

DIAX03 Drive With Electric Gear Function

Version notes: ELS 05VRS

DOK-DIAX03-ELS-05VRS**-FVN1-EN-P

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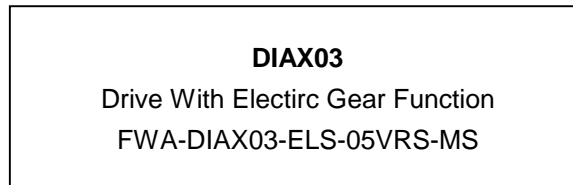
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Customer Service Location

1 General Information

1.1 Product Family

The product release description refers to the product family:



The following drive controls can be operated with this software:

- DDS 2.2
- DDS 3.2
- DKR 2.1
- DKR 3.1
- DKR 4.1

1.2 Documentation

The documentation for product **FWA-DIAX03-ELS-05VRS** is available as follows:

Paper form
Windows help system

The following table contains a summary of available items.

POS	Type	Document style	Register in Mappe 50-05V	Part number	Symbol number
1	DOK-DIAX03-ELS-05VRS**- 50M1-EN-P	Mappe 61-01V-EN Paper	--	276238	209-0072-4321-01
2	DOK-DIAX03-ELS-05VRS**- FKB1-EN-P	Functional Description Paper	3	276242	209-0072-4322-01
3	DOK-DIAX03-ELS-05VRS**- INF1-EN-P	Drive Configuration	6	276240	209-0072-4323-01
4	DOK-DIAX03-ELS-05VRS**- WAR1-EN-P	Trouble Shooting GuidePaper	8	276241	209-0072-4324-01
6	DOK-DIAX03-ELS-05VRS**- FVN1-EN-P	Firmware Versionsnote	10	276239	209-0072-4325-01
7	DOK-DIAX03-ELS-05VRS**- 50M1-EN-H1,44	Help System for Windows3.1 Disk	12	276237	209-0072-4321-01

Figure: 1-1: Documentation for FWA-DIAX03-ELS-05VRS

1.3 Notes on Replacing the Firmware

To successfully replace the firmware, the following steps in the prescribed order must be complied with and the listed tasks conducted as outlined.

- **Release - read the entire documentation**
- **Secure the current set of parameters**

Note: The parameters to be secured are stored in parameter S-0-0192.

- **Switch machine off, exchange the drive controller firmware (Eproms) and switch machine back on.**
- **Switch into operating mode**
The machine is now operable with the new firmware.
- **Check the functions**
Check the functions of the re-equipped machine carefully after firmware exchange.

2 Firmware-Version DIAX03-ELS-05V11

2.1 Release notes

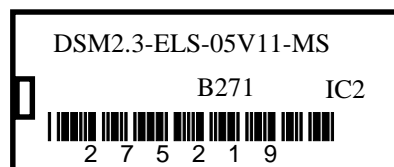
Firmware version **FWA-DIAX03-ELS-05V11** represents the first official edition of version 01. It was released on **01.08.97**.

The following drive controllers can be operated with the released software:

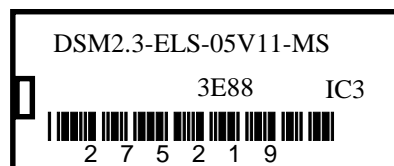
- DKR03.1-W100, DKR03.1-W150, DKR03.1-W200
- DKR03.1-F100, DKR03.1-F150, DKR03.1-F200
- DKR02.1-W200, DKR02.1-W300
- DKR02.1-F200, DKR02.1-F300
- DKR04.1-W300, DKR04.1-W400
- DKR04.1-F300, DKR04.1-F400
- DDS02.2-W015, DDS02.2-W025, DDS02.2-W050, DDS02.2-W100, DDS02.2-W150, DDS02.2-W200
- DDS02.2-A015, DDS02.2-A050, DDS02.2-A100, DDS02.2-A200
- DDS02.2-F015, DDS02.2-F050, DDS02.2-F100, DDS02.2-F200
- DDS03.2-W030, DDS03.2-W015, DDS03.2-W050

2.2 EPROM Labelling

EPROM IC2:



EPROM IC3:



2.3 New basic functions

SERCOS compatibility class B

The firmware is equipped with all functions needed to achieve SERCOS compatibility class B.

- **S-0-0018, IDN list of communications phase 2 operating data**
- **S-0-0019, IDN list of communications phase 3 operating data**
- **S-0-0025, IDN list of all commands**
- **S-0-0125, nx velocity threshold**
- **S-0-0157, speed window**
- **S-0-0013, C3D, bit 0 (nact = ncomm) and bit2 (|nact| < nx)**
- **S-0-0191, D600 command delete reference**

Command load base parameters

The command **P-0-4094, C800 command load base parameters** was implemented. While executing the command, all the parameters in **S-0-0192, IDN list of operating data to be secured**, are set to the default values specified in the drive.

If the firmware on a programming module is exchanged and the incompatibility of the parameter memory in terms of the previous firmware is detected, then the error message **F209 load base values of parameters** is generated. „PL“ appears on the 7-segment display. By pressing the S1 key, "load base parameters" is executed.

Error memory and elapsed hour meter

Elapsed hour meters and error memory were implemented to store the C1D errors and the number of elapsed hours. These were stored in the form of parameters:

- **P-0-0190, elapsed hour in the control**
- **P-0-0191, elapsed hours in the power section**
- **P-0-0192, error memory of diagnosis numbers**
- **P-0-0193, error memory of elapsed hours in the control**

The parameters are stored in the E²prom. Write access is not possible.

Freely configurable signal status word

A freely configurable signal status word was used. Via parameters

- **S-0-0026, configuration list of signal status word and**
- **S-0-0328, configuration list of signal status word, bit number**

it is possible to define which bit of which parameter has been configured in parameter

- **S-0-0144, signal status word**

Up to 16 bits can be configured. The group signal S-0-0144 is generated at time T4 every Sercos cycle.

Switching to French, Spanish and Italian

The following languages for parameter names and units as well as the diagnoses are in parameter **S-0-0095, diagnosis**.

S-0-0265, language select	Selected language
0	German
1	english
2	French
3	Spanish
4	Italian

Fig. 2-2: Language selection in *S-0-0265, Language selection*

Bit „IN_TARGET POSITION“ in **S-0-0182, manufacturer's C3D**

The message IN_TARGET POSITION has been introduced into the manufacturer's C3D as bit 10. The bit is „1“. It applies:

$$\left| \text{S-0-0258, target position} - \text{S-0-0051/53 actual position value} - 1/2 \right| < \text{S-0-0057, positioning window}$$

Supporting plug-in modules DEA 8/9/10.1-M

Plug-in modules DEA 8.1, 9.1 and 10.1 are supported by the firmware. The following parameters have been introduced for this purpose:

- **P-0-0170, Parallel output 4**
- **P-0-0171, Parallel input 4**
- **P-0-0172, Parallel output 5**
- **P-0-0173, Parallel input 5**
- **P-0-0174, Parallel output 6**
- **P-0-0175, Parallel input 6**

The option to allocate a parallel input or output to a specific parameter is given using parameter P-0-0124/125. This means that for each drive there is a maximum of 72 digital outputs and 96 digital inputs.

Evaluating distance-coded measuring systems

It is now possible to evaluate distance-coded measuring systems. Via bit 1 in **S-0-0277, Position feedback type parameter 1** or **S-0-0115, Position feedback type parameter 2** it can be indicated as to whether the measuring system has distance-coded reference markers. Via parameters

- **S-0-0165, distance coded reference dimension 1** and
- **S-0-0166, distance coded reference dimension 2**

the bigger and smaller distance is entered. During command **S-0-0148, C600 drive-guided homing** the drive crosses two adjacent reference markers. It uses this to calculate the new actual position value, in terms of the machine's zero point, based on the distance of the reference marker and the value in **S-0-0177 absolute dimension offset 1** or **S-0-0178 absolute dimension offset 2**.

Determine command marker position

With the help of **P-0-0014, d500 determine command marker position**, it is possible to detect the correct determination and position of the reference marker of an incremental linear scale. The position of the reference marker is then displayed in parameter **S-0-0173, marker position A**. This command is used to operate gantry axes with external measuring systems or to check whether the reference marker determination is error-free.

Return movement with error

If a "3" is set in parameter **P-0-0119, best possible deceleration** then a return movement with error is conducted if a non-fatal error or interface error occurs, or if the drive enable signal is removed, with phase regression of a communications phase while the drive is in „AF“. The drive runs a relative distance specified by parameters

- **P-0-0096, distance to move in error situation**
- **S-0-0091, bipolar velocity limit value**
- **S-0-0138, bipolar acceleration and**
- **S-0-0349, bipolar jerk limit value**

E-Stop as fatal warning

The response of the drive to an activated E-stop input can take three forms:

- A response as "travel distance error". This generates **F6/34 E-Stop activated**. The drive responds by going to zero velocity regardless of the setting in **P-0-0119, best possible deceleration**. The error must be cleared with "error reset".
- A response as "interface error". This generates **F4/34 E-Stop activated**. The drive responds in terms of what was set in **P-0-0119, best possible deceleration**. The error must be cleared with "error reset".
- A response as "fatal warning". This generates **E8/34 E-Stop activated**. The drive responds in terms of what was set in **P-0-0119, best possible deceleration**. No error is generated. (Similar to removal of drive enable signal.)

This is set in parameter **P-0-0008, Activation E-stop function**:

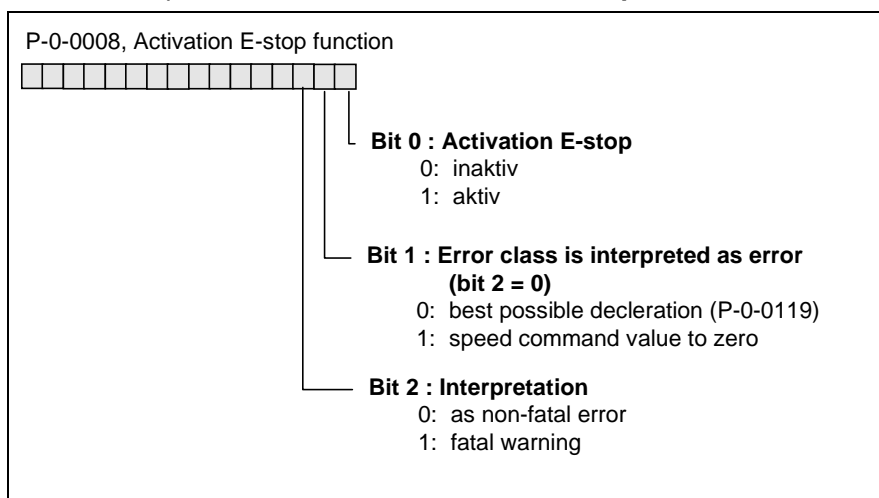


Fig. 2-3: E-Stop function in P-0-0008

Settable drive-internal position resolution

The resolution of the drive-internal position data is no longer dependent on the motor encoder type used but can instead be set in parameter **S-0-0278, Maximum travel range**. The maximum resolution equals 2^{15} per encoder spacing. Minimum resolution equals 2^2 . Calculated resolution for encoders 1 and 2 is displayed in parameters **S-0-0256, multiplicand-1** and **S-0-0257, multiplicand-2**.

The drive-internal resolution in the form of a the number of increments per motor resolution of a rotary motor encoder is thus calculated in terms of **S-0-0116, motor encoder resolution * S-0-0256, multiplicand-1**.

This function supports

- increasing the drive-internal resolution of the position data in small travel distances and high resolution requirements and
- to reduce the resolution in terms of a larger travel range.

New encoder types "Gear-wheel encoders with 1Vss signals“, "Resolver encoder without feedback memory" and „Resolver encoder + sine encoder"

Three new encoder types have been introduced:

encoder type	Interface no. in P-0-0074/75	Module required
gear-wheel encoder with 1Vss	9	DZF 3.1
resolver encoder without feedback data storage	10	--
resolver encoder + sine encoder	11	DLF-1

Fig. 2-4: New encoder types

Encoder type „gear-wheel encoder with 1Vss“ can be used either as a motor encoder or an external encoder. „Resolver encoder + sine encoder“ and „resolver encoder feedback data storage“ can only be used as a motor encoder.

New motor type „Rotary synchronous kit motor“

The new motor type *Rotary synchronous kit motor* has been introduced. In parameter **P-0-4014, motor type „7“** has been parametrized. This sets this type of motor. This motor type does not have a motor feedback data storage in which the motor parameters have been stored. The commutation offset in the form of parameter **P-0-0508, commutation offset** is buffered in the programming module.

The following motor encoders are permissible with this motor type:

P-0-0074, Motor encoder interface	Encoder type
1	all DSFs (Stegmann/Heidenhain)
8	Endat
10	Resolver without feedback data storage
11	Resolver without feedback data storage with sine encoder

Fig. 2-5: Possible motor encoders for rotary synchronous kit motors

„Relative drive-internal interpolation“ mode

Four new operating modes for relative drive-internal interpolation have been introduced.

S-0-0032/33/34/35	operating mode
0000.0010.0001.0011	A146 Relative drive-internal Interpolation, encoder 1
0000.0010.0001.0100	A147 Relative drive-internal Interpolation, encoder 2
0000.0010.0001.1011	A148 Relative drive-internal interpol. encoder 1, lagless
0000.0010.0001.1011	A149 Relative drive-internal interpol. encoder 2, lagless

Fig. 2-6: Operating modes „Relative drive-internal interpolation“

In these operating modes, the distance to be covered is set in parameter **S-0-0282, travel distance**. This is assumed by toggling parameter **S-0-0346, assume relative command value** into the absolute target position in **S-0-0258, target position**. It is set in the drive-internal interpolator and then covered. If modulo scaling has been set for the position data, then travel distances equalling more than one modulo value can also be set.

Load-side motor encoder with rotary asynchronous motor

If motor type „2“ or „6“ is set (rotary asynchronous motor), then the motor encoder can be mounted load side and operated there. This means that there is no motor encoder but rather an external encoder. The load side motor encoder is parametrized via external encoder parameters such as:

- **S-0-0115, position encoder type 2**
- **S-0-0117, resolution of external encoder**
- **P-0-0075, external encoder interface**

There is thus no motor encoder, i.e., **P-0-0074, motor encoder interface** must be parametrized with „0“. Parameter **P-0-0121, velocity mix factor encoder 1 & encoder 2** must be set to 100%.

Customer password

With parameter **S-0-0267, password**, a customer password can be activated. Once activated, all parameters backed up in the programming module cannot be write accessed (All parameters in **S-0-0192, list of operating data to be secured**.) If the attempt is made to write access a parameter with password, then the service channel error message *0x7009, data write protected with password* is generated. At delivery, the unit does not have an activated customer password. Reading **S-0-0267, password** generates the value „007“ (default customer password). By entering [old password] [new password] the (new) customer password is activated. Reading **S-0-0267, password** generates the value „***“ (customer password active).

Park Axes Command

Command **S-0-0139, D700 park axes command** was used. This command can only be write accessed in communications phase 2. If this command is active, then all monitors of commands **S-0-0128, C200 communications phase 4 transition check** are run. The message "**PA**" appears in the 7-segment display. Phase regression deactivates this command (as is the case with all other commands).

Motor overload monitor

The new dynamic current limit of DIAX03/04 drive controllers with firmware SSE-01VRS/ELS-04VRS, which is based on the temperature model of the amplifier, does not take the motor into consideration. The motor is protected only by its temperature sensor. If the motor is overloaded, then the temperature sensor does not respond quickly enough meaning that the winding could burn up. It does not suffice to limit motor peak current.

A motor overload limit was thus instituted. For 400msec a fourfold motor current at standstill is permitted. A 2.2 fold motor current at standstill is generally permitted. If motor overload limit is active, then the warning **E225 motor overload** is generated, bit 0 (overload warning) is set in **S-0-0012, C2D**. The limited peak current is displayed in **P-0-4046, active peak current**.

Expansion of parameters P-0-0118, power off with error

Parameter **P-0-0118, power off with error**, which controls power off, has been expanded. The following settings are now possible:

Bit no. in P-0-0118	Definition
0	Power supply module message with error 0- no message via X1.2 with error 1- message via X1.2 with error
1	First signal to power supply module 0 - first signal if no error and communications phase 4 <i>(X1.2 goes to „1“, when first reaching comm. phase 4 and there is no C2D error)</i> 1 - first signal if no error („passive axes“) <i>(X1.2 goes to „1“, if no C1D error)</i>
2	Time point for power off with error (only if bit 0 = „1“, message via X1.2 with error) 0 - X1.2 with error goes to 0 immediately, <i>(total reaction of all same power supply units in controller, preset for modular units (DDS))</i> 1 - X1.2 with error goes to 0 if drive goes torque free. <i>(preset for compact units (DKR))</i>
3	Reaction to DC bus undervoltage 0 - undervoltage treated like non-fatal error 1 - undervoltage treated like fata warning which stops operation of motor

Fig. 2-7: Expansion of parameter P-0-0118

Displaying the writability of a parameter in terms of the communications phase in the attribute

Every parameter is made up of a data block with 7 elements. One of these elements is the attribute made up of a bit strip with 32 bits. Information such as display format, number of decimal places and so on are displayed there. The bits 28, 29 and 30, not presently used, are now being used to display whether a parameter can be write accessed in terms of the communications phase. This means that the parametrizable surface of this information is available.

The following definitions use the new bits:

Bit no. in attribute	Definition
28	0 - Operating data can be write accessed in comm. phase 2 1 - Oper.data cannot be write accessed in comm. phase 2
29	0 - Operating data can be write accessed in comm. phase 3 1 - Oper.data cannot be write accessed in comm. phase 3
30	0 - Operating data can be write accessed in comm. phase 4 1 - Oper.data cannot be write accessed in comm. phase 4

Fig. 2-8: Expanding the SERCOS attribute

(See Update 97.1 on SERCOS interface.)

Warning for interpolation speed and acceleration equal to 0

In operating mode „drive-internal or relative drive-internal interpolation, drive halt or "drive guided referencing" command, the drive autonomously generates a position command value profile in the so-called drive-internal interpolator. The interpolator is given the maximum speed or maximum acceleration (referencing speed and acceleration or position speed and acceleration) it may use. If the effective speed is equal to 0, then the warning **E247 interpolation speed = 0** is generated. If the effective acceleration is 0, then the warning **E248 interpolation acceleration = 0** is generated. The relevant parameters should be correctly set.

List of supported operating modes

Parameter **S-0-0292, list of supported operating modes** has been used. It lists the codes of the operating modes supported in this firmware.

Changing decimal places with rotary parametr position scaling

If rotary parameter scaling is set for position data (**S-0-0076, position data scaling** = 0000.0000.xx00.1010), then the decimal places for the scaling dependent position data are set in terms of the selected rotary position resolution in **S-0-0079, rotary position resolution**.

S-0-0079, rotary position resolution = $360 * 10^x$, for $x = 0..6$.

If some other value is parametrized in **S-0-0079, rotary position resolution**, then the number of decimal places is 0 and the unit is increments.

Detailed error messages for missing external voltage supply

To quickly eliminate errors the error message **F2-33 external voltage supply error** has been broken down into the more detailed error messages as follows:

- **F2-70 zero switch voltage supply error**
- **F2-71 travel range limit switch voltage supply error**
- **F2-72 probe voltage supply error**
- **F2-73 emergency stop voltage supply error**

An error as defined by **F2-33 external voltage supply error** now exclusively defines the 24 volt supply for the DEA plug-in card.

Referencing with or without homing

Bit 7 of parameter **S-0-0147 homing parameter** as defined by the SERCOS specification is now supported. This means that that the drive, once it has recognized the reference marker and with bit 7 not set, will stop with the reference acceleration and velocity which has been set. **It does not go to home.**

If bit 7 is set in parameter **S-0-0147 homing parameter**, then the drive will assume the homing position.

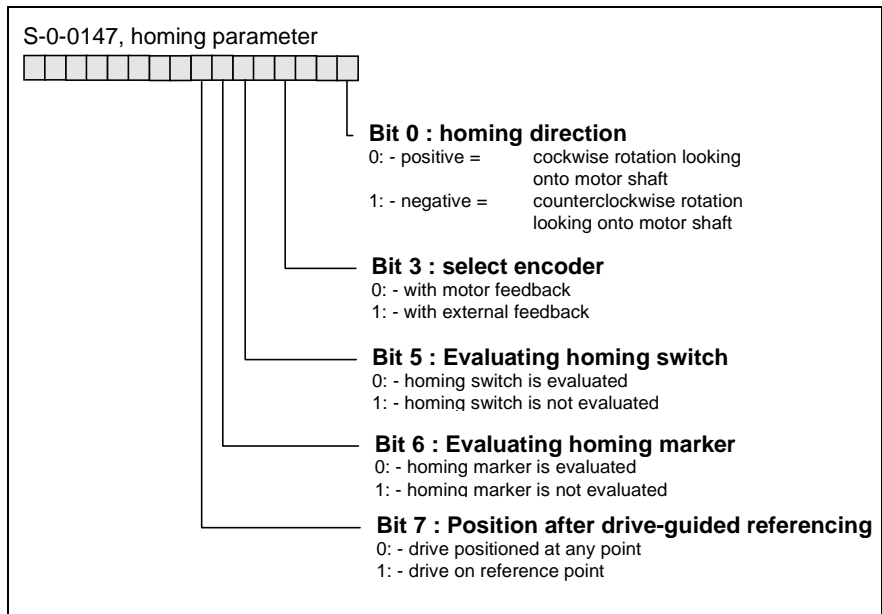


Fig. 2-9: Homing parameter S-0-0147

2.4 New ELS Functions

Measuring wheel operations command

Roll feed drives convey material intended for processing at some later time, e.g., tin cutting. The motor encoder, in this case, is not suited for measuring material length if lag can occur between material and drive. Position control is therefore conducted with the measuring wheel encoder (external encoder) to be able to precisely measure sectional lengths. Closing the position control loop with an external encoder does have the disadvantage that the entire mechanical power train, affected by lag, play, torsion and so on, in turn, affects the position control loop and only minor position control loop amplification can be set. The command measuring wheel operation represents a solution as it can activate a control that combines the high dynamics of position control and motor encoder with the high precision of position control and external encoder (see control loop structure in Fig. 2-9).

The command

- **P-0-0220 measuring wheel operations**

as well as the relevant parameter

- **P-0-0221, actual position value smoothing time constant in measuring wheel mode**

have been implemented.

Master axis train

A master axis train has been implemented which makes it possible to apply a dynamic gear ratio to the effective master position in the drive. Parameters

- **P-0-0156, master axis train input revolutions**
- **P-0-0157, master axis output revolutions**

have been implemented. They can be cyclically configured in the MDT. The master axis trains works in all ELS modes similarly to

- speed synchronization
- angle synchronization
- electrical cam
- pattern control

Translatory angle synchronization

In angle synchronization mode to calculate the electronic gear in terms of the position scaling set in parameter **S-0-0076, scaling mode position data**, either parameter **S-0-0237, following axis revolution 1** or **P-0-0159, slave drive feed path** should be used to define the electronic gear factor.

S-0-0076, scaling mode position data	Parameter for electrical gear factor
0000.0000.1xxx.xx10	S-0-0236, master drive revolution 1 / S-0-0237, slave drive 1
0000.0000.1xxx.xx01	S-0-0236, master drive revolution 1 / P-0-0159, slave drive feed path

Fig. 2-10: Electrical gear as dependent on the position scaling set

Phase offset begin of profile speed

In operating modes cam and pattern control, parameter **P-0-0061, phase offset begin of profile** affects the profile access angle. If angle displacement is to be enlarged, then a slow approach to the new value must be set as each change represents a position command value jump. This slow approach to a new value is assumed by the drive.

A new value in parameter **P-0-0061, phase offset begin of profile** does not immediately become effective. Starting with the current value, a slow approach to the new value is executed with the help of parameter

- **P-0-0158, phase offset begin of profile speed**

Incremental encoder emulation for master axis position and actual position value 1

The signals

- master axis position and
- actual position value 1

can be generated via the incremental emulation function of module DAE 2.1. The following parameters are available for this function:

- **P-0-0502, number of lines of the incremental encoder**
- **P-0-0503, reference pulse offset**
- **P-0-0504, select signal of incremental encoder**

The following can be set in parameter **P-0-0504, select signal of incremental encoder**.

Value in P-0-0504	Definition
0	no emulation
1	master axis position is emulated
2	actual position value 1 is emulated

Fig. 2-11: Select signal of incremental encoder emulation

Monitor window for measuring probe function

The measuring probe function was expanded so that a monitor window can be opened for measuring probe function 1. This window accepts master probe flanks. Parameters

- **P-0-0204, measuring probe function start position active** and
- **P-0-0205, measuring probe function end position active**

have been implemented for this purpose.

The signal select for measuring probe input 1 in parameter **P-0-0200, signal select measuring probe function 1** has been expanded with the values 3 and 4 giving it the following definitions:

Value in P-0-0200	Definition
0	actual position value 1 / 2
1	time
2	master axis position
3	actual position value 1 / 2 with monitor window activated
4	master axis position with monitor window active

Fig. 2-12: Signal select in P-0-0200

2.5 Expanded / changed functions

Evaluating absolute measuring systems

Function *Evaluating absolute measuring systems* has been expanded.

It is now also possible:

- to treat single turn encoders as if there were absolute encoders and
- to switch absolute encoder evaluation for multiturn encoders off.

Additional, a plausibility check is run with the (new) parameters **S-0-0278, maximum travel range** or **S-0-0103, modulo values**. The following table outlines the relationships:

Encoder type (Absolute range)	Position scaling	Modulo value	Maximum travel range	Position feedback type parameter, Bit 6
incremental (< 1 encoder rev.)	absolute format	not relevant	not relevant	0
	modulo format	not relevant	>= modulo value	0
Singleturn (= 1 encoder rev.)	absolute format	not relevant	<= ½ absolute range	1
		not relevant	> ½ absolute range	0
	modulo format	<= absolute range	>= modulo value	1
		> absolute range	>= modulo value	0
Multiturn (> 1 encoder rev.)	absolute format	not relevant	<= ½ absolute range	1
		not relevant	> ½ absolute range	0
	modulo format	<= absolute range	>= modulo value	1
		> absolute range	>= modulo value	0
Absolute Linear scale	not relevant	not relevant	not relevant	1

Fig. 2-13: Absolute encoder evaluation as dependent on position format, modulo value and maximum travel range

To be able to switch the absolute encoder evaluation off, it was necessary to redefine bit 7 in the position encoder type parameters, as well as to modify the definition of bit 6.

Bit 7, Bit 6 in S-0-0277/S-0-0115	Definition
x , 0	absolute evaluation no possible, bit 7 is not relevant
0 , 1	absolute evaluation possible and permissible -> encoder treated as absolute encoder !
1 , 1	absolute evaluation possible but not permitted

Fig. 2-14: Absolute encoder evaluation as per position encoder type parameter

Analog output

Function analog output has been revised. It is now possible

- for the control to write access the parameters directly set by the digital/analog converter (parameter **P-0-0139, analog output-1** and **P-0-0140 analog output-2** new).
- to generate certain parameters of the drive with variable scaling via digital/analog converter (parameter **P-0-0426, Analog output, IDN list of all allocatable parameters, P-0-0420, analog output-1, signal select, P-0-0422, analog output-1, eval. , P-0-0423, analog output-1, signal select** and **P-0-0425, analog output-2, eval., new**).
- to generate permanently set signals, as well as all bits and bytes via the expanded signal select (parameter **P-0-0421 analog output-1, expanded signal select** and **P-0-0424 analog output-2, expanded signal select** new).
- List of permanently set signals:

Signal number P-0-0421/424	Output signal	Reference unit: Weighting factor 1.0
0x00000001	sien signal motor encoder	0.5V/10V
0x00000002	cosine signal motor encoder	0.5V/10V
0x00000003	sine signal ext. encoder	0.5V/10V
0x00000004	cosine signal ext. encoder	0.5V/10V
0x00000005	position command difference on position control	rot. =>1000rpm/10V lin. =>100m/min/10V
0x00000006	DC bus output	1kW/10V
0x00000007	DC bus output absolute sum	1kW/10V
0x00000008	in-phase current (Iq)	S-0-0110/10V
0x00000009	idle current (Id)	S-0-0110/10V
0x0000000a	thermal load	--
0x0000000b	motor temperature	150°C/10V
0x0000000c	magnetization current	S-0-0110/10V
0x0000000d	speed command value at speed control	rot. =>1000Upm/10V lin. => 100m/min/10V

Fig. 2-15: Signal list with pre-defined selection of signals

- These outputs do not depend on the weightings and always related to the motor shaft. Signal scaling is possible via the evaluation parameters P-0-0422 & P-0-0425. With the expanded choice of signals with pre-defined signals, they are defined as factors with four decimal places with a permanent reference unit to the selected signal (see table).

Analog input

The function *Analog input* has been expanded. It is now also possible

- to enter certain parameters of the drive with variable scaling via the analog/digital converter (parameter **P-0-0212, analog inputs, IDN list of all allocatable parameters, P-0-0213, analog input-1, allocation, P-0-0214, analog input-1, evaluation , P-0-0215, analog input-2, allocation and P-0-0216, analog input-2, evaluation , new**).
- the analog input signals can be given an offset (parameter **P-0-217, analog input-1, Offset and P-0-218, analog input-2, Offset new**).

Analog input-1 is processed every 250 usec, analog input-2 only every 8 msec.

Parameter **P-0-0115, analog input 1** and **P-0-0116, analog input-2**, used via plug-in module DRF-1, have been dropped. The new analog inputs use parameter **P-0-0210, Analog input 1** and **P-0-0211, Analog output 2** and use module DAE-2-1. This means it is now possible to use analog inputs in configurations using modules DLF-1 or DZF-1.

Speed control

Speed control has been modified in terms of

- the low-pass filter of the actual speed value via parameter **S-0-0392, actual speed limit filter time constant** has been dropped
- the manipulated variable generated by speed control (force - torque command value) can be filtered via a band stop filter with settable filter frequency and band width (parameter **P-0-0180, blocking frequency of speed control** and **P-0-0181 band width locking filter speed control new**) and
- the low-pass filter via **P-0-0004, smoothing time constant** does not effect the variable but rather speed control offset.

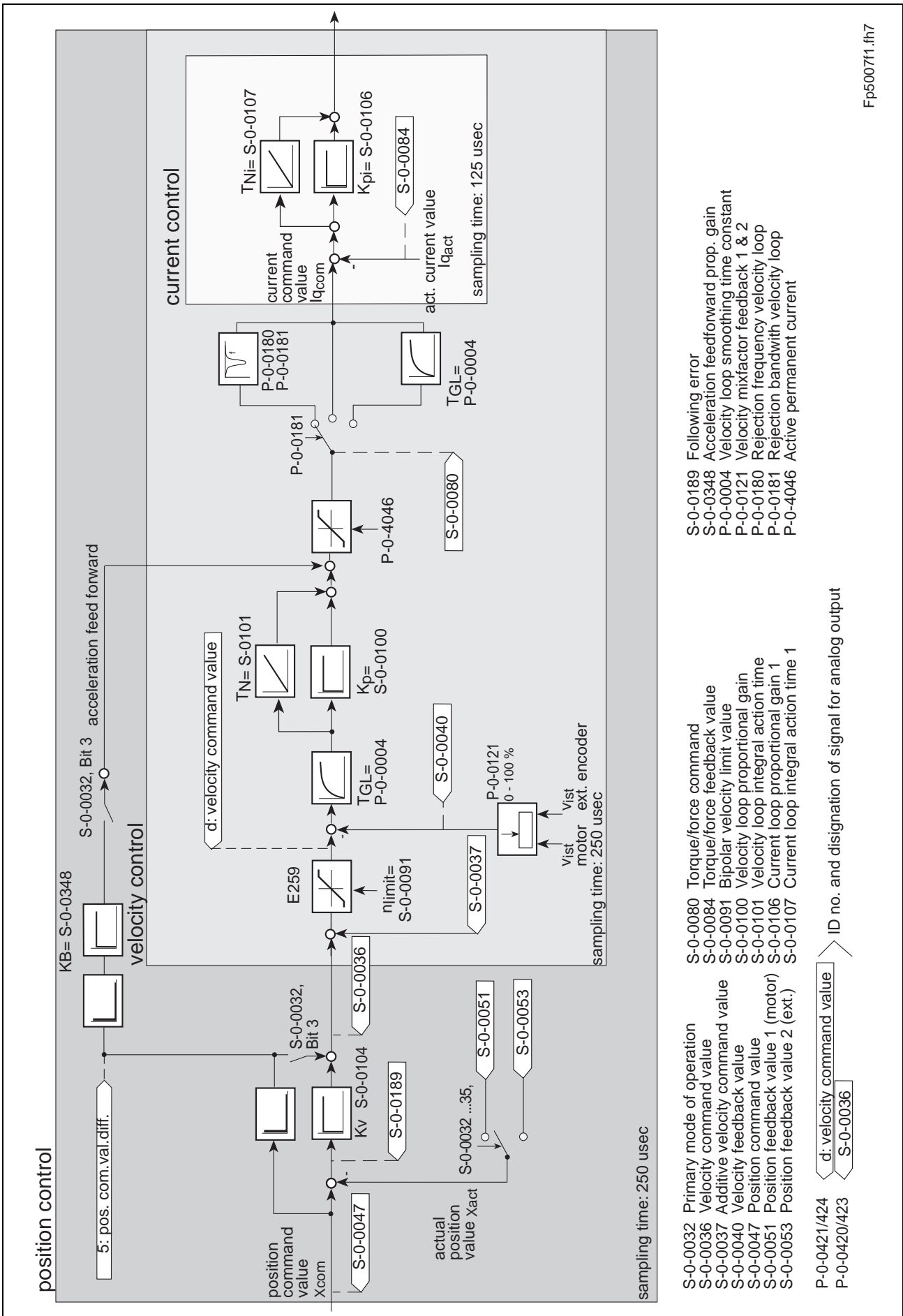


Abb. 2-16: Reglerstruktur FWA-DIAX03-ELS-05VRS

- S-0-0189 Following error
- S-0-0348 Acceleration feedforward prop. gain
- P-0-0004 Velocity loop smoothing time constant
- P-0-0121 Velocity mixfactor feedback 1 & 2
- P-0-0180 Rejection frequency velocity loop
- P-0-0181 Rejection bandwidth velocity loop
- P-0-4046 Active permanent current

- S-0-0080 Torque/force command
- S-0-0084 Torque/force feedback value
- S-0-0091 Bipolar velocity limit value
- S-0-0100 Velocity loop proportional gain
- S-0-0101 Velocity loop integral action time
- S-0-0106 Current loop proportional gain 1
- S-0-0107 Current loop integral action time 1

- S-0-0032 Primary mode of operation
- S-0-0036 Velocity command value
- S-0-0040 Additive velocity command value
- S-0-0047 Velocity feedback value
- S-0-0047 Position command value
- S-0-0051 Position feedback value 1 (motor)
- S-0-0053 Position feedback value 2 (ext.)
- P-0-0421/424 d: velocity command value
- P-0-0420/423 S-0-0036

Evaluating an external encoder

Evaluating an external encoder has been changed so that the evaluation mode is set via parameter **P-0-0185, external encoder function**.

Value in P-0-0185, function of the external encoder	Definition
0	external encoder as additional control encoder (as earlier standard function „external encoder“)
1	external encoder as master axis encoder
2	external encoder as load side motor encoder
3	external encoder as measuring wheel encoder

Fig. 2-17: External encoder functions

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