

xx.0123.00060 [713](#)

xx.0123.00061 [713](#)

xx.0123.00062 [713](#)

xx.0123.00065 [713](#)

xx.0123.00071 [713](#)

xx.0123.00074 [714](#)

xx.0123.00075 [714](#)

xx.0123.00090 [714](#)

xx.0123.00093 [714](#)

xx.0123.00094 [715](#)

xx.0123.00095 [715](#)

xx.0123.00096 [715](#)

xx.0123.00097 [715](#)

xx.0123.00098 [715](#)

xx.0123.00099 [716](#)

xx.0123.00105 [716](#)

xx.0123.00145 [716](#)

xx.0123.00200 [716](#)

xx.0123.00201 [716](#)

xx.0123.00205 [717](#)

xx.0123.00206 [717](#)

xx.0125.00001 [717](#)

xx.0125.00002 [717](#)

xx.0126.00001 [718](#)

xx.0126.00002 [718](#)

xx.0127.00002 [718](#)

xx.0127.00015 [718](#)

xx.0131.00000 [719](#)

xx.0131.00006 [719](#)

xx.0131.00007 [719](#)

xx.0131.00008 [719](#)

xx.0131.00011 [719](#)

xx.0131.00015 [720](#)

xx.0135.00001 [720](#)

xx.0135.00002 [720](#)

xx.0135.00003 [720](#)

xx.0135.00004 [720](#)

xx.0140.00013 [721](#)

xx.0144.00001 [721](#)

xx.0144.00002 [721](#)

xx.0144.00003 [721](#)

xx.0144.00004 [722](#)

xx.0144.00007 [722](#)
xx.0144.00008 [722](#)
xx.0144.00009 [722](#)
xx.0144.00010 [722](#)
xx.0145.00014 [723](#)
xx.0145.00015 [723](#)
xx.0145.00024 [723](#)
xx.0145.00025 [723](#)
xx.0145.00026 [723](#)
xx.0145.00033 [723](#)
xx.0145.00034 [723](#)
xx.0145.00035 [724](#)
xx.0145.00050 [724](#)
xx.0145.00051 [724](#)
xx.0145.00052 [724](#)
xx.0184.00001 [724](#)
xx.0184.00002 [725](#)
xx.0184.00005 [725](#)
xx.0184.00007 [725](#)
xx.0184.00008 [725](#)
xx.0184.00015 [725](#)
xx.0184.00064 [726](#)
xx.0184.00153 [726](#)
xx.0184.00154 [726](#)
xx.0184.00155 [726](#)
xx.0184.00156 [726](#)
xx.0184.08005 [726](#)
xx.0184.08007 [727](#)
xx.0184.08009 [727](#)
xx.0184.08014 [727](#)
xx.0184.08015 [727](#)
xx.0400.00009 [728](#)
xx.0400.00016 [728](#)
xx.0400.00104 [728](#)
xx.0400.00105 [728](#)
xx.0400.00106 [728](#)
xx.0980.00000 ... xx.0980.65535 [728](#)
xx.0981.00000 ... xx.0981.65535 [729](#)
xx.0982.00000 ... xx.0982.65535 [729](#)
xx.0983.00000 ... xx.0983.65535 [729](#)
xx.0984.00000 ... xx.0984.65535 [729](#)
xx.0985.00000 ... xx.0985.65535 [729](#)
xx.0986.00000 ... xx.0986.65535 [729](#)
xx.0987.00000 ... xx.0987.65535 [730](#)

Error number masked (C00162) [924](#)

Error register (I-1001) [805](#)

Error subject area [697](#), [699](#)

Error type [697](#)

Export error texts [701](#)

Exporting logbook entries [685](#)

Extended status word (C00155) [921](#)

F

Failure indication (C00561) [1009](#)

FB Editor [1329](#)

Functional range [1329](#)

FC01: Switching frequency reduction (error message) [715](#)

FC02: Maximum speed for Fchop (error message) [715](#)

FC03: Field controller limitation (error message) [716](#)

Feed constant [585](#)

Feedback to Lenze [1758](#)

Feedforward control of the current controller [255](#)

FI brake [284](#)

Field weakening for synchronous motors [276](#)

Field weakening oscillation damping (C00236) [941](#)

Fieldbus interface [829](#)

Field-oriented motor currents (C00937) [1125](#)

Filter setpoint feedforward control (C00275) [945](#)

Filter time - earth-fault detect. is running (C01770) [1231](#)

Filter time constant (C00497) [999](#)

Firmware (C00201) [937](#)

Firmware product type (C00200) [936](#)

Firmware update [114](#)

Firmware version (C00099) [907](#)

Firmware version (C00100) [907](#)

Fixed setpoint x (L_NSet_1 n-Fix) (C00039) [896](#)

Flying restart function [264](#)

Activation (C00990) [1135](#)

Current (C00994) [1136](#)

Integration time (C00993) [1135](#)

Process (C00991) [1135](#)

Restart on the fly fd_add (C00989) [1134](#)

Start frequency (C00992) [1135](#)

Following error [597](#)

Following error monitoring system [597](#)

Format error [797](#), [845](#)

FreqIn12

Function (C02844) [1282](#)

PosIn comparison value (C02845) [1282](#)

FreqInxx

Gain (C02843) [1282](#)

Offset (C02842) [1281](#)

FreqInxx_dnOut_p (C00449) [983](#)

FreqInxx_nOut_a (C00446) [982](#)

FreqInxx_nOut_v (C00445) [981](#)

Frequency limitation (C00910) [1122](#)

Function block editor [1329](#)

Function block interconnection [32](#)

Function blocks [1381](#)

Function L_Counter 1-3 (C01100) [1162](#)

Function library [1381](#)

G

Gearbox ratio [584](#)

General data (CAN on board) [750](#)

General purpose functions [546](#)

GP functions (GeneralPurpose) [546](#)

H

Hardware limit switch [592](#)
Heartbeat protocol [798](#)
Heatsink temperature (C00061) [899](#)
Hiperface
 Detected TypCode (C00492) [997](#)
 Resolutions (C00494) [998](#)
 Settings (C00499) [1001](#)
 TypCode (C00493) [998](#)
Hiperface messages (C00491) [997](#)
Holding brake
 Activation time (C02593) [1272](#)
 Operating mode (C02580) [1268](#)
 Setting (C02582) [1270](#)
 Speed thresholds (C02581) [1269](#)
 Status (C02607) [1273](#)
 Time system (C02589) [1271](#)
Holding brake control [655](#)
Homing [606](#)
Homing on the fly [624](#)
HomPosAvailable (status bit) [564](#)

I

I-1000 [805](#)
I-1001 [805](#)
I-1003 [806](#)
I-1005 [807](#)
I-1006 [808](#)
I-1014 [808](#)
I-1016 [809](#)
I-1017 [810](#)
I-1018 [810](#)
I-1200 [811](#)
I-1201 [812](#)
I-1400 [814](#)
I-1401 [815](#)
I-1402 [816](#)
I-1403 [817](#)
I-1600 [818](#)
I-1601 [819](#)
I-1602 [819](#)
I-1603 [820](#)
I-1800 [821](#)
I-1801 [823](#)
I-1802 [824](#)
I-1803 [825](#)
I-1A00 [826](#)
I-1A01 [826](#)
I-1A02 [827](#)
I-1A03 [827](#)
Id1: Motor data identification error (error message) [712](#)
Id2: Motor data identification error (error message) [712](#)
Id3: CINH identification (error message) [712](#)
Id4: Resistance identification error (error message) [712](#)

Id5: Pole position identification error (error message) [714](#)
Id6: Resolver ident. error (error message) [714](#)
Id7: Motor control does not match motor data (error message) [713](#)
Id8: Speed sensor has not been set (error message) [713](#)
Identification procedure (C02867) [1288](#)
Identifier (CAN) [757](#)
Identifiers of the parameter data objects [786](#)
Identifiers of the process data objects [778](#)
Identity (C00219) [938](#)
Identity object (I-1018) [810](#)
Imax controller [162](#)
Imax in generator mode (C00023) [892](#)
Imax in motor mode (C00022) [892](#)
Imax/M controller gain (C00073) [901](#)
Inching mode [625](#)
Initial value motor overload (I²xt) (C00122) [913](#)
Insert options for copied elements [1372](#)
Inserting complete interconnection from reference project [1380](#)
Inserting copied elements [1372](#)
Inserting FB interconnection from reference project [1380](#)
Integrated error detection [797](#)
Internal control signals (C00138) [917](#)
Inversion of gearbox stages (C01067) [1152](#)
Inverter motor brake [284](#)
 nAdd (C00987) [1134](#)
 PT1 filter time (C00988) [1134](#)

J

Jerk limitation [642](#)

K

Keypad [34](#), [36](#)
 Default manual jog (C00453) [985](#)
 Default parameter (C00466) [988](#)
 Default welcome screen (C00467) [988](#)
 Display of internal process factors [1704](#)
 Fct. STOP key (C00469) [989](#)
 LCD display [679](#)
 Set language [38](#)
 Timeout welcome screen (C00465) [988](#)
 Userlevel [37](#)
Keypad analog values (C00728) [1060](#)
Keypad language [38](#)
Keypad Userlevel (C00001) [879](#)
Kp position controller (C00254) [944](#)
KTY motor temperature compensation (C02878) [1292](#)

L

L_Absolut [1386](#)
L_Absolute_1 [1386](#)
L_Absolute_2 [1386](#)
L_AddSub [1387](#)
L_AddSub_1 [1387](#)

- L_AnalogSwitch [1388](#)
- L_AnalogSwitch_1 [1388](#)
- L_AnalogSwitch_2 [1389](#)
- L_AnalogSwitch_3 [1390](#)
- L_AnalogSwitch_4 [1391](#)
- L_AnalogSwitch_5 [1392](#)
- L_And [1393](#)
- L_And_1 [1393](#)
- L_And_2 [1394](#)
- L_And_3 [1395](#)
- L_And5 [1396](#)
- L_And5_1 [1396](#)
- L_And5_2 [1397](#)
- L_Arithmetik [1398](#)
- L_Arithmetik 3-5
 - Function (C00650) [1041](#)
- L_Arithmetik_1 [1398](#)
 - Function (C00338) [951](#)
- L_Arithmetik_2 [1399](#)
 - Function (C00339) [951](#)
- L_Arithmetik_3 [1400](#)
- L_Arithmetik_4 [1401](#)
- L_Arithmetik_5 [1402](#)
- L_ArithmetikPhi [1403](#)
- L_ArithmetikPhi 1-3
 - Function (C01010) [1139](#)
- L_ArithmetikPhi 4-6
 - Function (C01011) [1139](#)
- L_ArithmetikPhi_1 [1403](#)
- L_ArithmetikPhi_2 [1404](#)
- L_ArithmetikPhi_3 [1405](#)
- L_ArithmetikPhi_4 [1406](#)
- L_ArithmetikPhi_5 [1407](#)
- L_ArithmetikPhi_6 [1408](#)
- L_CalcDiameter [1409](#)
- L_CalcDiameter_1 [1409](#)
 - Current diameter (C01057) [1148](#)
 - Diameter recalculation (C01050) [1146](#)
 - Filter time constant (C01051) [1146](#)
 - Status (C01049) [1146](#)
 - Web break monitoring (C01052) [1147](#)
- L_Compare [1414](#)
- L_Compare 4-5
 - Fct. (C00693) [1047](#)
 - Hysteresis (C00694) [1048](#)
 - Window (C00695) [1048](#)
- L_Compare_1 [1414](#)
 - Fct. (C00680) [1045](#)
 - Hysteresis (C00681) [1045](#)
 - Window (C00682) [1046](#)
- L_Compare_2 [1419](#)
 - Fct. (C00685) [1046](#)
 - Hysteresis (C00686) [1046](#)
 - Window (C00687) [1046](#)
- L_Compare_3 [1420](#)
- Fct. (C00690) [1047](#)
- Hysteresis (C00691) [1047](#)
- Window (C00692) [1047](#)
- L_Compare_4 [1421](#)
- L_Compare_5 [1422](#)
- L_ComparePhi [1423](#)
- L_ComparePhi 1-5
 - Function (C01670) [1229](#)
 - Hysteresis (C01671) [1229](#)
 - Window (C01672) [1230](#)
- L_ComparePhi_1 [1423](#)
- L_ComparePhi_2 [1428](#)
- L_ComparePhi_3 [1429](#)
- L_ComparePhi_4 [1430](#)
- L_ComparePhi_5 [1431](#)
- L_ConvActPos [1432](#)
 - Damping (C01468) [1227](#)
 - DeadBand (C01467) [1227](#)
 - DelayTime (C01465) [1226](#)
 - Length (C01462) [1226](#)
 - MaxPos/MinPos (C01461) [1225](#)
 - TConst (C01460) [1225](#)
 - TConstVAdd (C01466) [1227](#)
 - UpperRef/LowerRef (C01463) [1226](#)
 - WindowSetPos (C01464) [1226](#)
- L_ConvActPos_1 [1432](#)
- L_ConvAP [1435](#)
- L_ConvAP 1-3
 - Numerator/denominator (C01045) [1145](#)
- L_ConvAP_1 [1435](#)
- L_ConvAP_2 [1436](#)
- L_ConvAP_3 [1437](#)
- L_ConvBitsToWord [1438](#)
- L_ConvBitsToWord_1 [1438](#)
- L_ConvBitsToWord_2 [1439](#)
- L_ConvBitsToWord_3 [1440](#)
- L_ConvDIntToWords [1441](#)
- L_ConvDIntToWords_1 [1441](#)
- L_ConvDIntToWords_2 [1442](#)
- L_ConvDIntToWords_3 [1443](#)
- L_ConvPA [1444](#)
- L_ConvPA 1-3
 - byDivision (C01046) [1145](#)
- L_ConvPA_1 [1444](#)
- L_ConvPA_2 [1445](#)
- L_ConvPA_3 [1446](#)
- L_ConvPP [1447](#)
- L_ConvPP_1 [1447](#)
- L_ConvPP_2 [1448](#)
- L_ConvPP_3 [1449](#)
- L_ConvUnitsToIncr [1450](#)
- L_ConvUnitsToIncr_1 [1450](#)
- L_ConvUnitsToIncr_2 [1452](#)
- L_ConvUnitsToIncr_3 [1454](#)

L_ConvW [1456](#)
L_ConvW conversion method (C00942) [1126](#)
L_ConvW denominator (C00941) [1126](#)
L_ConvW numerator (C00940) [1125](#)
L_ConvW_1 [1456](#)
L_ConvW_2 [1458](#)
L_ConvW_3 [1459](#)
L_ConvW_4 [1460](#)
L_ConvWordsToDInt [1461](#)
L_ConvWordsToDInt_1 [1461](#)
L_ConvWordsToDInt_2 [1462](#)
L_ConvWordsToDInt_3 [1463](#)
L_ConvWordToBits [1464](#)
L_ConvWordToBits_1 [1464](#)
L_ConvWordToBits_2 [1465](#)
L_ConvWordToBits_3 [1466](#)
L_ConvX [1467](#)
L_ConvX_1 [1467](#)
L_ConvX_2 [1468](#)
L_ConvX_3 [1469](#)
L_Counter [1470](#)
L_Counter_1 [1470](#)
L_Counter_2 [1472](#)
L_Counter_3 [1474](#)
L_Curve [1476](#)
 Current output value (C00959) [1127](#)
L_Curve_1 [1476](#)
 Input limitation (C00961) [1128](#)
 Selected curve type (C00960) [1128](#)
 Table X-values (C00963) [1128](#)
 Table Y-values (C00964) [1129](#)
L_Curve_2 [1480](#)
 Input limitation (C01026) [1141](#)
 Selected curve type (C01025) [1141](#)
 Table X-values (C01028) [1141](#)
 Table Y-values (C01029) [1142](#)
L_Curve_3 [1482](#)
 Input limitation (C01031) [1142](#)
 SelectCurve (C01035) [1143](#)
 Selected curve type (C01030) [1142](#)
 Table X-values (C01033) [1143](#)
 Table Y-values (C01034) [1143](#)
L_DFlipFlop [1487](#)
L_DFlipFlop_1 [1487](#)
L_DFlipFlop_2 [1488](#)
L_DFRFG [1489](#)
L_DFRFG_1 [1489](#)
 Following error (C01078) [1156](#)
 Max. speed-up (C01077) [1155](#)
 Offset (C01080) [1156](#)
 Sync. direction / TP function (C01081) [1156](#)
 Synchronisation window (C01079) [1156](#)
 Times (C01076) [1155](#)

L_DFSET [1498](#)
L_DFSET_1 [1498](#)
 Angular trimming (C01070) [1153](#)
 Following error limit (C01071) [1153](#)
 Multiplier - angular trimming (C01072) [1153](#)
 Ramp settings (C01069) [1153](#)
 Setting (C01073) [1154](#)
 Synchronisation mode (C01075) [1155](#)
 Zero pulse divider (C01074) [1154](#)
L_DigitalDelay [1510](#)
L_DigitalDelay 2..3
 Delay (C00721) [1058](#)
L_DigitalDelay_1 [1510](#)
 Delay (C00720) [1058](#)
L_DigitalDelay_2 [1512](#)
L_DigitalDelay_3 [1513](#)
L_DigitalLogic [1514](#)
L_DigitalLogic_1 [1514](#)
 Function (C00820) [1070](#)
 Truth table (C00821) [1071](#)
L_DigitalLogic_2 [1516](#)
 Function (C00822) [1071](#)
 Truth table (C00823) [1072](#)
L_DigitalLogic_3 [1518](#)
 Function (C00828) [1074](#)
 Truth table (C00829) [1075](#)
L_DigitalLogic5 [1520](#)
L_DigitalLogic5_1 [1520](#)
 Function (C00824) [1072](#)
 Truth table (C00825) [1072](#)
L_DigitalLogic5_2 [1522](#)
 Function (C00826) [1073](#)
 Truth table (C00827) [1073](#)
L_DT1 [1524](#)
L_DT1_1 [1524](#)
 Gain (C00252) [944](#)
 Sensitivity (C00253) [944](#)
 Time constant (C00251) [943](#)
L_FixSet_a [1525](#)
L_FixSet_a_1 [1525](#)
 Analog values (C00660) [1042](#)
L_FixSet_w [1526](#)
L_FixSet_w_1 [1526](#)
 Fixed values (C00661) [1043](#)
L_FixSet_w_2 [1527](#)
 Fixed values (C00662) [1043](#)
L_GainOffset [1528](#)
L_GainOffset_1 [1528](#)
L_GainOffset_2 [1529](#)
L_GainOffset_3 [1530](#)
L_GainOffsetP [1531](#)
L_GainOffsetP 1-3
 Parameter (C00677) [1044](#)
L_GainOffsetP_1 [1531](#)
L_GainOffsetP_2 [1532](#)

- [L_GainOffsetP_3](#) [1533](#)
- [L_GainOffsetPhiP](#) [1534](#)
- [L_GainOffsetPhiP 1-2](#)
 - Parameter (C00678) [1045](#)
- [L_GainOffsetPhiP_1](#) [1534](#)
- [L_GainOffsetPhiP_2](#) [1535](#)
- [L_GearComp](#) [1536](#)
- [L_GearComp_1](#) [1536](#)
 - Num_Denom (C01048) [1146](#)
 - Offset (C01047) [1145](#)
- [L_Interpolator](#) [1538](#)
- [L_Interpolator_1](#) [1538](#)
 - Activation FB functions (C00950) [1126](#)
 - Limit value - error cycles (C00952) [1127](#)
 - No. of interpolation steps (C00951) [1127](#)
 - Speed-up (C00953) [1127](#)
- [L_JogCtrlEdgeDetect_1](#) (C00488) [996](#)
- [L_JogCtrlExtension](#) [1542](#)
- [L_JogCtrlExtension_1](#) [1542](#)
- [L_Limit](#) [1544](#)
- [L_Limit 1-2](#)
 - Min/Max (C00630) [1036](#)
- [L_Limit_1](#) [1544](#)
- [L_Limit_2](#) [1545](#)
- [L_LimitPhi](#) [1546](#)
- [L_LimitPhi 1-3](#)
 - Min/Max (C00631) [1037](#)
- [L_LimitPhi_1](#) [1546](#)
- [L_LimitPhi_2](#) [1547](#)
- [L_LimitPhi_3](#) [1548](#)
- [L_MckCtrlInterface](#) [572](#)
- [L_MckCtrlInterface_1](#) [572](#)
 - Alternative function (C01297) [1197](#)
- [L_MckStateInterface](#) [579](#)
- [L_MckStateInterface_1](#) [579](#)
 - Pos. selection (C01295) [1196](#)
- [L_MFail](#) [1549](#)
 - Tn (C01470) [1228](#)
 - Vp (C01469) [1227](#)
- [L_MFail_1](#) [1549](#)
- [L_MPot](#) [1560](#)
- [L_MPot_1](#) [1560](#)
 - Acceleration time (C00802) [1067](#)
 - Deceleration time (C00803) [1067](#)
 - Inactive fct. (C00804) [1067](#)
 - Init fct. (C00805) [1067](#)
 - Lower limit (C00801) [1067](#)
 - Upper limit (C00800) [1066](#)
 - Use (C00806) [1068](#)
- [L_MulDiv](#) [1564](#)
- [L_MulDiv_1](#) [1564](#)
 - Parameter (C00699) [1049](#)
- [L_MulDiv_2](#) [1565](#)
 - Parameter (C00679) [1045](#)
- [L_Mux](#) [1566](#)
- [L_Mux_1](#) [1566](#)
- [L_Negation](#) [1567](#)
- [L_Negation_1](#) [1567](#)
- [L_Negation_2](#) [1568](#)
- [L_NLim](#) [1569](#)
 - Current status (C00812) [1070](#)
- [L_NLim_1](#) [1569](#)
 - Current output value (C00811) [1069](#)
 - Max.SkipFrq. (C00807) [1068](#)
 - Min.SkipFrq. (C00808) [1068](#)
- [L_NLim_2](#) [1572](#)
 - Max.SkipFrq. (C00809) [1069](#)
 - Min.SkipFrq. (C00810) [1069](#)
- [L_Not](#) [1574](#)
- [L_Not_1](#) [1574](#)
- [L_Not_2](#) [1574](#)
- [L_Not_3](#) [1575](#)
- [L_Not_4](#) [1575](#)
- [L_Not_5](#) [1576](#)
- [L_Not_6](#) [1576](#)
- [L_Not_7](#) [1577](#)
- [L_NSet](#) [1578](#)
- [L_NSet_1](#) [1578](#)
 - Accel. time - add. setpoint (C00220) [939](#)
 - Additional value output (C00639) [1039](#)
 - Decel. time - add. setpoint (C00221) [939](#)
 - Hyst. NSet reached (C00241) [941](#)
 - Max.SkipFrq. (C00632) [1037](#)
 - Min.SkipFrq. (C00633) [1037](#)
 - nMaxLimit (C00635) [1038](#)
 - nMinLimit (C00636) [1038](#)
 - nNOut_a (C00640) [1039](#)
 - Output blocking zones (C00637) [1039](#)
 - Output ramp rounding (C00638) [1039](#)
 - Ramp smoothing (C00134) [914](#)
 - Setpoint arithmetic (C00190) [935](#)
 - S-ramp time PT1 (C00182) [933](#)
 - wState (C00634) [1038](#)
- [L_Odometer](#) [1589](#)
- [L_Odometer_1](#) [1589](#)
 - Edge selection (C01023) [1140](#)
 - Input selection (C01022) [1140](#)
 - Memory length (C01020) [1140](#)
 - Memory type (C01021) [1140](#)
- [L_OffsetGain](#) [1591](#)
- [L_OffsetGain_1](#) [1591](#)
- [L_OffsetGain_2](#) [1592](#)
- [L_OffsetGain_3](#) [1593](#)
- [L_OffsetGainP](#) [1594](#)
- [L_OffsetGainP_1](#) [1594](#)
 - Gain (C00670) [1043](#)
 - Offset (C00696) [1048](#)
- [L_OffsetGainP_2](#) [1595](#)
 - Gain (C00671) [1043](#)
 - Offset (C00697) [1048](#)

- L_OffsetGainP_3 [1596](#)
 - Gain (C00672) [1044](#)
 - Offset (C00698) [1048](#)
- L_OffsetGainPhiP [1597](#)
- L_OffsetGainPhiP 1-2
 - Gain (C00674) [1044](#)
 - Offset (C00673) [1044](#)
- L_OffsetGainPhiP_1 [1597](#)
- L_OffsetGainPhiP_2 [1598](#)
- L_Or [1599](#)
- L_Or_1 [1599](#)
- L_Or_2 [1600](#)
- L_Or_3 [1601](#)
- L_Or_4 [1602](#)
- L_Or5 [1603](#)
- L_Or5_1 [1603](#)
- L_Or5_2 [1604](#)
- L_PCTRL [1605](#)
- L_PCTRL_1 [1605](#)
 - Acceleration time (C00227) [940](#)
 - Acceleration time influence (C00243) [942](#)
 - Deceleration time (C00228) [940](#)
 - Deceleration time influence (C00244) [942](#)
 - Internal actual value nAct_a (C00246) [943](#)
 - Kd (C00224) [939](#)
 - MaxLimit (C00225) [940](#)
 - MinLimit (C00226) [940](#)
 - Operating mode (C00242) [942](#)
 - Operating range (C00231) [940](#)
 - PID output value (C00245) [942](#)
 - Root function (C00233) [941](#)
 - Tn (C00223) [939](#)
 - Vp (C00222) [939](#)
 - Window setpoint reached (C00247) [943](#)
- L_PhaseDiff [1613](#)
- L_PhaseDiff_1 [1613](#)
- L_PhaseDiff_2 [1614](#)
- L_PhaseIntK [1615](#)
 - Compare (C01151) [1170](#)
 - Function (C01150) [1170](#)
- L_PhaseIntK_1 [1615](#)
- L_PhaseIntK_2 [1619](#)
- L_PhiAdd [1621](#)
- L_PhiAdd_1 [1621](#)
- L_PhiDiv [1622](#)
 - byDivision (C01012) [1139](#)
- L_PhiDiv_1 [1622](#)
- L_PhiIntegrator [1623](#)
- L_PhiIntegrator_1 [1623](#)
- L_PosCtrlLin [1627](#)
- L_PosCtrlLin 1-2
 - Limit stop (C01058) [1148](#)
 - Positioning behaviour (C01059) [1148](#)
 - Ramps (C01060) [1149](#)
 - Traversing speeds (C01061) [1149](#)
- L_PosCtrlLin_1 [1627](#)
- L_PosCtrlLin_2 [1630](#)
- L_PosiShaftCtrlInterface [1633](#)
- L_PosiShaftCtrlInterface_1 [1633](#)
- L_ProcessCtrl [1634](#)
- L_ProcessCtrl_1 [1634](#)
 - Controller gain (C01056) [1148](#)
 - Controller times (C01053) [1147](#)
 - Correcting variable limitation (C01055) [1147](#)
 - System deviation (C01054) [1147](#)
- L_PT1 [1638](#)
- L_PT1 2-3
 - Time constant (C00250) [943](#)
- L_PT1_1 [1638](#)
 - Time constant (C00249) [943](#)
- L_PT1_2 [1639](#)
- L_PT1_3 [1640](#)
- L_RLQ [1641](#)
- L_RLQ_1 [1641](#)
- L_RSFlipFlop [1642](#)
- L_RSFlipFlop_1 [1642](#)
- L_RSFlipFlop_2 [1643](#)
- L_SampleHold [1644](#)
- L_SampleHold_1 [1644](#)
- L_SampleHold_2 [1645](#)
- L_Sequencer [1646](#)
- L_Sequencer_1 [1646](#)
 - Aktueller Zählerstand (C01443) [1220](#)
 - Bool signal (C01453) [1224](#)
 - BranchIn (C01415) [1211](#)
 - BranchLevel (C01416) [1212](#)
 - BranchStep (C01417) [1212](#)
 - BranchStep1 (C01418) [1212](#)
 - BranchStep10 (C01427) [1215](#)
 - BranchStep11 (C01428) [1215](#)
 - BranchStep12 (C01429) [1215](#)
 - BranchStep13 (C01430) [1215](#)
 - BranchStep14 (C01431) [1216](#)
 - BranchStep15 (C01432) [1216](#)
 - BranchStep16 (C01433) [1216](#)
 - BranchStep17 (C01434) [1216](#)
 - BranchStep18 (C01435) [1217](#)
 - BranchStep19 (C01436) [1217](#)
 - BranchStep2 (C01419) [1213](#)
 - BranchStep20 (C01437) [1217](#)
 - BranchStep3 (C01420) [1213](#)
 - BranchStep4 (C01421) [1213](#)
 - BranchStep5 (C01422) [1213](#)
 - BranchStep6 (C01423) [1214](#)
 - BranchStep7 (C01424) [1214](#)
 - BranchStep8 (C01425) [1214](#)
 - BranchStep9 (C01426) [1214](#)
 - Current step (C01401) [1205](#)
 - INT signal (C01454) [1224](#)
 - PS_WD_Step (C01410) [1209](#)
 - PS_WD_Time (C01409) [1208](#)

- PSInput (C01405) [1207](#)
- PSLevel (C01406) [1207](#)
- PSProfil (C01407) [1208](#)
- PSStep (C01408) [1208](#)
- SchrittwertZähler (C01445) [1220](#)
- Sequence control
 - Control word (C01403) [1206](#)
 - Status (C01402) [1206](#)
- Sequence step (C01400) [1205](#)
- SetZählernummer (C01441) [1219](#)
- SetZählerStartwert (C01442) [1219](#)
- Standby Eingang f. Ende (C01449) [1222](#)
- Standby Modusfolger (C01451) [1223](#)
- Standby PolaritätEingang (C01450) [1222](#)
- StandbySollwert (C01452) [1223](#)
- Step for bCancel = TRUE (C01404) [1206](#)
- SwitchLevel1 (C01412) [1210](#)
- SwitchLevel2 (C01414) [1211](#)
- SwitchOut1 (C01411) [1209](#)
- SwitchOut2 (C01413) [1210](#)
- Wait Eingang f. Weiter (C01439) [1218](#)
- WaitLevel (C01440) [1219](#)
- Wartezeit (C01438) [1218](#)
- Word signal (C01455) [1225](#)
- ZählerNummer (C01444) [1220](#)
- ZählerSprungziel (C01447) [1221](#)
- ZählerVergleichsfunktion (C01448) [1221](#)
- ZählerVergleichswert (C01446) [1221](#)
- L_SignalMonitor_a [1666](#)
 - Offs./gain (C00413) [969](#)
 - Signal sources (C00410) [968](#)
- L_SignalMonitor_b [1667](#)
 - Inversion (C00412) [969](#)
 - Signal sources (C00411) [969](#)
- L_SignalSwitch [1668](#)
- L_SignalSwitch_1 [1668](#)
- L_SignalSwitch_2 [1669](#)
- L_SignalSwitch_3 [1670](#)
- L_SignalSwitch_4 [1671](#)
- L_SignalSwitch32 [1672](#)
- L_SignalSwitch32_1 [1672](#)
- L_SignalSwitch32_2 [1673](#)
- L_SignalSwitch32_3 [1674](#)
- L_SQrt [1675](#)
- L_SQrt_1 [1675](#)
- L_SRFG [1676](#)
- L_SRFG_1 [1676](#)
- L_SRFG_1..2 limitations of output values (C01042) [1144](#)
- L_SRFG_1..2 linear ramp time (C01040) [1144](#)
- L_SRFG_1..2 S-ramp time (C01041) [1144](#)
- L_SRFG_2 [1678](#)
- L_SwitchPoint [1680](#)
- L_SwitchPoint_1 [1680](#)
 - CenterMode (C01064) [1150](#)
 - Dead time (C01062) [1149](#)
 - Dead time factor (C01108) [1163](#)
- Hysteresis (C01063) [1150](#)
- inversion (C01068) [1152](#)
- Running time (C01065) [1151](#)
- Status (C01066) [1151](#)
- L_SwitchPointPar [1685](#)
- L_SwitchPointPar_1 [1685](#)
 - CenterMode (C01154) [1171](#)
 - Dead time (C01152) [1170](#)
 - Dead time factor (C01109) [1163](#)
 - Hysteresis (C01153) [1171](#)
 - Inversion (C01158) [1174](#)
 - Position (C01157) [1173](#)
 - Running time (C01155) [1172](#)
 - Status (C01156) [1172](#)
- L_Transient [1688](#)
- L_Transient 1-4
 - Function (C01138) [1168](#)
 - Pulse duration (C01139) [1169](#)
- L_Transient 5-8
 - Function (C01140) [1169](#)
- L_Transient 5-8 pulse duration (C01141) [1169](#)
- L_Transient_1 [1688](#)
- L_Transient_2 [1691](#)
- L_Transient_3 [1692](#)
- L_Transient_4 [1693](#)
- L_Transient_5 [1694](#)
- L_Transient_6 [1695](#)
- L_Transient_7 [1696](#)
- L_Transient_8 [1697](#)
- LA_NCtrl [433](#), [462](#)
 - Analog connection list (C00700) [1049](#)
 - Application block [433](#), [462](#)
 - Digital connection list (C00701) [1050](#)
- LA_NCtrl_In [433](#), [462](#)
- LA_NCtrl_Out [433](#), [462](#)
- LA_SwitchPos [522](#)
 - Analog connection list (C00760) [1063](#)
 - Application block [522](#)
 - Digital connection list (C00761) [1064](#)
- LA_SwitchPos_In [522](#)
- LA_SwitchPos_Out [522](#)
- LA_TabPos [494](#)
 - Analog connection list (C00710) [1053](#)
 - Application block [494](#)
 - Digital connection list (C00711) [1054](#)
 - phi connection list (C00712) [1057](#)
- LA_TabPos_In [494](#)
- LA_TabPos_Out [494](#)
- Laser position encoder [341](#)
- Layout of the safety instructions [27](#)
- LCD display (keypad) [679](#)
- LED "AB-STATE" [674](#), [837](#)
- LED "CAN-ERR" [755](#)
- LED "CAN-RUN" [755](#)
- LED "USER" [674](#)

LED status displays [674](#)
L-force »EASY Starter« [33](#)
L-force »Engineer« [33](#)
Library [1381](#)
Limit position monitoring [590](#)
Limit switch [592](#)
Lock bFail at TroubleQSP [130](#)
Logbook - analog elements (C00164) [927](#)
Logbook - binary elements (C00163) [924](#)
Logbook access index User (C00191) [935](#)
Logbook data User (C00192) [935](#)
Logbook element User (C00193) [936](#)
Logbook setting (C00169) [930](#)
LP_CanIn decoupling value (C00343) [954](#)
LP_CanIn mapping (C00407) [967](#)
LP_CanIn mapping (C00409) [968](#)
LP_CanIn mapping selection (C00408) [967](#)
LP_CanIn1 [766](#)
LP_CanIn2 [768](#)
LP_CanIn3 [770](#)
LP_CanIn4 [772](#)
LP_CanOut decoupling value (C00344) [955](#)
LP_CanOut1 [774](#)
LP_CanOut2 [775](#)
LP_CanOut3 [776](#)
LP_CanOut4 [777](#)
LP_MciIn [833](#)
LP_MciOut [834](#)
LP1: Motor phase failure (error message) [716](#)
LS_AnalogIn1
 PT1 time constant (C00440) [978](#)
LS_AnalogInput [409](#)
LS_AnalogOutput [410](#)
LS_AxisBusAux [849](#)
LS_AxisBusIn [848](#)
LS_AxisBusIO [856](#)
LS_AxisBusOut [847](#)
LS_Brake [656](#)
LS_CANManagement [828](#)
LS_DeviceMonitor [311](#)
LS_DFOut [348](#)
 Angular offset (C00545) [1008](#)
 Const. (C00030) [894](#)
 Function (C00540) [1008](#)
LS_DigitalInput [390](#)
LS_DigitalOutput [400](#)
LS_DisFree [1702](#)
LS_DisFree (C00481) [994](#)
LS_DisFree_a [1703](#)
LS_DisFree_a (C00482) [994](#)
LS_DisFree_b [1705](#)
LS_DisFree_b (C00480) [993](#)
LS_DisFree_p [1706](#)
LS_DisFree_p (C00483) [994](#)

LS_DriveInterface [127](#)
 bNActCompare (C00024) [893](#)
 Error message config. (C00148) [919](#)
LS_Keypad [1707](#)
LS_Keypad digital values(C00727) [1060](#)
LS_MotionControlKernel [554](#)
LS_MotorInterface [305](#)
LS_MultiEncoder [349](#)
 bFail information (C00451) [984](#)
 bFail selection (C00431) [975](#)
 Current position (C01119) [1165](#)
 Encoder constant (C01111) [1164](#)
 Encoder type (C00422) [971](#)
 Max. initialization time (C00430) [974](#)
 Position values (C01112) [1164](#)
 Solid measure (C01110) [1164](#)
 Supply voltage (C00421) [970](#)
LS_ParFix [1709](#)
LS_ParFix_2 [1709](#)
LS_ParFree [1710](#)
LS_ParFree (C00471) [989](#)
LS_ParFree_2 [1711](#)
LS_ParFree_2 (C00477) [992](#)
LS_ParFree_a [1712](#)
LS_ParFree_a (C00472) [990](#)
LS_ParFree_a_2 [1713](#)
LS_ParFree_a_2 (C00476) [992](#)
LS_ParFree_b [1714](#)
LS_ParFree_b (C00470) [989](#)
LS_ParFree_p [1715](#)
LS_ParFree_p (C00474) [991](#)
LS_ParFree_v [1716](#)
LS_ParFree_v (C00473) [990](#)
LS_ParFree_v_2 [1717](#)
LS_ParFree_v_2 (C00478) [993](#)
LS_ParFree32 [1718](#)
LS_ParFree32 (C00479) [993](#)
LS_ParFreeUnit [1719](#)
LS_ParFreeUnit_1_2 (C00475) [991](#)
LS_ParFreeUnit_2 [1720](#)
LS_ParReadWrite [1721](#)
LS_ParReadWrite 1-6
 Arithmetic mode (C01093) [1161](#)
 Cycle time (C01091) [1160](#)
 Denominator (C01095) [1162](#)
 FailState (C01092) [1160](#)
 Index (C01090) [1159](#)
 Numerator (C01094) [1161](#)
LS_ParReadWrite_1 [1721](#)
LS_ParReadWrite_2 [1721](#)
LS_ParReadWrite_3 [1721](#)
LS_ParReadWrite_4 [1721](#)
LS_ParReadWrite_5 [1721](#)
LS_ParReadWrite_6 [1721](#)
LS_PulseGenerator [1725](#)

- LS_PulseGenerator (C00400) [966](#)
- LS_Resolver [324](#)
 - bFail information (C00452) [985](#)
 - bFail selection (C00432) [976](#)
 - Number of pole pairs (C00925) [1124](#)
- LS_RetainData [1727](#)
 - 16Bit data (C01131) [1167](#)
 - 32Bit data (C01132) [1168](#)
 - Bool data (C01133) [1168](#)
 - Selection (C01130) [1167](#)
- LS_SetError_1 [731](#)
- LS_SetError_2 [732](#)
- LS_SetError_x
 - Error number (C00161) [924](#)
- LS_SyncManagement [858](#)
- LS_TouchProbe [417](#)
- LS_WriteParamList [870](#)
 - Auto-DCB
 - Hold time (C02244) [1244](#)
 - Threshold (C02215) [1235](#)
 - DC braking
 - Current (C02219) [1236](#)
 - Hold time (C02245) [1245](#)
 - Empfindlichkeit Sollwertvorsteuerung (C02264) [1248](#)
 - Error line (C01084) [1157](#)
 - Error status (C01083) [1157](#)
 - Execute Mode (C01082) [1157](#)
 - Field weakening oscillation damping (C02251) [1246](#)
 - Flying restart function
 - Activation (C02295) [1256](#)
 - Current (C02299) [1257](#)
 - Integration time (C02298) [1257](#)
 - Process (C02296) [1256](#)
 - Start frequency (C02297) [1256](#)
 - Frequency limitation (C02274) [1250](#)
 - Function (C02200) [1232](#)
 - I_{max} in generator mode (C02218) [1236](#)
 - I_{max} in motor mode (C02217) [1235](#)
 - I_{max}/M controller gain (C02223) [1238](#)
 - Index (C01085) [1157](#)
 - Inverter motor brake
 - nAdd (C02293) [1255](#)
 - PT1 filter time (C02294) [1255](#)
 - Kp position controller (C02252) [1246](#)
 - Manual entry of motor type (C02315) [1263](#)
 - Max. motor speed (C02280) [1251](#)
 - Moment of inertia (C02256) [1247](#)
 - Motor cable cross-section (C02276) [1250](#)
 - Motor cable length (C02275) [1250](#)
 - Motor control (C02210) [1233](#)
 - Motor cosine phi (C02240) [1243](#)
 - Motor magnetising current (C02242) [1244](#)
 - Motor magnetising inductance (C02241) [1244](#)
 - Motor phase direction of rotation (C02272) [1249](#)
 - Motor rotor resistance (C02232) [1241](#)
 - Motor stator leakage inductance (C02234) [1242](#)
 - Motor stator resistance (C02233) [1241](#)
 - Oscillation damping filter time (C02250) [1246](#)
 - Oscillation damping influence (C02249) [1245](#)
 - Override point of field weakening (C02230) [1240](#)
 - PLI without motion
 - Adaptation of ident angle (C02313) [1262](#)
 - Adaptation of time duration (C02311) [1261](#)
 - PLI without motion (C02312) [1262](#)
 - PSM
 - Activate Lss sat. char. (C02307) [1261](#)
 - I_{max} Lss saturation characteristic (C02306) [1261](#)
 - Lss saturation characteristic (C02305) [1259](#)
 - Maximum motor current field weakening (C02278) [1251](#)
 - Rated motor current (C02237) [1242](#)
 - Rated motor frequency (C02238) [1243](#)
 - Rated motor power (C02231) [1241](#)
 - Rated motor speed (C02236) [1242](#)
 - Rated motor voltage (C02239) [1243](#)
 - Reset time I_{max}/M controller (C02224) [1238](#)
 - SC
 - Field feedforward control (C02261) [1247](#)
 - Settings (C02229) [1240](#)
 - T_{dn} speed controller (C02222) [1237](#)
 - T_n field controller (C02228) [1239](#)
 - T_n field weakening controller (C02263) [1248](#)
 - V_p field controller (C02227) [1239](#)
 - V_p field weakening controller (C02262) [1248](#)
 - Setting of motor overload (I²xt) (C02246) [1245](#)
 - Slip comp. (C02216) [1235](#)
 - SLPSM
 - Controlled current setpoint (C02300) [1257](#)
 - Filter cutoff frequency (C02302) [1258](#)
 - Filter time rotor position (C02303) [1258](#)
 - PLL gain (C02304) [1259](#)
 - Switching speed (C02301) [1258](#)
 - SLVC
 - Cross current controller gain (C02292) [1255](#)
 - Field current controller gain (C02291) [1254](#)
 - Speed limitation (C02273) [1249](#)
 - Speed sensor selection (C02260) [1247](#)
 - Switching frequency (C02214) [1234](#)
 - Ti current controller (C02226) [1239](#)
 - Ti speed controller (C02221) [1237](#)
 - Ultimate motor current (C02279) [1251](#)
 - VFC
 - Limitation V/f + sensor (C02284) [1252](#)
 - Ti V/f +sensor (C02286) [1253](#)
 - Time const. slip comp. (C02281) [1252](#)
 - V/f base frequency (C02212) [1233](#)
 - V_{min} boost (C02213) [1234](#)
 - V_p V/f +sensor (C02285) [1252](#)
 - VFC-ECO
 - Minimum voltage V/f (C02289) [1254](#)
 - Ti CosPhi controller (C02288) [1253](#)
 - Voltage reduction ramp (C02290) [1254](#)
 - V_p CosPhi controller (C02287) [1253](#)
 - V_p current controller (C02225) [1238](#)
 - V_p speed controller (C02220) [1236](#)
 - WriteValue_1 (C01086) [1158](#)

WriteValue_2 (C01087) [1158](#)
WriteValue_3 (C01088) [1158](#)
WriteValue_4 (C01089) [1159](#)
LU: DC bus undervoltage (error message) [709](#)

M

Machine parameters [582](#)
Main program runtime (C00321) [949](#)
Mains connection (behaviour) [124](#)
Mains phase failure monitoring [303](#)
Mains voltage (C00173) [931](#)
Manual control [58](#)
Manual DC-injection braking (DCB) [268](#)
Manual entry of motor type (C01001) [1138](#)
Manual jog [625](#)
 Setting (C01230) [1185](#)
Manual jog to software limit position [631](#)
Manual motor direction of rotation check [58](#)
Master functionality (CAN) [763](#)
MasterPin [50](#)
Max. motor speed (C00965) [1129](#)
Max. number of AutoFailReset processes (C00186) [933](#)
Maximum current monitoring [303](#)
Maximum torque (C00057) [898](#)
Maximum torque monitoring [304](#)
Maximum travel distance [596](#)
MCI input words (C00876) [1120](#)
MCI output words (C00877) [1121](#)
MCI_InOut
 Inversion (C00890) [1121](#)
MCK [552](#)
 Accel./decel. times (C02610) [1274](#)
 Control word (C01240) [1189](#)
 Current operating mode (C01243) [1192](#)
 Current pos profile number (C01242) [1192](#)
 Current positions (C01210) [1177](#)
 Cycle (C01201) [1175](#)
 Diagnostic word (C01247) [1194](#)
 Feed constant (C01204) [1176](#)
 Follower accelerations (C01237) [1188](#)
 Follower speeds (C01236) [1187](#)
 Follower S-ramp times (C01238) [1188](#)
 Following error (C01215) [1178](#)
 iG motor/position encoder (C01203) [1176](#)
 iM motor/process (C01202) [1176](#)
 Limitations (C02611) [1274](#)
 Manual jog accelerations (C01232) [1186](#)
 Manual jog breakpoints (C01234) [1187](#)
 Manual jog speeds (C01231) [1186](#)
 Manual jog S-ramp time (C01233) [1186](#)
 Manual jog waiting times (C01235) [1187](#)
 Max. travel distance [596](#)
 Max. traversing distance (C01213) [1178](#)
 Mounting direction (C01206) [1177](#)
 Operating mode change at profile no. (C01298) [1198](#)
 Position follower setting (C01218) [1180](#)

Position limiting values (C01229) [1185](#)
Position resolution (C01205) [1176](#)
Positioning setting (C01216) [1179](#)
Ref speeds (C01224) [1183](#)
Ref. accelerations (C01225) [1183](#)
Ref. M limit mode 14/15 (C01222) [1182](#)
Ref. mode (C01221) [1182](#)
Ref. positions (C01227) [1184](#)
Ref. sequence profile (C01228) [1184](#)
Ref. setting (C01220) [1181](#)
Ref. S-ramp time (C01226) [1184](#)
Ref. waiting time mode 14/15 (C01223) [1183](#)
Resp. to MCK error (C00595) [1018](#)
Select signal source (C01246) [1194](#)
Speed (C01211) [1178](#)
Speed follower setting (C01219) [1180](#)
Status word (C01241) [1191](#)
Stop accelerations (C01251) [1195](#)
Stop S-ramp times (C01252) [1196](#)
Target detection - positions (C01245) [1193](#)
Target detection - times (C01244) [1193](#)
MCK control word [560](#)
MCK interface [570](#)
MCK state machine [566](#)
MCK status bit "HomPosAvailable" [564](#)
MCK status bit "S_ShapingActive" [565](#)
MCK status word [562](#)
MCKI
 Status MCKInterface (C01299) [1198](#)
MCTRL
 Actual speed value (C00051) [896](#)
 Optimisations (C02864) [1284](#)
 Special settings (C02865) [1286](#)
 Special settings (C02866) [1287](#)
 Speed setpoint (C00050) [896](#)
 Status (C01000) [1138](#)
Memory module [40](#)
 Binding ID [48](#)
Min/max speed [589](#)
Mode
 Position calculation (C01294) [1196](#)
 Position calculation (C01296) [1197](#)
Modulo measuring system [586](#)
Moment of inertia from load (C00919) [1124](#)
Moment of inertia motor (C00273) [945](#)
Monitoring [292](#), [689](#)
Monitoring of the maximum travel distance [596](#)
Motion Control Kernel (MCK) [552](#)
Motor cable cross-section (C00916) [1123](#)
Motor cable length (C00915) [1123](#)
Motor cable resistance (C00917) [1123](#)
Motor catalogue [139](#)
Motor control [134](#)
 87-Hz operation [165](#)
 DC-injection braking [267](#)
 Energy-saving V/f characteristic control (VFCplusEco) [176](#)

Flying restart function [264](#)
Oscillation damping [272](#)
Selection help [153](#)
Selection of switching frequency [256](#)
Selection of the control type [149](#)
Sensorless vector control (SLVC) [193](#)
Servo control (SC) [226](#)
Slip compensation [271](#)
V/f characteristic control (VFCplus) [157](#)
V/f control (VFCplus + encoder) [186](#)
Motor control (C00006) [883](#)
Motor cosine phi (C00091) [906](#)
Motor current (C00054) [897](#)
Motor data [135](#)
Motor data changeover [859](#)
Motor data parameter list [859](#)
Motor holding brake [655](#)
Motor load monitoring (I2xt) [294](#)
Motor magnetising current (C00095) [906](#)
Motor magnetising inductance (C00092) [906](#)
Motor overcurrent monitoring [296](#)
Motor parameter identification [141](#)
Motor parameter identification is active [116](#)
Motor phase direction of rotation (C00905) [1122](#)
Motor phase error monitoring before operation [301](#)
Motor phase failure monitoring [300](#)
Motor phase failure threshold (C00599) [1019](#)
Motor rotor position (C00060) [898](#)
Motor rotor position (C00927) [1124](#)
Motor rotor resistance (C00082) [904](#)
Motor rotor time constant (C00083) [904](#)
Motor selection [135](#)
Motor speed monitoring [304](#)
Motor stator leakage inductance (C00085) [904](#)
Motor stator resistance (C00084) [904](#)
Motor temp. feedback system (C01193) [1175](#)
Motor temperature (C00063) [899](#)
Motor temperature monitoring (PTC) [297](#)
Motor thermal sensor (C01190) [1174](#)
Motor voltage (C00052) [897](#)
Motorparameter (C00969) [1131](#)
Multilingualism [38](#)

N

Network management telegram (NMT) [762](#)
NMT (network management) [762](#)
Node address [758](#)
Node ID [758](#)
Number of CAN SDO channels (C00366) [962](#)
Number of encoder increments (C00420) [970](#)

O

oC1: Power section - short circuit (error message) [709](#)
oC10: Maximum current reached (error message) [711](#)
oC11: Clamp operation active (error message) [713](#)
oC12: I2xt overload - brake resistor (error message) [713](#)
oC13: Maximum current for Fch exceeded (error message) [714](#)
oC14: Direct-axis current controller limitation (error message) [715](#)
oC15: Cross current controller limitation (error message) [715](#)
oC16: Torque controller limitation (error message) [715](#)
oC17: Clamp sets pulse inhibit (error message) [711](#)
oC2: Power section - earth fault (error message) [710](#)
oC5: Ixt overload (error message) [708](#)
oC6: I2xt overload - motor (error message) [716](#)
oC7 [296](#)
oC7: Motor overcurrent (error message) [708](#)
oH1: Heatsink overtemperature (error message) [706](#)
oH12: Motor overtemperature MultiEncoder (error message) [707](#)
oH3: Motor temperature (X106) triggered (error message) [707](#)
oH4: Heatsink temp. > shutdown temp. -5°C (error message) [706](#)
oH6: Motor temperature MultiEncoder >= C121 (error message) [707](#)
oH7: Motor temperature resolver >= C121 (error message) [706](#)
oH9: Motor overtemperature resolver (error message) [707](#)
Open-circuit monitoring
HTL encoder [370](#)
Open-circuit monitoring (C00498) [1000](#)
Operating conditions (CAN on board) [750](#)
Operating mode
Homing [606](#)
Manual jog [625](#)
Position follower [649](#)
Positioning [633](#)
Speed follower [604](#)
StandBy [567](#)
Stop [648](#)
Operating mode change with profile number [578](#)
Operation with increased rated power [260](#)
Operation with safety module [568](#)
Optical location [112](#)
Optimising the response to setpoint changes (SC) [241](#)
Optimising the response to setpoint changes (SLVC) [203](#)
Option "Lock bFail at TroubleQSP" [130](#)
Original application|control source (C00008) [887](#)
oS1: Maximum speed limit reached (error message) [711](#)
oS2: Max. motor speed (error message) [712](#)
Oscillation damping [272](#)
Oscillation damping filter time (C00235) [941](#)
Oscillation damping influence (C00234) [941](#)
Oscilloscope function [733](#)
ot1: Maximum torque reached (error message) [708](#)
ot2: Speed controller output limited (error message) [714](#)

oU: DC bus overvoltage (error message) [709](#)
Output frequency (C00058) [898](#)
Output power (C00980) [1133](#)
Overcharge [639](#)
Override [651](#)
Override point of field weakening (C00080) [903](#)
OxI
 Current (C00437) [977](#)
OxU
 Voltage (C00436) [977](#)
OxU/I
 Gain (C00434) [976](#)
 Input value (C00439) [978](#)
 Offset (C00435) [977](#)
P
Parameter change-over [859](#)
Parameterisable function blocks [1332](#)
Password data (C00505) [1001](#)
Password protection [44](#)
PC manual control [90](#)
PDO mapping [766](#), [768](#), [770](#), [772](#)
PDO synchronisation [782](#)
Peak current limitation [154](#)
Phase sequence reversal [275](#)
Plant parameters [140](#)
PLI current amplitude (C00646) [1040](#)
PLI max. permissible deflection (C00645) [1040](#)
PLI ramp time (C00647) [1040](#)
PLI traversing direction (C00644) [1040](#)
PLI without motion
 Adaptation of ident angle (C02875) [1290](#)
 Adaptation of time duration (C02872) [1289](#)
 Ident. el. rotor displ. angle (C02873) [1289](#)
 Optimisation factor (C02870) [1288](#)
 Running time (C02871) [1288](#)
PLI without motion (C02874) [1290](#)
Pole position (C00926) [1124](#)
Pole position identification (PPI) [358](#)
Pole position identification without motion [364](#)
Port block "LP_CanIn1" [766](#)
Port block "LP_CanIn2" [768](#)
Port block "LP_CanIn3" [770](#)
Port block "LP_CanIn4" [772](#)
Port block "LP_CanOut1" [774](#)
Port block "LP_CanOut2" [775](#)
Port block "LP_CanOut3" [776](#)
Port block "LP_CanOut4" [777](#)
PosExecute (control bit) [577](#)
PosExecute control bit [577](#)
Position control [280](#)
Position encoder selection (C00490) [997](#)
Position follower [649](#)
Position teaching [647](#)

Positioning [633](#)
Positioning modes [640](#)
Power section ID (C00093) [906](#)
Power-on time meter (C00179) [932](#)
Pre-defined error field (I-1003) [806](#)
Printing the interconnection [1375](#)
Process data objects, identifiers [778](#)
Processing time [752](#)
Producer heartbeat time (I-1017) [810](#)
Product type code (C00203) [937](#)
Profile data
 Acceleration (C01303) [1200](#)
 Deceleration (C01304) [1201](#)
 Final speed (C01305) [1201](#)
 Position (C01301) [1200](#)
 Positioning mode (C01300) [1199](#)
 Sequence profile (C01307) [1202](#)
 Speed (C01302) [1200](#)
 S-ramp time (C01306) [1201](#)
 TP profile (C01308) [1202](#)
 TP signal source (C01309) [1202](#)
Profile entry [637](#)
Profile generator (L_DFRFG) [1489](#)
Profile linkage with velocity changeover (overchange) [639](#)
PS01: No memory module (error message) [721](#)
PS02: Par. set invalid (error message) [721](#)
PS03: Par. set device invalid (error message) [721](#)
PS04: Par. set Mci invalid (error message) [722](#)
PS07: Par. memory module invalid (error message) [722](#)
PS08: Par. device invalid (error message) [722](#)
PS09: Par. format invalid (error message) [722](#)
PS10: Memory module binding invalid (error message) [722](#)
PSM
 Activate Lss sat. char. (C02859) [1283](#)
 Imax Lss saturation characteristic (C02855) [1283](#)
 Lss saturation characteristic (C02853) [1283](#)
 Max. motor temperature (C02876) [1291](#)
 Maximum motor current field weakening (C00938) [1125](#)
PSM temperature coefficient (C02877) [1291](#)
PTC [297](#)
PTC characteristic
 Resistance 1/2 (C01192) [1175](#)
 Temperature 1/2 (C01191) [1175](#)
Pulse form TTL-Encoder (C00424) [971](#)
PW protection config MCI (C00510) [1006](#)
PW protection config X1(CAN) (C00509) [1005](#)
PW protection config X6(DIAG) (C00508) [1004](#)
PW protection internal config (C00506) [1002](#)

Q

Quick stop setting (C00104) [909](#)

R

Ramp function generator (L_DFRFG) [1489](#)
Rated device current (C00098) [907](#)
Rated heat amount of brake resist. (C00131) [914](#)
Rated motor current (C00088) [905](#)
Rated motor frequency (C00089) [905](#)
Rated motor power (C00081) [904](#)
Rated motor speed (C00087) [905](#)
Rated motor torque (C00097) [906](#)
Rated motor voltage (C00090) [905](#)
Rated power - brake resistor (C00130) [914](#)
Reduc. brake chopper threshold (C00174) [931](#)
Reference project [1380](#)
Reference setting [606](#)
Referencing mode [609](#)
Remote
 Acceleration/deceleration time (C00461) [986](#)
 Control (C00462) [986](#)
 MCK control (C00463) [987](#)
 Monitoring timeout (C00464) [988](#)
 Setpoint selection (C00729) [1060](#)
Reset error message [700](#)
Reset node (CAN) [756](#)
Reset reference information [564](#)
Reset time I_{max}/M controller (C00074) [902](#)
Resolver
 Phase error (C02863) [1284](#)
Resolver gain (C02862) [1284](#)
Resp. to axis bus error (C00591) [1015](#)
Resp. to brake resist. overtemp. (C00574) [1011](#)
Resp. to CAN bus connection (C00592) [1016](#)
Resp. to CANx_IN monitoring (C00593) [1016](#)
Resp. to communication error with MCI (C01501) [1228](#)
Resp. to control word error (C00594) [1017](#)
Resp. to controller limitations (C00570) [1010](#)
Resp. to DC-bus voltage (C00600) [1020](#)
Resp. to device overload (I_{xt}) (C00604) [1021](#)
Resp. to earth fault (C00602) [1020](#)
Resp. to fan failure (C00566) [1009](#)
Resp. to feedback (C00603) [1021](#)
Resp. to feedback (C00605) [1022](#)
Resp. to heatsink temp. > shutdown temp. -5°C (C00582) [1013](#)
Resp. to LS_SetError_x (C00581) [1013](#)
Resp. to mains phase failure (C00565) [1009](#)
Resp. to max. freq. feedb. DIG12/67 (C00607) [1022](#)
Resp. to max. speed at switching freq. (C00588) [1015](#)
Resp. to max. speed/output freq. reached (C00579) [1012](#)
Resp. to maximum current (C00609) [1023](#)
Resp. to maximum torque (C00608) [1022](#)
Resp. to motor overload (I_{xt}) (C00606) [1022](#)
Resp. to motor overtemp. PTC (C00585) [1014](#)
Resp. to motor phase failure (C00597) [1019](#)
Resp. to motor temperature KTY (C00583) [1014](#)
Resp. to open circuit AINx (C00598) [1019](#)

Resp. to open circuit HTL encoder (C00586) [1014](#)
Resp. to operating system error (C00580) [1012](#)
Resp. to peak current (C00569) [1010](#)
Resp. to PLI monitoring (C00643) [1039](#)
Resp. to speed controller limited (C00567) [1009](#)
Resp. to switching frequency reduction (C00590) [1015](#)
Resp. to too frequent AutoFailReset (C00189) [934](#)
Resp. to wrong controller setting (C00571) [1011](#)
Retracting from limit switches [632](#)
Reversing the phase sequence [275](#)
Rotary table application [586](#)
Rotor displacement angle detection after controller enable [364](#)
RPDO1 communication parameter (I-1400) [814](#)
RPDO1 mapping parameter (I-1600) [818](#)
RPDO2 communication parameter (I-1401) [815](#)
RPDO2 mapping parameter (I-1601) [819](#)
RPDO3 communication parameter (I-1402) [816](#)
RPDO3 mapping parameter (I-1602) [819](#)
RPDO4 communication parameter (I-1403) [817](#)
RPDO4 mapping parameter (I-1603) [820](#)
Running time (C00180) [932](#)

S

S_ShapingActive (status bit) [565](#)
Safe stop 1 [568](#)
Safety functions [568](#)
Safety instructions [27](#)
Safety module [568](#)
Saturation characteristic [262](#)
SC
 Depth of current setpoint filter (C00272) [945](#)
 Filter time const. DC detection (C00280) [946](#)
 Freq. current setpoint filter (C00270) [944](#)
 Max. acceleration change (C00274) [945](#)
 max. output voltage (C00276) [946](#)
 Optimisation of field feedforward control (C00576) [1011](#)
 Settings (C00079) [903](#)
 Start motor magnetising current (C00918) [1123](#)
 T_{dn} speed controller (C00072) [901](#)
 T_n field controller (C00078) [903](#)
 T_n field weakening controller (C00578) [1012](#)
 V_p field controller (C00077) [902](#)
 V_p field weakening controller (C00577) [1012](#)
 Width of current setpoint filter (C00271) [945](#)
Scaling of physical units [1335](#)
Sd10: Speed limit for feedback system 12 (error message) [716](#)
Sd11: Speed limit for feedback system 67 (error message) [716](#)
Sd12: Error thermal detector MultiEncoder (error message) [708](#)
Sd13: Inaccuracy SinCos (error message) [717](#)
Sd14: Position invalid Hiperface (error message) [711](#)
Sd2: Open circuit resolver (error message) [710](#)
Sd3: Feedback system open circuit (error message) [717](#)
Sd4: Open circuit MultiEncoder (error message) [710](#)
Sd6: Error thermal detector resolver (error message) [707](#)
Sd7: Encoder communication (error message) [710](#)

- Sd8: Encoder angular drift monit. (error message) [713](#)
- Sd9: Status message Hiperface (error message) [711](#)
- SDO1 server parameter (I-1200) [811](#)
- SDO2 server parameter (I-1201) [812](#)
- Selection help for motor control [153](#)
- Selection of switching frequency [256](#)
- Selection of the control type [149](#)
- Sensibility - Setpoint feedforward control (C00653) [1041](#)
- Sensorless control for synchronous machines (SLPSM) [151](#)
- Sensorless vector control (SLVC) [151](#), [193](#)
- Sequence control [1646](#)
- Serial number (C00204) [938](#)
- Servo control (SC) [151](#), [226](#)
- Setpoint holding (C01239) [1188](#)
- Setpoint synchronisation ramp [589](#)
- Setting of motor overload (I²t) (C00120) [912](#)
- Setting the baud rate [754](#)
- Setting the error response [691](#)
- Setting the node address [754](#)
- Settings of measuring system (C02652) [1275](#)
- Short overview of error messages [702](#)
- Signal flow
 - Energy-saving V/f characteristic control (VFCplusEco) [177](#), [211](#)
 - Sensorless vector control (SLVC) [195](#)
 - Servo control (SC) for ASM [230](#)
 - Servo control (SC) for PSM [228](#)
 - V/f characteristic control (VFCplus) [158](#), [159](#)
 - V/f control (VFCplus + encoder) [187](#), [188](#), [194](#)
- Signal type entry [1335](#)
- Slip calculation from equivalent circuit diagram (C02879) [1293](#)
- Slip comp. (C00021) [892](#)
- Slip compensation [271](#)
- Slip regulator [190](#)
- SLPSM
 - Controlled current setpoint (C00995) [1136](#)
 - Filter cutoff frequency (C00997) [1136](#)
 - Filter time rotor position (C00998) [1137](#)
 - PLL gain (C00999) [1137](#)
 - Switching speed (C00996) [1136](#)
- SLVC
 - Cross current controller gain (C00986) [1134](#)
 - Field current controller gain (C00985) [1134](#)
- Software limit positions [590](#)
- Source of diff. setpoint feedforward control (C00654) [1042](#)
- Speed control with torque limitation (SC) [232](#)
- Speed control with torque limitation (SLVC) [196](#)
- Speed feedback [152](#)
- Speed follower [604](#)
- Speed limitation (C00909) [1122](#)
- Speed override [652](#)
- Speed sensor selection (C00495) [998](#)
- Speed setpoint generation [589](#)
- S-ramp smoothing override [654](#)
- S-ramp time for jerk limitation [642](#)
- SS1 [568](#)
- SSI encoder
 - Bit rate (C00427) [973](#)
 - Coding (C00428) [974](#)
 - Data bits (C00426) [973](#)
- SSI laser position encoder [341](#)
- StandBy (MCK operating mode) [567](#)
- State machine (MCK) [566](#)
- Status "Drive in target" [594](#)
- Status "Reference known" [564](#)
- Status determining error (16-bit) (C00160) [923](#)
- Status determining error (C00168) [929](#)
- Status displays [674](#)
- Status of brake output BD (C00117) [912](#)
- Status of last device command (C00003) [882](#)
- Status word (C00150) [920](#)
- Status word (MCK) [562](#)
- Stop [648](#)
- Stop of the ramp function generator [284](#)
- Stop the ramp function generator [284](#)
- Stuff-bit error [797](#), [845](#)
- Su02: One mains phase is missing (error message) [705](#)
- Su03: Too frequent mains switching (error message) [705](#)
- Su04: CU insufficiently supplied (error message) [706](#)
- Su06: Mains input overload (error message) [706](#)
- Switching cycles (C00177) [932](#)
- Switching freq. reduct. (Temp.) (C00144) [918](#)
- Switching frequency [256](#)
- Switching frequency (C00018) [891](#)
- Switching status of the fans (C00560) [1008](#)
- Switch-on inhibit [124](#)
- Sync correction width (C01124) [1166](#)
- Sync cycle time setpoint (C01121) [1165](#)
- Sync phase position (C01122) [1166](#)
- Sync signal source (C01120) [1165](#)
- Sync telegram [782](#)
- Sync window (C01123) [1166](#)
- Synchronisation mode [1506](#)
- Synchronous motor
 - Field weakening [276](#)
- SyncTxRxTimes (C00370) [964](#)
- System blocks [1698](#)
- System bus [749](#)
- System connection list
 - 16-bit (C00620) [1024](#)
 - Angle (C00622) [1035](#)
 - Bool (C00621) [1028](#)
- System fault messages [696](#)
- System runtimes (C00312) [948](#)

T

Target group [23](#)
Target position monitoring [594](#)
Task selection [1339](#)
Teaching of the position [647](#)
Technology applications [30](#)
Temperature inside the controller (C00062) [899](#)
Terminals [376](#)
 Analog terminals [401](#)
 Digital input terminals [377](#)
 Digital output terminals [398](#)
 For electrical data see the hardware manual
 User-defined terminal assignment [421](#)
Thermal motor load (I²xt) (C00066) [900](#)
Ti current controller (C00076) [902](#)
Ti speed controller (C00071) [901](#)
Time settings (C00181) [933](#)
Torque (C00056) [898](#)
Torque control with speed limitation (SC) [234](#)
Torque control with speed limitation (SLVC) [197](#)
Torque feedforward control (SC) [241](#)
Torque feedforward control (SLVC) [203](#)
Torque limitation [170](#)
Touch probe detection [411](#)
TP
 Edge selection (C02810) [1276](#)
 Pos. window end (C02814) [1278](#)
 Pos. window start (C02813) [1277](#)
 Position offset (C02812) [1277](#)
 Position source (C02815) [1278](#)
 Sensor delay (C02811) [1276](#)
 Signal counter (C02816) [1279](#)
 TouchProbe position (C02817) [1279](#)
TP (touch probe) [411](#)
TPDO1 communication parameter (I-1800) [821](#)
TPDO1 mapping parameter (I-1A00) [826](#)
TPDO2 communication parameter (I-1801) [823](#)
TPDO2 mapping parameter (I-1A01) [826](#)
TPDO3 communication parameter (I-1802) [824](#)
TPDO3 mapping parameter (I-1A02) [827](#)
TPDO4 communication parameter (I-1803) [825](#)
Transmission mode CAN Rx PDOs (C00323) [950](#)
Transmission mode CAN TxPDOs (C00322) [949](#)
Transmission type [780](#)
Travel range monitoring [592](#)

U

Ultimate motor current [296](#)
Ultimate motor current (C00939) [1125](#)
USB diagnostic adapter [34](#)
User data [786](#)
User error 1 (error message) [728](#)
User error 2 (error message) [729](#)
User error 3 (error message) [729](#)

User error 4 (error message) [729](#)
User error 5 (error message) [729](#)
User error 6 (error message) [729](#)
User error 7 (error message) [729](#)
User error 8 (error message) [730](#)
User menu (C00517) [42](#), [1007](#)
User-definable V/f characteristic [172](#)
Userlevel [37](#)

V

V/f base frequency [164](#)
V/f characteristic control (VFCplus) [150](#), [157](#)
V/f control (VFCplus + encoder) [186](#)
V/f emergency operation in case of encoder open circuit [186](#), [226](#), [313](#)
Validity [23](#)
Validity of the reference measuring system [564](#)
VFC
 Frequency interpol. point n (C00967) [1130](#)
 Limitation V/f + sensor (C00971) [1131](#)
 Ti V/f +sensor (C00973) [1131](#)
 Time const. slip comp. (C00966) [1129](#)
 V/f base frequency (C00015) [890](#)
 Vmin boost (C00016) [890](#)
 Voltage interpol. point n (C00968) [1130](#)
 Vp V/f +sensor (C00972) [1131](#)
VFC-ECO
 Minimum voltage V/f (C00977) [1132](#)
 Ti CosPhi controller (C00976) [1132](#)
 Voltage reduction (C00978) [1132](#)
 Voltage reduction ramp (C00982) [1133](#)
 Vp CosPhi controller (C00975) [1132](#)
Vmin boost [166](#)
Vp current controller (C00075) [902](#)
Vp speed controller (C00070) [901](#)

W

Warning threshold motor temperature (C00121) [913](#)



Your opinion is important to us

These instructions were created to the best of our knowledge and belief to give you the best possible support for handling our product.

If you have suggestions for improvement, please e-mail us to:

feedback-docu@Lenze.de

Thank you for your support.

Your Lenze documentation team



Lenze Drives GmbH
Breslauer Straße 3
D-32699 Extertal
Germany

☎ +49 5154 82-0

@ lenze@lenze.com

🌐 www.lenze.com

Service

Lenze Service GmbH
Breslauer Straße 3
D-32699 Extertal
Germany

☎ 00800 24 46877 (24 h helpline)

☎ +49 5154 82-1112

@ service@lenze.com