



SINUMERIK

SINUMERIK 840D sl CNC Commissioning: NC, PLC, Drive

Commissioning Manual

Valid for:

SINUMERIK 840D sl/840DE sl

CNC Software Version 4.5 SP2

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Warning notice system

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

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


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

Qualified Personnel

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

Proper use of Siemens products

Note the following:

 WARNING
Siemens products may only be used for the applications described in the catalog and in the relevant technical documentation. If products and components from other manufacturers are used, these must be recommended or approved by Siemens. Proper transport, storage, installation, assembly, commissioning, operation and maintenance are required to ensure that the products operate safely and without any problems. The permissible ambient conditions must be complied with. The information in the relevant documentation must be observed.

Trademarks

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Disclaimer of Liability

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

Preface

SINUMERIK documentation

The SINUMERIK documentation is organized in the following categories:

- General documentation
- User documentation
- Manufacturer/service documentation

Additional information

You can find information on the following topics under the link (www.siemens.com/motioncontrol/docu):

- Ordering documentation/overview of documentation
- Additional links to download documents
- Using documentation online (find and search in manuals/information)

Please send any questions about the technical documentation (e.g. suggestions for improvement, corrections) to the following address:

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- SITRAIN (www.siemens.com/sitrain) - training courses from Siemens for automation products, systems and solutions
- SinuTrain (www.siemens.com/sinutrain) - training software for SINUMERIK

FAQs

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Target group

This documentation is intended for commissioning personnel.

The plant or system is readily assembled and wired. For the following steps, e.g. configuring the individual components, the Commissioning Manual contains all necessary information or at least references.

Benefits

The intended target group can use the Commissioning Manual to test and commission the system or the plant correctly and safely.

Utilization phase: Setup and commissioning phase

Standard version

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

Other functions not described in this documentation might be executable in the control. This does not, however, represent an obligation to supply such functions with a new control or when servicing.

Further, for the sake of simplicity, this documentation does not contain all detailed information about all types of the product and cannot cover every conceivable case of installation, operation or maintenance.

Technical Support

Country-specific telephone numbers for technical support are provided in the Internet under "Contact" (www.siemens.com/automation/service&support).

EC Declaration of Conformity

The EC declaration of conformity for the EMC directive can be found in the Internet (www.siemens.com/automation/service&support).

There, as search term, enter the number **15257461** or contact your local Siemens office.

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Introduction

1.1 Commissioning manuals for SINUMERIK 840D sl

Steps for commissioning SINUMERIK 840D sl

Commissioning a SINUMERIK 840D sl is performed in two basic steps:

1. **Step 1:** Commissioning the NC, PLC, drive
2. **Step 2:** Commissioning the NC functions, PLC user program, machine data

The relevant manuals for commissioning SINUMERIK 840D sl are:

- Commissioning Manual: CNC Commissioning: NC, PLC, Drive
- Function manuals: Basic functions, extension functions, special functions, synchronized actions
- List manuals: Machine data and interface signals

The following figure is a schematic representation of the commissioning steps that are described in Step 1 and in Step 2:

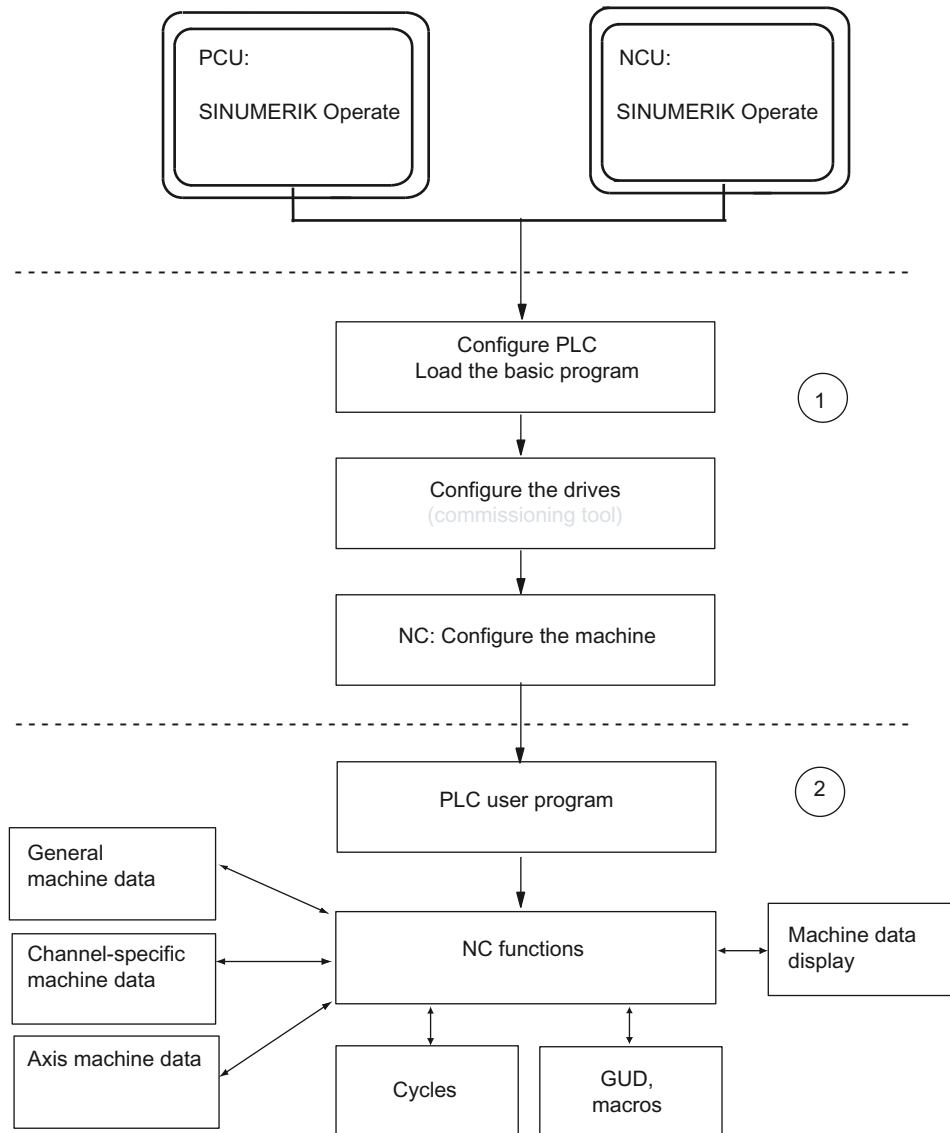


Figure 1-1 Commissioning overview

References

The commissioning of SINUMERIK 840D sl with Safety Integrated is described in the SINUMERIK 840D sl Safety Integrated Function Manual.

1.2 Configuration of SINUMERIK 840D sl and components and I/O

Introduction

In principle, an NCU contains the following components:

- NCK
- PLC
- Drive
- HMI
- CP

The following figure is a schematic representation of the NCU:

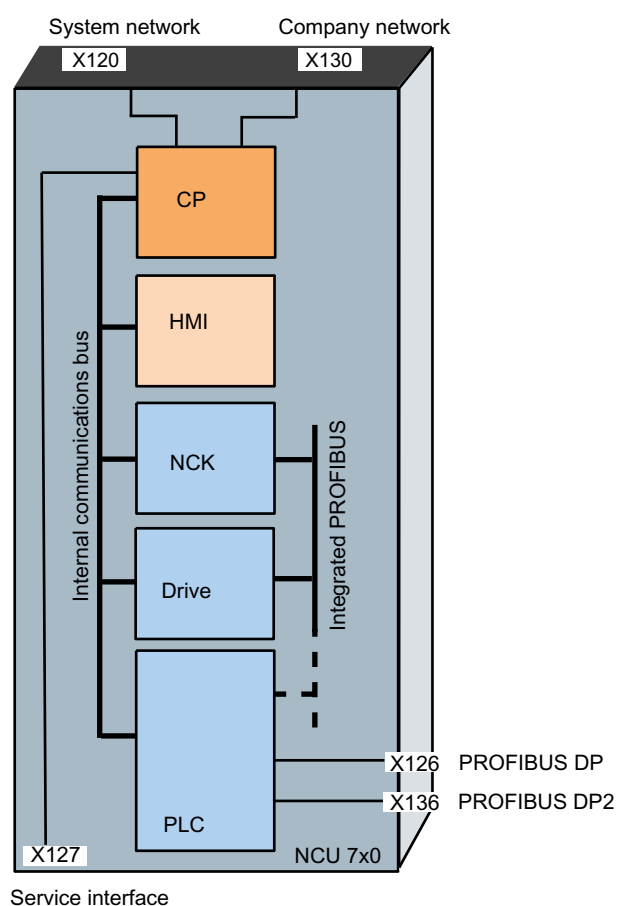


Figure 1-2 Schematic representation of NCU

Commissioning the components

The PG/PC required for commissioning is connected to the X127 service interface or access is made via the company network to X130. The following software tools are also required:

- The commissioning tool on the PG/PC is needed for commissioning the drive.
- For commissioning the PLC, a PG/PC with SIMATIC STEP7 Version 5.5 SP1 is required as well as the toolbox for SINUMERIK 840D sl for the current CNC software version.
- A network switch is required to connect several communication partners to X120.

SINUMERIK Operate on the NCU is running under the Linux operating system. In addition, a PCU can be connected to each NCU on which SINUMERIK Operate is running under Windows XP or Windows 7 with the following general conditions:

- PCU 50.3 with Windows XP
- PCU 50.5 with Windows XP or Windows 7

Note

For the operation of SINUMERIK Operate on the PCU **without** TCU, the "HMI" subsystem must be switched off for SINUMERIK Operate on the NCU.

NCU 7x0.3 PN configuration with SINAMICS S120 Booksize

The following diagram shows an example configuration of an NCU 7x0.3 PN with SINAMICS S120 Booksize:

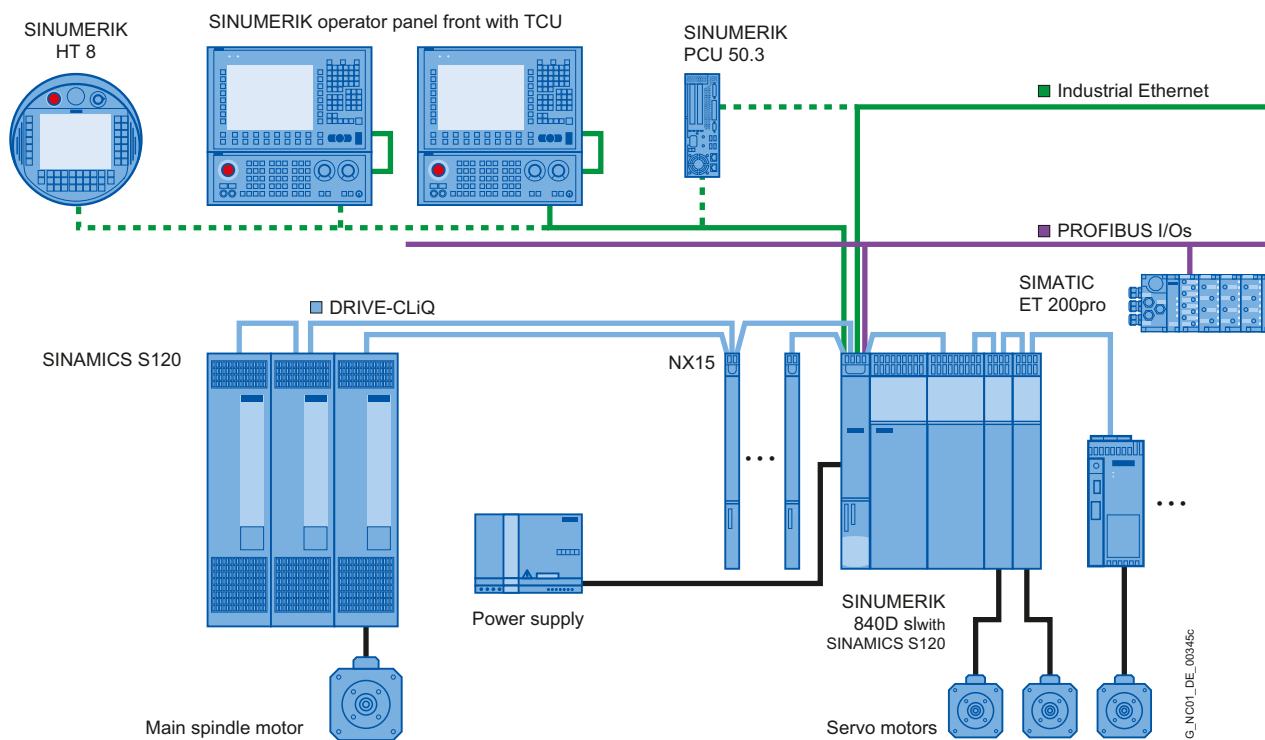


Figure 1-3 Example: SINUMERIK 840D sl configuration with SINAMICS S120 Booksize

NCU 710.3 PN configuration with SINAMICS S120 Combi

The following figure shows a typical configuration of the NCU 710.3 PN with SINAMICS S120 Combi:

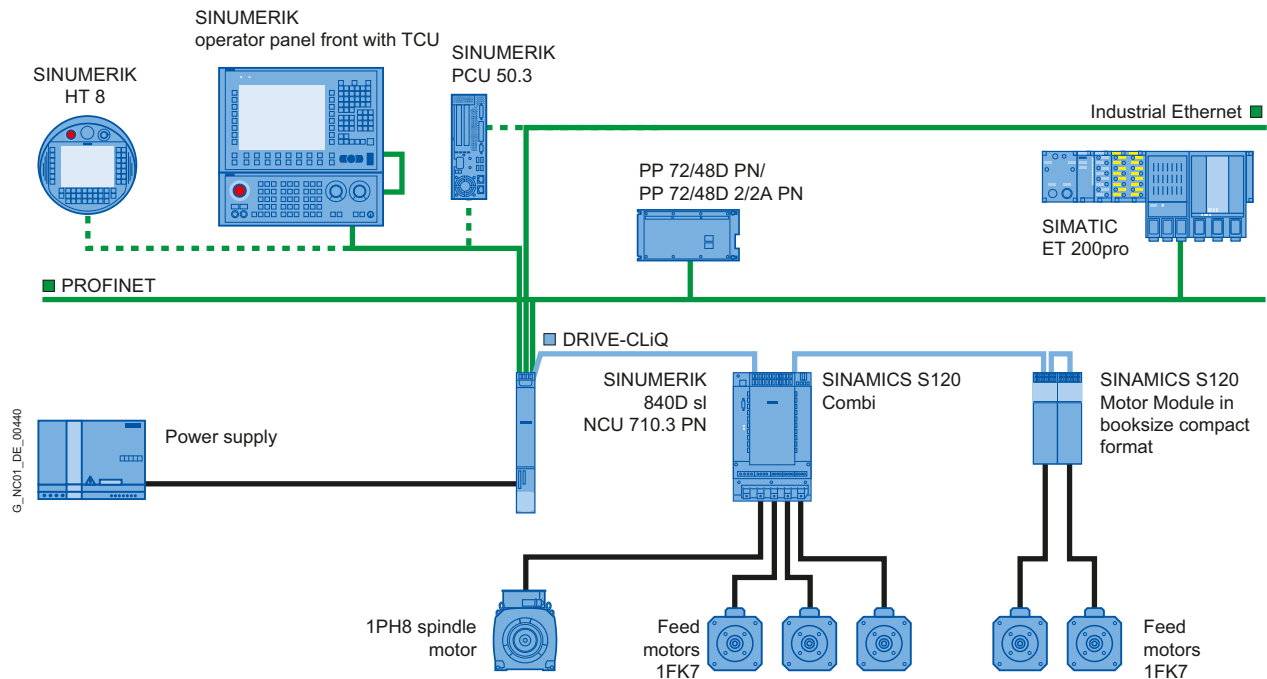


Figure 1-4 Example: SINUMERIK 840D sl configuration with SINAMICS S120 Combi

Note

SINAMICS S120 Combi

The configuration with SINAMICS S120 Combi is permissible only on an NCU 710.3 PN.

1.3 Initial commissioning procedure

Introduction

The mechanical and electrical installation of the system must be completed.

The following is important when starting commissioning:

- The controller with its components boots error-free.
- The EMC guidelines were carefully maintained when configuring the system.

Commissioning options depending on the CNC software on the CompactFlash card

When commissioning the system for the first time, the following dependencies to the CNC software on the CompactFlash card are considered:

- CompactFlash card with the current CNC software.
- CompactFlash card without CNC software.
- CompactFlash card with older CNC software.

Commissioning steps

The commissioning steps depending on the CNC software on the CompactFlash card are listed in the following table. The order is recommended but not mandatory:

Commissioning steps	With current CNC software (first commissioning)	Without CNC software (re-installation and initial commissioning)	With older CNC software (upgrade)	See chapter
Install the CNC software on the CompactFlash card using one of the following media: <ul style="list-style-type: none"> • Bootable USB-FlashDrive • WinSCP on PC/PG • VNC viewer on PC/PG Note: Upgrade the controller: New installation/upgrading (Page 343)		1.		Automatic installation of the CNC software using USB-FlashDrive (Page 344) Installation of the CNC software using WinSCP on PC/PG (Page 348) Installation of the CNC software using VNC Viewer on PC/PG (Page 349)
Archive the NCK, PLC, HMI and drive data			1.	Saving data (Page 319)


1.3 Initial commissioning procedure


Commissioning steps	With current CNC software (first commissioning)	Without CNC software (re-installation and initial commissioning)	With older CNC software (upgrade)	See chapter
Upgrade the CNC software using one of the following media: <ul style="list-style-type: none"> • Bootable USB-FlashDrive • WinSCP on PC/PG • VNC viewer on PC/PG 			2.	Automatic upgrade of the CNC software using USB-FlashDrive (Page 354) Upgrading the CNC software using WinSCP on PC/PG (Page 358) Upgrading the CNC software using VNC Viewer on PC/PG (Page 359)
Load the archived NCK, PLC, HMI and drive data			3.	Saving data (Page 319)
Boot the SINUMERIK 840D sl with NCK/PLC general reset	1.	2.		NCK and PLC general reset (Page 26)
Make a communication connection to the PLC	2.	3.		Setting up the communication (Page 33)
PLC commissioning	3.	4.		PLC commissioning (Page 33)
Commission the SINAMICS drive system	4.	5.		Commissioning NC-controlled drives (Page 67)
NCK ↔ drive communication	5.	6.		Communication between the NC and the drive (Page 155)
NCK commissioning <ul style="list-style-type: none"> • Assign the NCK machine data for communication • Scale the machine data • Parameterize the axis data • Parameterize the spindle data • Parameterize the measuring systems 	6.	7.		Commissioning the NC (Page 165)
Drive Optimization	7.	8.		Optimize the drive (Page 241)

Safety information

2.1 Danger notices

The following notices are intended firstly for your personal safety and secondly to prevent damage occurring to the product described or any connected devices and machines. Non-observance of the warnings can result in severe personal injury or property damage.

 DANGER
<p>Only appropriately qualified personnel may commission/start-up SINUMERIK equipment.</p> <p>The personnel must take into account the information provided in the technical customer documentation for the product, and be familiar with and observe the specified danger and warning notices.</p> <p>When electrical equipment and motors are operated, the electrical circuits automatically conduct a dangerous voltage.</p> <p>When the system is operating, dangerous axis movements may occur throughout the entire work area.</p> <p>A potential fire hazard exists due to the energy being transferred in the equipment and the work materials used.</p> <p>All work on the electrical system must be performed after the system has been switched off and disconnected from the power supply.</p>

 DANGER
<p>Proper transportation, expert storage, installation and mounting, as well as careful operation and maintenance are essential for this SINUMERIK device to operate correctly and reliably.</p> <p>The details in the catalogs and proposals also apply to the design of special equipment versions.</p> <p>In addition to the danger and warning information provided in the technical customer documentation, the applicable national, local, and system-specific regulations and requirements must be taken into account.</p> <p>Only protective extra-low voltages (PELVs) that comply with EN 61800-5-1 can be connected to all connections and terminals between 0 and 48 V.</p> <p>Should it be necessary to test or take measurements on live equipment, then the specifications and procedural instructions defined in Accident Prevention Regulation BGV A2 must be adhered to, in particular § 8 "Permissible deviations when working on live components". Suitable electric tools should be used.</p>

 **WARNING**

Power cables and signal lines should be installed in such a way that inductive and capacitive interference does not in any way impair the automation and safety functions.

 **WARNING**

Repairs to devices that have been supplied by our company may only be carried out by Siemens customer service or by repair centers authorized by Siemens. When replacing parts or components, only use those parts that are included in the spare parts list.

Before opening the device, always disconnect the power supply.

Emergency stop/off devices which comply with EN 60204 / IEC 60204 (VDE 0113-1) must remain effective in all automation equipment operating modes. The act of releasing the emergency stop/off device must not cause an uncontrolled or undefined hot restart.

Additional external measures must be taken, or devices must be created that enforce a safe operational state even when there is a fault (e.g. using independent limit value switches, mechanical locks, etc.) at any location in the automation equipment where faults might cause major material damage or even physical injury, in other words, where faults could be dangerous.

2.2 ESD notices

Note

Handling ESDS modules:

The modules contain electrostatically sensitive devices. Discharge yourself of electrostatic energy before touching the components. The easiest way to do this is to touch a conductive, grounded object immediately beforehand (for example, bare metal parts of the control cabinet or the protective ground contact of a socket outlet).

- When handling electrostatically sensitive devices, make sure that operator, workplace and packing material are properly grounded.
 - Generally, electronic modules must not be touched unless work has to be carried out on them. When handling PC boards make absolutely sure that you do not touch component pins or printed conductors.
 - Components may only be touched under the following conditions:
 - You are permanently grounded by means of an ESD armband.
 - You are wearing ESD shoes or ESD shoe grounding strips if there is an ESD floor.
 - Modules must only be placed on conductive surfaces (table with ESD surface, conductive ESD foam, ESD packaging, ESD transport container).
 - Keep modules away from visual display units, monitors or TV sets (minimum distance from screen 10 cm).
 - Do not bring electrostatically-sensitive modules into contact with chargeable and highly-insulating materials, such as plastic, insulating table tops or clothing made of synthetic materials.
 - Measurements may only be carried out on modules under the following conditions:
 - The measuring device is grounded (via a protective conductor).
 - When floating measuring equipment is used, the probe is briefly discharged before making measurements (e.g. a bare-metal controller housing is touched).
-

Requirements for commissioning

3.1 General prerequisites

Prerequisites for components involved

The complete system is connected mechanically and electrically, and has been verified in the following points:

- All ESD measures are observed for the design of the components.
- All screws are tightened with their prescribed torque.
- All connectors are plugged correctly and locked/screwed.
- All components are grounded and connected to shields.
- The load capacity of the central power supply is taken into account.

Limit values

All components are dimensioned for defined mechanical, climatic and electrical environmental conditions. No limit value may be exceeded, neither during operation, nor during transportation.

Special attention must be paid to the limit values:

- Power supply conditions
- Pollution burden
- Function-impairing gases
- Ambient environmental conditions
- Storage/transport
- Shock stressing
- Vibration stressing
- Ambient temperature

References

You can find further details in the following manuals:

- Installing the SINAMICS S120 drive components: SINAMICS S120 manuals
- Connecting the interfaces: NCU Equipment Manual
- Operator Components and Networking Manual, "Networking" chapter

3.2 Requirements for hardware and software

Preconditions

For the commissioning of SINUMERIK 840D sl, the following points are required:

- Hardware requirements
 - NCU 73x0.3 PN
 - CompactFlash card (8 GB, empty, MLFB: 6FC5313-6AG00-0AA0)
 - Dual fan / battery module (MLFB: 6FC5348-0AA02-0AA0) for NCU
 - PCU 50.5 (basic software V5XP1.3) or PCU 50.3 (basic software V8.6 SP3)

Note

Please dispose of used batteries in the specially provided collection points on site. This will ensure they are reused in the correct manner or treated as special waste.

- Connection to NCU
 - Network switch to X120
 - Ethernet connection from PG/PC to X120 or X127 for commissioning the PLC
 - Ethernet machine control panel to socket X120
 - Ethernet connection from the TCU to the Ethernet machine control panel
 - Ethernet connection from the PCU to the Ethernet machine control panel
- Software requirements
 - CNC software with SINUMERIK Operate, NCK, PLC and drive
 - SINUMERIK Operate for operation on the PCU
 - Commissioning tool on PG/PC V7.6 SP3 for commissioning the drive
 - SIMATIC STEP 7 V5.5 SP3 on PG/PC (SIMATIC Manager)
 - SINUMERIK 840D sl Toolbox for STEP 7 package
 - GSD file (Toolbox)

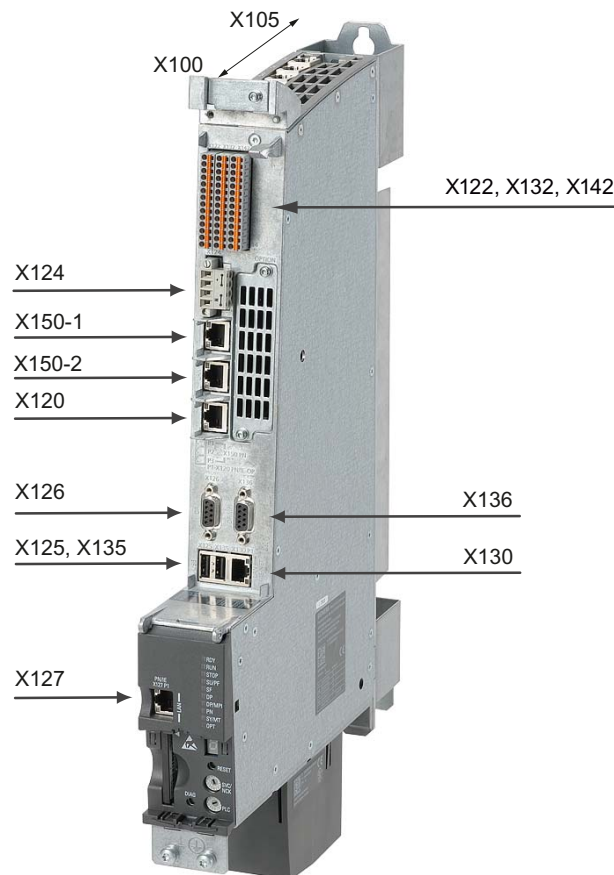
Note

The order numbers (MLFB) of the SINAMICS drives, encoders, and motors should be available for parameterization.

3.3 Position of the interfaces

Interfaces on the NCU

The NCU has the following interfaces:



X100 ... X105	DRIVE-CLiQ	for SINAMICS drive components
X124	+24 V DC	external power supply
X125, X135	USB	only for commissioning and servicing
X120	Industrial Ethernet	for connection to a system network (TCU and/or PCU)
X130	Industrial Ethernet	for connection to a company network
X127	Industrial Ethernet	service interface for PG/PC
X136	PROFIBUS DP / MPI	
X126	PROFIBUS DP	PROFIBUS DP (for example for PLC axes)
X150-1, X150-2	PROFINET IO	for PROFINET components
X122, X132, X142	Based on PROFINET	Digital inputs/outputs for I/O devices

Figure 3-1 Position of the interfaces

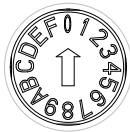
3.4 Power-On and boot-up

3.4.1 NCK and PLC general reset

SVC/NCK and PLC rotary switches

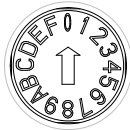
The NCU has two rotary switches in the lower section of the front panel.

NCK commissioning switch



SVC/
NCK

PLC mode selector



PLC

The settings on the SVC/NCK switch have the following meaning:

Switch position	NC operating mode
0	NC normal boot-up
1	NC boot-up with default values (= memory reset)
2	The NC (and PLC) boots up with the data that was saved at the last shutdown
7	Debug mode (NC is not started)
8	IP address of the NCU is displayed on the seven-segment display
All others	Not relevant

The settings on the PLC switch have the same meaning as for a SIMATIC S7-CPU:

Switch position	Operating mode of the PLC
0	RUN
1	RUN (protected mode)
2	STOP
3	Memory reset (MRES)
All others	Not relevant

Initial commissioning

In order to achieve a defined initial state of the complete system, for the initial commissioning of the NCU, a general reset of the NC and the PLC must be performed.

Note

In the following cases, a general PLC reset must always be performed:

- Initial commissioning
 - Module replacement
 - General reset request by the PLC
 - Upgrading the PLC
-

Procedure:

1. Set the rotary switch of the NCU to the following settings:
 - NCK commissioning switch: Switch position "1"
 - PLC mode selector switch: Switch position "3"
2. Initiate a power-on reset by switching-off the control and switching-on again – or by pressing the Reset button on the front of the NCU. The NCU is terminated and with the request for a general reset is restarted.

Effect:

- The "STOP" LED flashes.
- The "SF" LED illuminates continuously.

3. Within approx. three seconds, turn the PLC mode selector switch to the positions "2" → "3" → "2".

Effect:

- The "STOP" LED first flashes with about 2 Hz and then illuminates continuously.

4. Turn the PLC mode selector switch back to the "0" position.

Effect:

- The "STOP" LED extinguishes.
- The "RUN" LED flashes initially and then illuminates green continuously.

5. Turn the NCK commissioning selector switch back to the "0" position.

Result

The NCU has now been generally reset and is in the following state:

- NC
 - The user data is deleted.
 - The system data is initialized
 - The standard machine data is loaded
- PLC
 - The general reset places the PLC in a defined initial state:
 - The user data has been deleted (data and program blocks).
 - The system data blocks (SDB) have been deleted.
 - The diagnostics buffer and the MPI parameters have been reset.

The "RUN" LED illuminates. NC and PLC are in cyclic operation.

Note

PLC general reset

If a general PLC reset is performed using a power-on reset, then the user data must again be transferred to the PLC, e.g. via a programming device (PG).

After the PLC general reset, no PLC start is performed and at least the following alarm issued:

- Alarm: "2001 PLC not booted"

These alarms have no influence on the next steps.

3.4.2 Separate NCK and PLC general reset

NCK general reset

Carry out the following actions to perform an NCK general reset:

1. Turn the NCK commissioning switch on the front of the NCU to position "1".
2. Initiate a power on reset by switching-off the controller and switching-on again - or by pressing the Reset button on the front of the NCU (labeled "RESET").
The NCU is terminated and with the request for a general NCK reset is restarted.
3. After the NCU has booted, turn the NCK commissioning switch back to position "0".

Effect:

- The number "6" and a flashing point are output on the status display (7-segment display) on the front of the NCU
- "RUN" LED is lit

The NCU is in the following state after an error-free boot-up:

- The static memory of the NCU is deleted.
- The machine data is preassigned standard values.
- The NCK is in cyclic operation.

Alternatives

A PLC general reset can be performed with or without power-on reset. Depending on this, various states result for the PLC user program.

PLC general reset without power-on reset

Perform the following operator actions for a PLC general reset **without** power-on reset:

1. Turn the PLC mode selector switch on the front of the NCU to position "2" (STOP).

Effect:

- The PLC goes into the "STOP" mode.
- The "STOP" LED illuminates.

2. Turn the PLC mode selector switch to position "3" (MRES)

Effect:

- The "STOP" LED goes dark and after approx. three seconds illuminates again.

3. Within approx. three seconds, turn the PLC mode selector switch to the positions "2" → "3" → "2"

Effect:

- The "STOP" LED first flashes with about 2 Hz and then illuminates continuously.

4. Turn the PLC mode selector switch back to the "0" position.

Effect:

- The "STOP" LED extinguishes.
- The "RUN" LED illuminates.

A general reset has now been performed for the PLC and it is in cyclic transmission with the following properties:

- The time of day and the operating hours counter have not been reset.
- The diagnostics buffer and the MPI parameters have not been reset.

PLC general reset with power-on reset

Perform the following operator actions for a PLC general reset **with** power-on reset:

1. Turn the PLC mode selector on the front of the NCU to position "3" (MRES).
2. Initiate a power-on reset by switching-off the control and switching-on again – or by pressing the Reset button on the front of the NCU. The NCU is terminated and with the request for a general reset is restarted.

Effect:

- The "STOP" LED flashes.
- The "SF" LED illuminates continuously.

3. Within approx. three seconds, turn the PLC mode selector switch to the positions "2" → "3" → "2".

Effect:

- The "STOP" LED first flashes with about 2 Hz and then illuminates continuously.

4. Turn the PLC mode selector switch back to the "0" position.

Effect:

- The "STOP" LED extinguishes.
- The "RUN" LED flashes initially and then illuminates green continuously.

The general reset places the PLC in a defined initial state:

- The user data has been deleted (data and program blocks).
- The system data blocks (SDB) have been deleted.
- The diagnostics buffer and the MPI parameters have been reset.

Note

For the general reset without power-on reset, the most recently loaded blocks from the PLC user program are reimported.

Boot completed without error

After an error-free boot of the NCU, the following status is displayed:

- The number "6" and a flashing point
- The "RUN" LED illuminates green continuously.

In the following step, commissioning of the PLC is done with the SIMATIC Manager.

3.5 Access levels

Access to functions and machine data

The access concept controls access to functions and data areas. Access levels 0 to 7 are available, where 0 represents the highest level and 7 the lowest level. Access levels 0 to 3 are locked using a password and 4 to 7 using the appropriate key-operated switch settings.

Access level	Locked by	Area	Data class
0	---	(reserved)	---
1	Password: SUNRISE	Manufacturer	Manufacturer (M)
2	Password: EVENING	Service	Individual (I)
3	Password: CUSTOMER	User	User (U)
4	Key-operated switch setting 3	Programmer, machine setter	User (U)
5	Key-operated switch setting 2	Qualified operator	User (U)
6	Key-operated switch setting 1	Trained operator	User (U)
7	Key-operated switch setting 0	Semi-skilled operator	User (U)

The password remains valid until it is reset with the "Delete Password" softkey. The passwords can be changed after activation.

If, for example, the passwords are no longer known, reinitialization (boot-up with "NCK default data") must be carried out. This resets all passwords to the default (see table). POWER ON does not reset the password.

Key-operated switch

Access levels 4 to 7 require a corresponding key-operated switch setting on the machine control panel. Three keys of different colors are provided for this purpose. Each of these keys provides access only to certain areas.

Meaning of the key-operated switch settings:

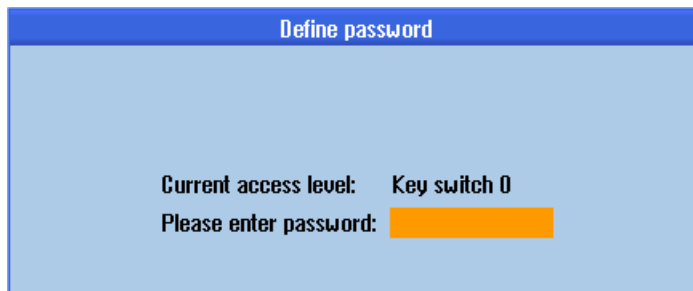
Access level	Switch position	Key color
4-7	0 to 3	red
5-7	0 to 2	green
6-7	0 and 1	black
7	0 = Key removal position	No key inserted

The key-operated switch setting must always be edited from the PLC user program and applied to the interface accordingly.

Set password

To change the access level, select the "Start-up" operating area:

1. Press the "Password" softkey.
2. Press the "Set password" softkey to open the following dialog:



Define password

Current access level: Key switch 0

Please enter password:

Figure 3-2 Set password

3. Enter a password and confirm this with "OK" or with the <Input> key.

A valid password is acknowledged as set and the currently applicable access level is displayed. Invalid passwords will be rejected.

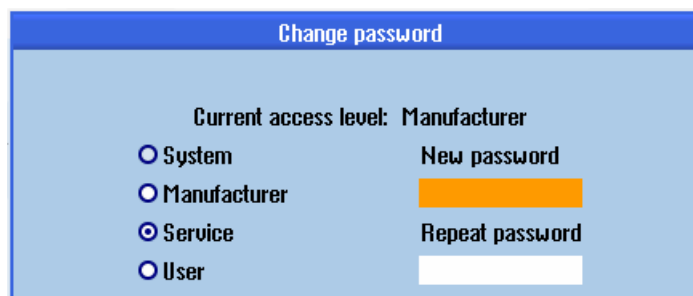
4. You must delete the old password before activating a password for a lower access level than the one activated.

The last valid password is deleted by pressing the "Delete password" softkey. Then the current key-operated switch setting is valid.

Change password

To change the password:

1. Press the "Change password" softkey to open the following dialog:



Change password

Current access level: Manufacturer

☐ System New password

☐ Manufacturer

☒ Service Repeat password

☐ User

Figure 3-3 Change password

2. Enter the new password in both fields and then confirm with the "OK" softkey. If both passwords match, the new password becomes valid and is adopted by the system.

PLC commissioning

4.1 Connect PG/PC with the PLC

4.1.1 Setting up the communication

Introduction

SIMATIC Manager is a GUI for online/offline editing of S7 objects (projects, user programs, blocks, hardware stations and tools).

You can perform the following actions with the SIMATIC Manager:

- Manage projects and libraries
- Call STEP 7 tools
- Establish an online connection to the PLC

A corresponding editing tool is started up when you open the relevant objects. The program editor starts by double-clicking a program block. The block can be processed.

Starting SIMATIC Manager

After installation, the SIMATIC Manager icon appears on the Windows desktop, and in the Start menu a "SIMATIC Manager" program item appears under "SIMATIC".

- Start the SIMATIC Manager by double-clicking the link on the Windows desktop or from the Start menu.
- The online help for the active window is always called by pressing the <F1> function key.

Establishing a communications connection to the PLC

To load the configuration into the PLC, the communications connection (Ethernet) from the PG/PC to the PLC required for the loading must be secured.

Procedure:

1. Select menu command: "Extras" > "Set PG/PC interface..."
2. Under the "Access mode" tab, look for the interface used in the "Interface parameterization used" selection field, for instance: "TCP/IP → Realtek RTL8139/810x F..."
3. Confirm the parameterization with "OK".

Note

Parameterization of the PG/PC interface can be performed or changed from the SIMATIC Manager at any time.

4.2 Creating a SIMATIC S7 project

4.2.1 SIMATIC S7 project overview

Steps to be taken

It is necessary to create a SIMATIC S7 project for the basic commissioning of the PLC, the Ethernet and PROFIBUS communication as well as the input/output data areas of the NCK. To do this, perform the following steps:

- Create a project
- Insert a SIMATIC station 300
- Insert an NCU to the hardware configuration
- Configure the network interfaces
- Insert the machine control panel and hand wheel

What do you need to be aware of?

Loading the PLC via network interface X130 is also possible if the IP address of the Ethernet interface is known. Loading an archive may always be carried out if the communication HMI↔NCK is available.

Note

Loading the PLC (CP840) is essential for the configuration of the data path for saving/restoring the drive data.

References

The PLC interface signals are described in:

- "NC Variables and Interface Signals" List Manual
- Function Manual, Basic Functions; Section "NC/PLC Interface Signals (Z1)"

Operating sequence

You have started the SIMATIC Manager.

1. To create a new project, select the "File" → "New" menu command in the SIMATIC Manager.
2. Enter the project data:
 - Name (for example: SINU_840Dsl)
 - Storage location (path)
 - Type
3. Confirm the dialog with "OK".

The project window is displayed showing an empty S7 project structure.

4.2.2 Inserting SINUMERIK NCU to the HW Config

Overview

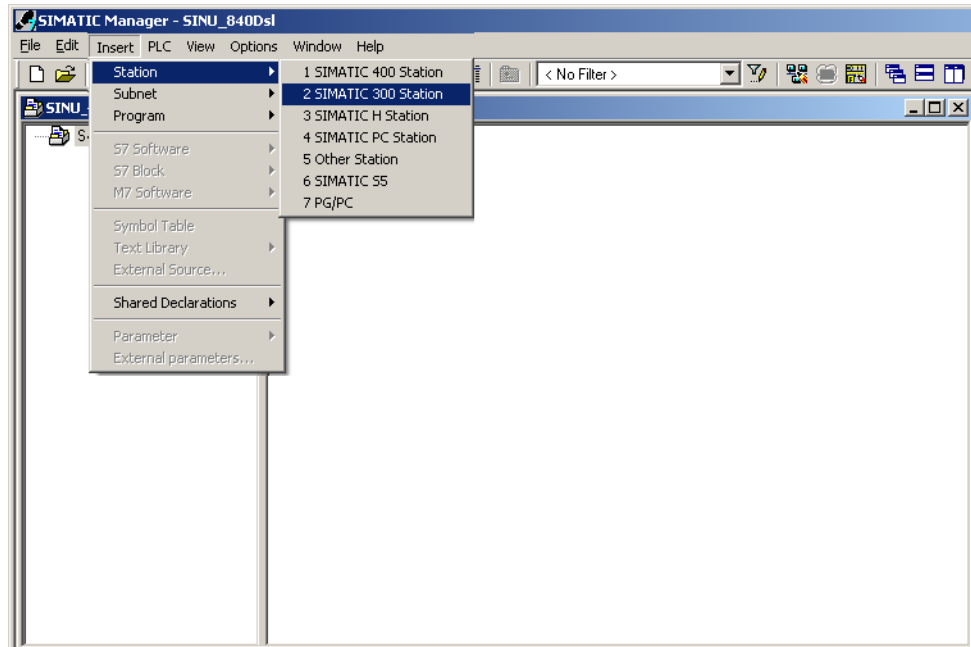
Insert the necessary hardware in the following order in the S7 project:

- Insert a SIMATIC station 300
- Start the hardware configuration
- Insert a SINUMERIK NCU

Operating sequence

Procedure:

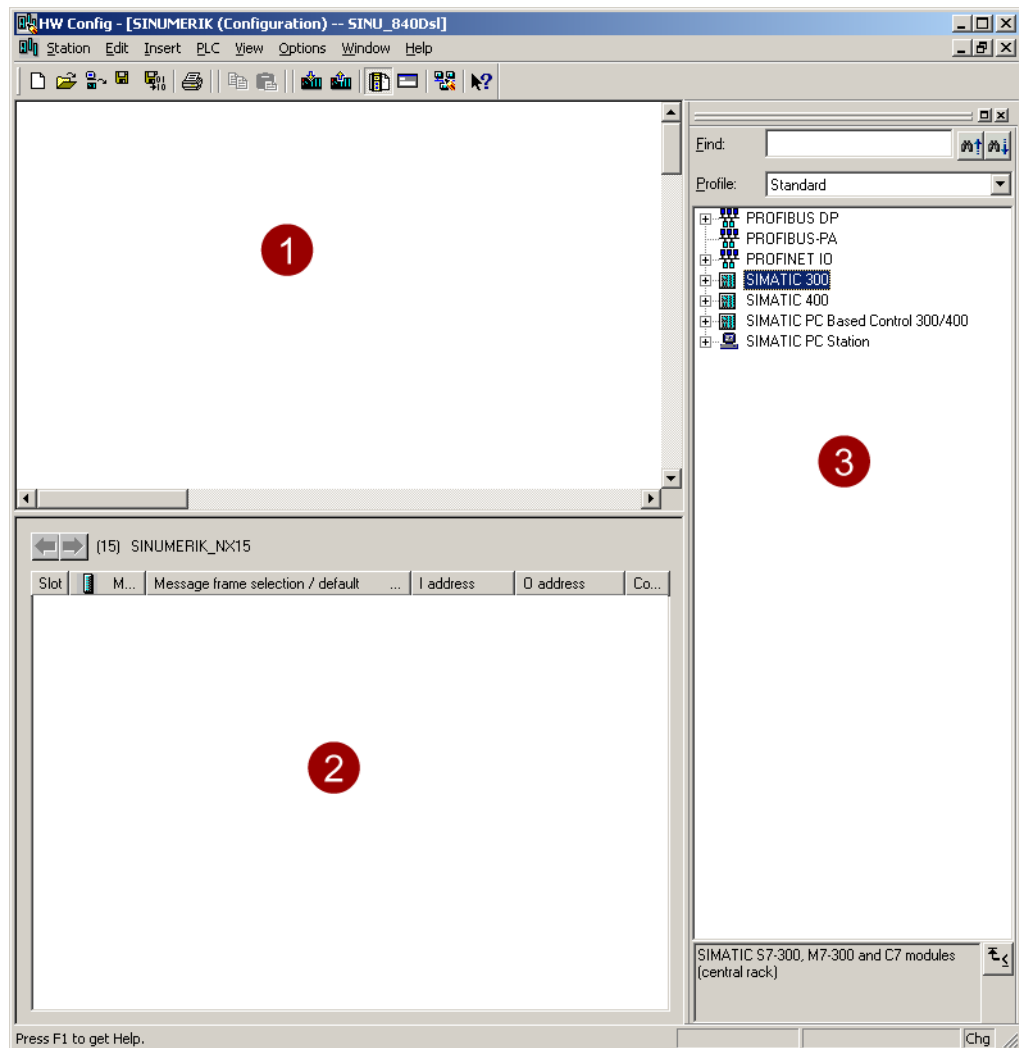
1. Select via the context menu (right-click) "Insert new object" > "SIMATIC 300 station".



2. Double-click the <SIMATIC 300> symbol.
3. Double-click the <Hardware> symbol.

The HW Config for introducing required hardware is started.

4. In the menu, select "View" > "Catalog". The catalog with the modules is displayed.



- ① Station window:
- ② Details
- ③ Hardware catalog

The user interface of the "HW Config" hardware configuration shows the following details:

- Station window:

The station window is split. The upper part displays the structure of the station graphically, and the lower part provides a detailed view of the selected module.

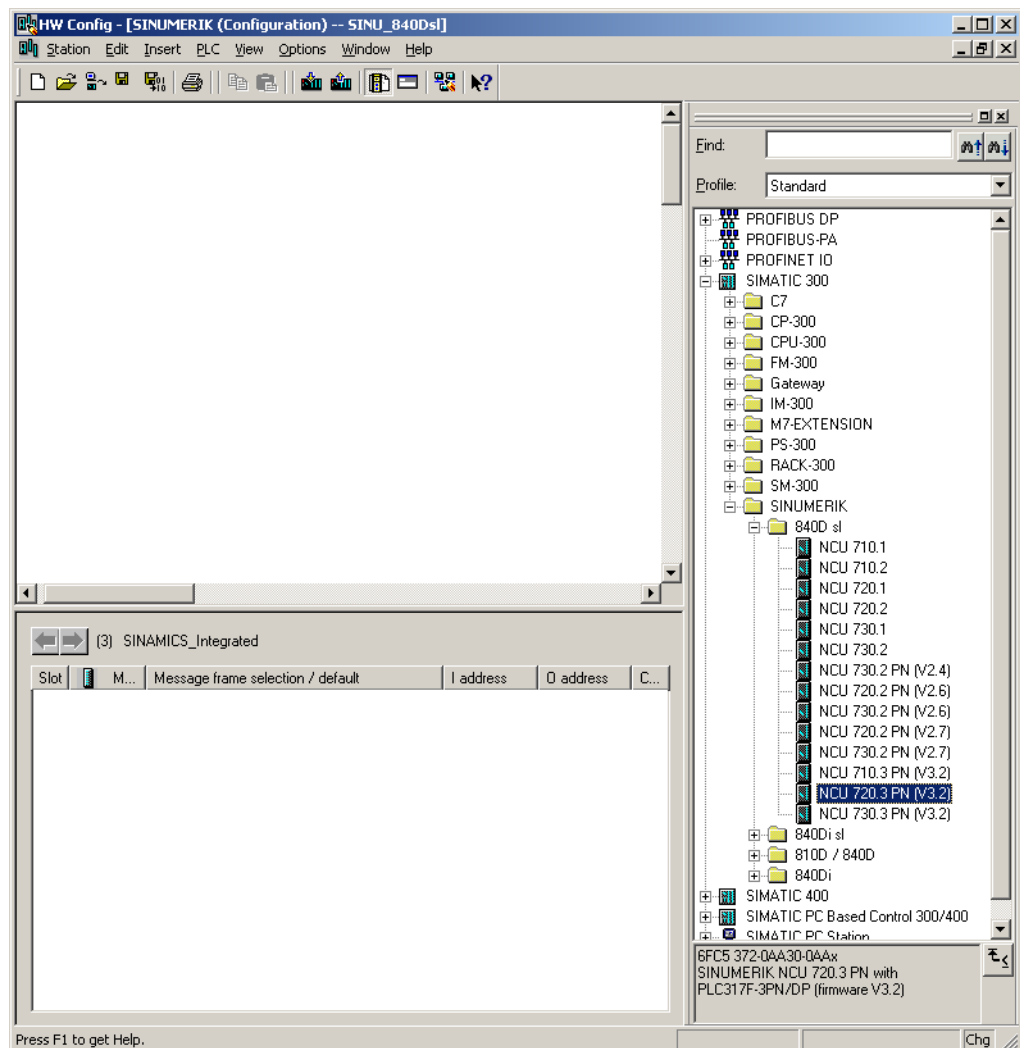
- Hardware catalog

This catalog also contains the SINUMERIK NCU that you need for configuring the hardware.

Inserting a SINUMERIK NCU

With the operating sequence described below, you insert the NCU 720.3 PN as example:

1. Select "View" > "Catalog".
2. Search for the module in the catalog under "SIMATIC 300" → "SINUMERIK" → "840D sl" > "NCU 720.3 PN".



3. Select "NCU 720.3 PN" with the left mouse button and drag it to the "Station design" station window while keeping the mouse button pressed.

After you release the mouse button, configure in the dialog the properties of the interfaces of the CP 840D sl processor present on the NCU 720.3 PN.

4.2.3 Configure the network interfaces

Introduction

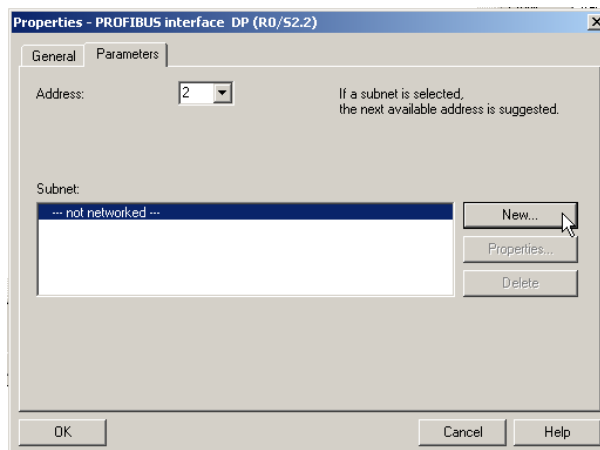
Configure the following network interfaces in the STEP 7 project over which you want to reach the NCU:

- Ethernet
- Integrated PROFIBUS
- PROFIBUS DP, only with machine control panel for PROFIBUS (see Configure PROFIBUS components (Page 389))

When creating a new project using the catalog, the configuration of the PROFIBUS interface is called automatically.

PROFIBUS DP operating sequence

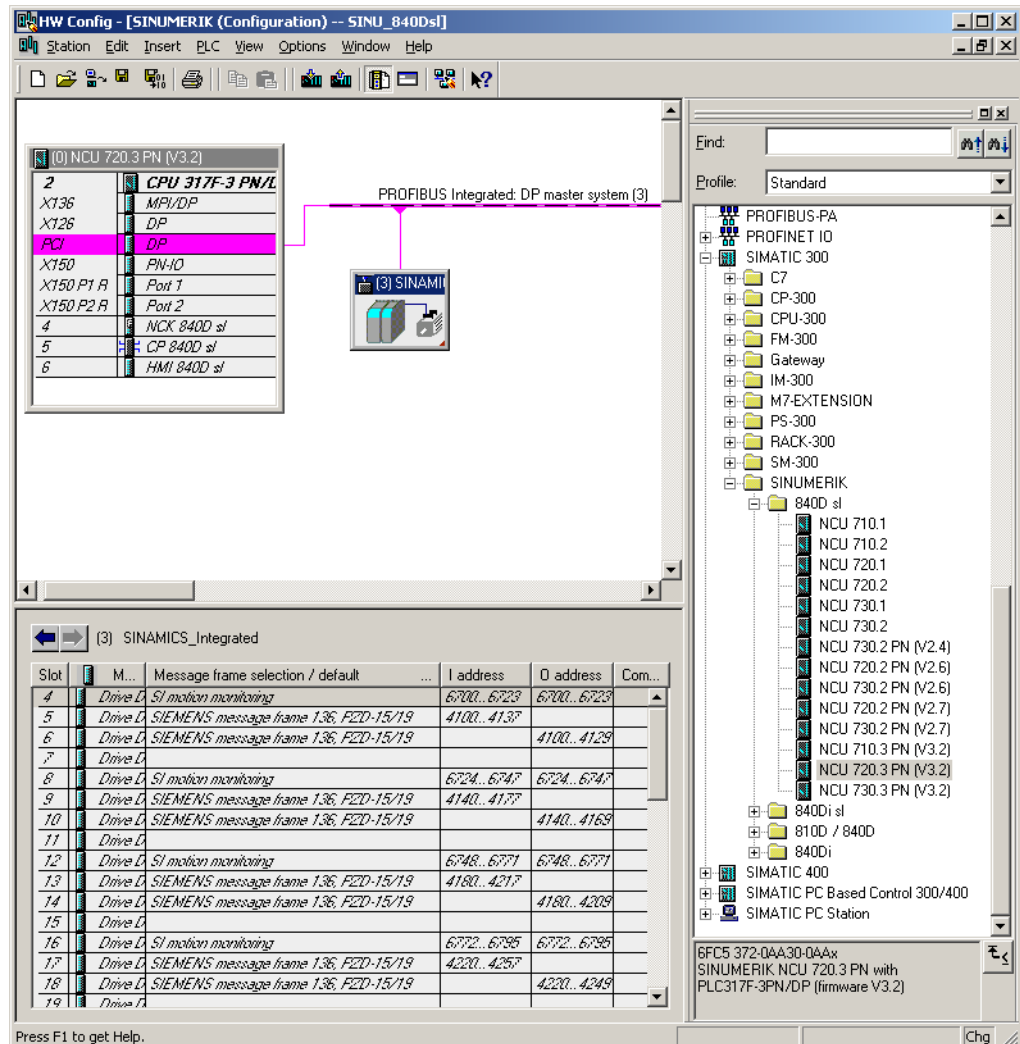
1. You used the left mouse button to select an NCU and while holding down the mouse button you dragged it to the "Station design" station window.
2. After you release the mouse button, configure the properties of the PROFIBUS DP interface for socket X126 (machine control panel) in the dialog.



3. This is an Ethernet machine control panel that does not require configuration. Select "Cancel".
4. The NCU module with SINAMICS S120 is inserted into the HW Config.

Note

With the <F4> key and confirmation of the prompt regarding "Reorganize", you can reorganize the display in the station window.



Next, specify the properties for the Ethernet interface.

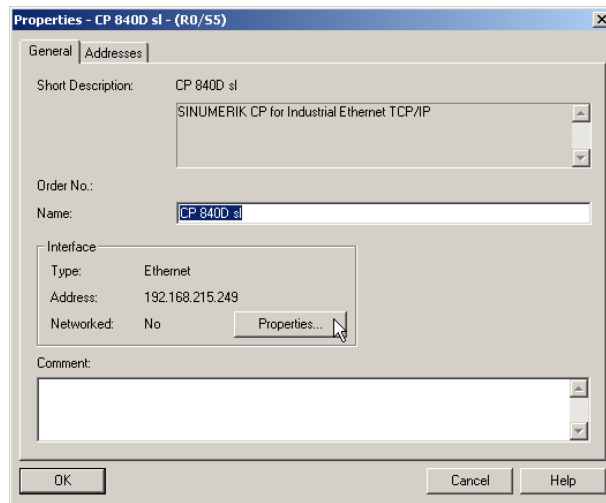
Operating sequence for Ethernet interface

Note

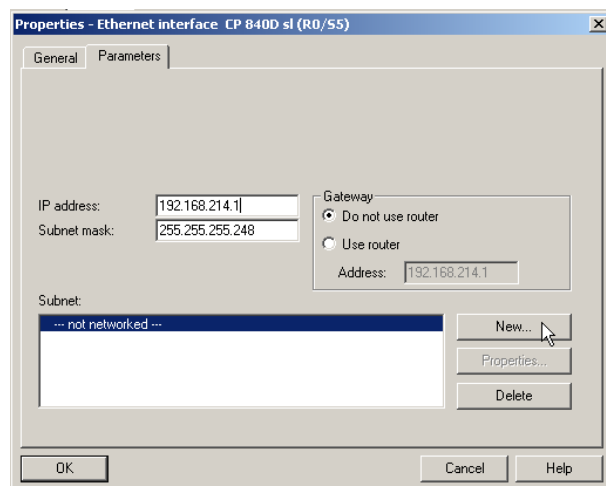
Use the X127 service interface for commissioning the PLC. No configuration of the Ethernet interface is required for this. This interface is already initialized with the IP address 192.168.215.1

For the initial commissioning with a PG/PC, it is necessary to configure an Ethernet interface. In our example, this involves the interface to socket X120.

1. Double-click "CP 840D sI" in the basic rack of the NCU. The "Properties - CP 840D sI" dialog opens.



2. After clicking the "Properties" button, a new Ethernet interface can be created.



3. For socket X120, enter the IP address "192.168.214.1" and the Subnet screen form "255.255.255.0".
4. Create the Ethernet interface using "New" and then "OK".
5. Click "OK" twice.

As the next step, configure the Web browser of the PLC.

See also

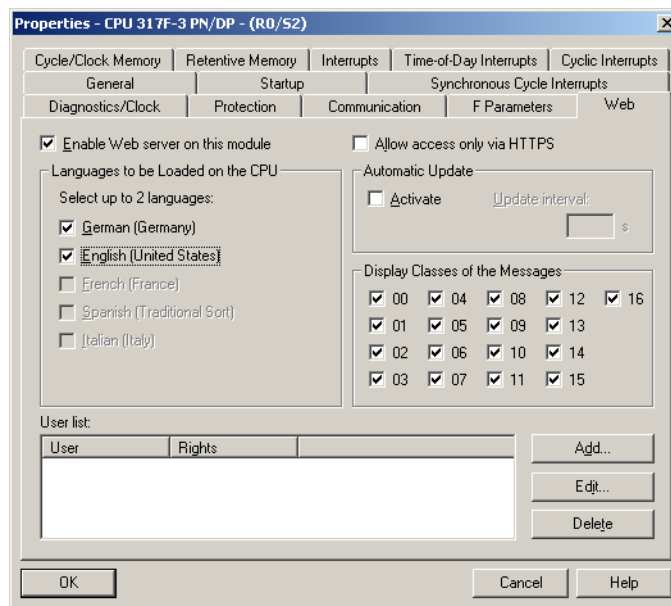
Configuring the communication to the drive (Page 157)

4.2.4 Configuring the Web browser

Operating sequence

1. Click the SINUMERIK module in the hardware configuration.

The following dialog opens:



2. Select the "Web" tab.
3. Select the option: "Enable the Web server on this module".

If the checkbox is selected, after loading the configuration data, the Web server of the CPU is started and information can be read from the PLC via a Web browser.

4. Select the language for language-dependent texts to be loaded into the CPU.

The number of available languages is CPU-dependent. Examples of language-dependent texts are diagnostics buffer entries or messages.

Note

Available languages

The languages you select here must be installed in the S7 project. You can install the languages for the project in the SIMATIC Manager from "Extras" → "Language for display devices ..."

If the languages you select in the SIMATIC Manager have not been installed previously, the Web server can only display texts in the set default language.

5. Activate the "Automatic update" if you want the Web pages to be updated automatically. The "Identification" Web page is excluded from the automatic update.

Telegram lengths and I/O addresses

The telegram lengths and I/O addresses for communication between the PLC and the drive (can be viewed via the object properties of the integrated SINAMICS) have already been pre-assigned correctly and do not need to be configured.

As the next step insert an NX component.

4.2.5 Inserting an NX to the hardware configuration

Introduction

The NX must be wired to the NCU via the DRIVE-CLiQ. A fixed DRIVE-CLiQ socket is provided for the relevant address. The following table contains the wiring:

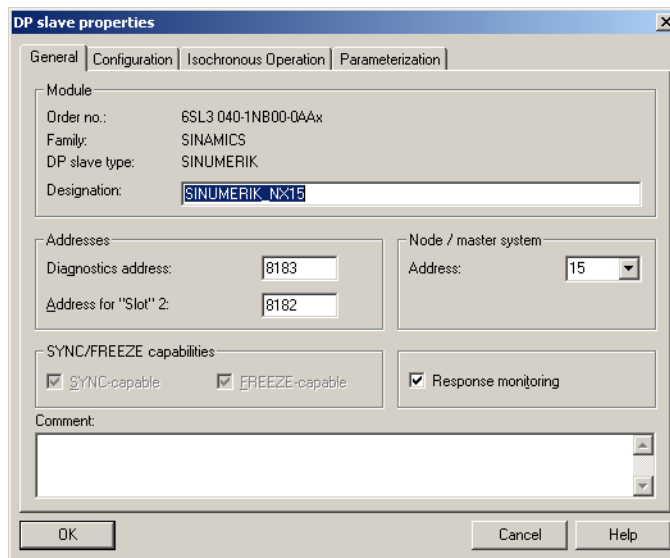
Address on the integrated PROFIBUS	DRIVE-CLiQ interfaces NCU 720.3 PN / 730.3 PN	DRIVE-CLiQ interfaces NCU 710.3 PN
10	X100	X100
11	X101	X101
12	X102	X102
13	X103	X103
14	X104	--
15	X105	--

Operating sequence

An NX component is contained in the example configuration, for the axis to control the spindle. This component must be integrated in the hardware configuration also when creating the STEP 7 project:

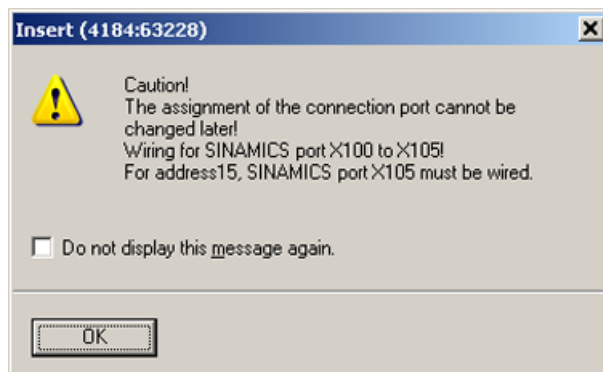
1. Search for the NX module NX15.3 in the hardware catalog under "PROFIBUS DP" > "SINAMICS" > "SINUMERIK NX...".
2. Left-click to select the "SINUMERIK NX ..." module and drag it to the "PROFIBUS Integrated DP master system" bus in the "Station design" station window.

3. The "DP Slave Properties" dialog box opens.



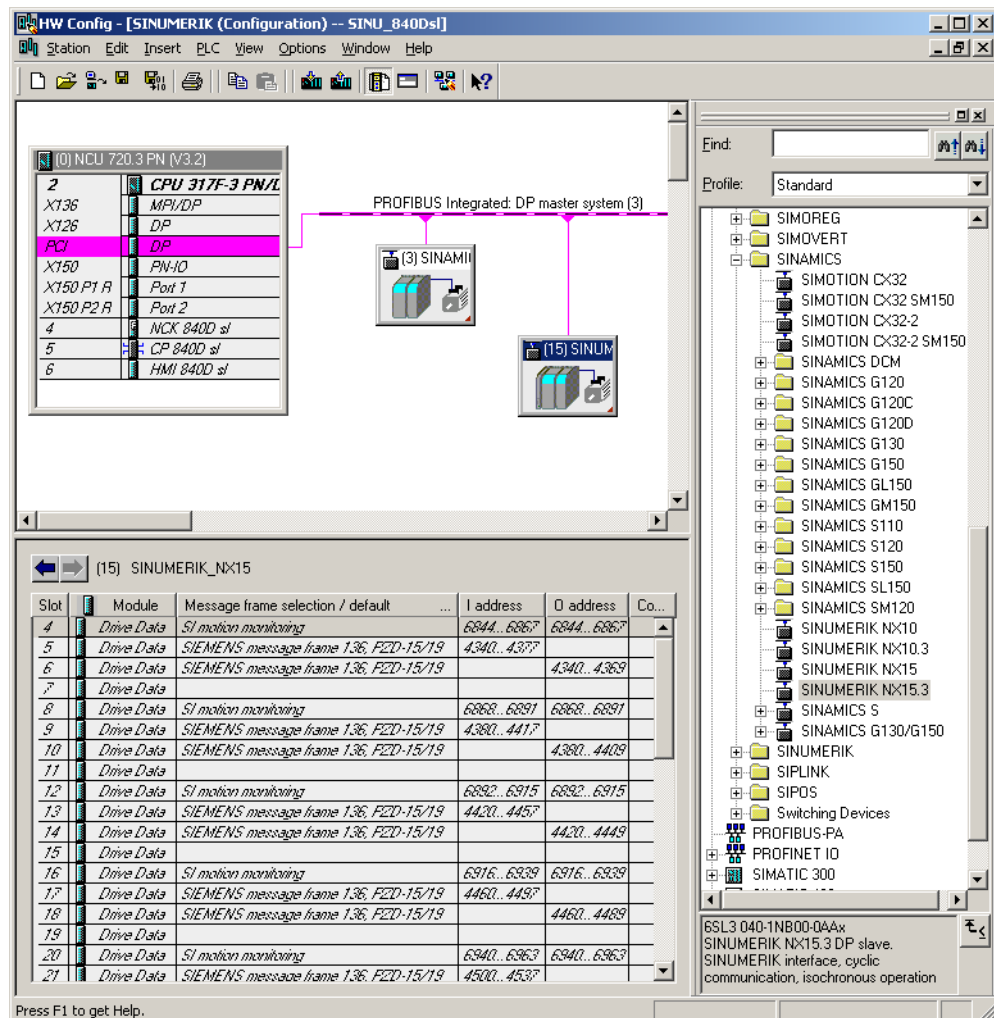
Enter the address for the integrated PROFIBUS in this dialog. "15" is proposed for the first NX in a configuration.

4. Enter the address and click "OK".



5. Confirm the wiring notification with "OK".

6. After releasing the mouse key, you have inserted the NX module:



When deleting and re-inserting NX modules in the hardware configuration, new slot addresses are assigned during the address assignment. In order to create a clear and transparent configuration that is always the same, we recommend that addresses are allocated as shown in the following table:

Address on the integrated PROFIBUS	DRIVE-CLiQ interface, e.g. NCU 720.3 PN	Start address of first controller slot	Start address of last controller slot
10	X100	5540	5740
11	X101	5300	5500
12	X102	5060	5260
13	X103	4820	5020
14	X104	4580	4780
15	X105	4340	4540

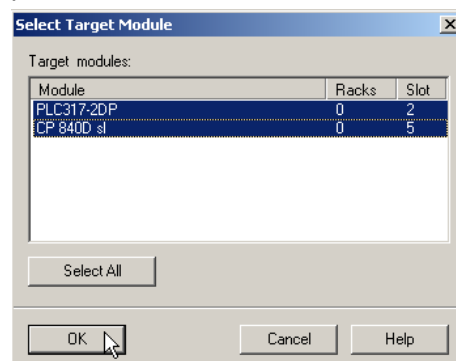
4.2.6 End the hardware configuration and load it to the PLC

End the hardware configuration and load the to the PLC

To end the overall configuration and generate the system data for the PLC, the project must be saved and compiled.

1. Select the "Station" > "Save and compile" menu.
2. Click the "Load in module" button to load the configuration to the PLC.

The "Select target module" dialog automatically displays both configured communication partners.



3. Confirm with OK to load into these two modules.
4. Confirm the dialog boxes displayed subsequently with "OK" or "No" for the query "...Should the module be started now (restart)?".

Note

You can test the communication interface at "Target system > Diagnosis > Operating mode".

5. Close the "HW Config" window.

The next step is to create the PLC program.

4.3 Creating a PLC program

Introduction

The PLC program is constructed modularly. It comprises the two parts:

- PLC basic program

The PLC basic program organizes the exchange of signals and data between the PLC user program and the NCK, HMI, and machine control panel components. The PLC basic program is a part of the Toolbox delivered with the SINUMERIK 840D sl.

- PLC user program

The PLC user program is the user-specific part of the PLC program by which the PLC basic program has been added to or extended.

FB 1 (start-up block of the PLC program) must be assigned variables. A precise description of the variables and options for modifying their parameterization can be found in:

Literature

Function Manual, Basic Functions, PLC Basic Program (P3)

Cyclical mode (OB 1)

From a chronological viewpoint, the basic program runs ahead of the PLC user program. The complete processing of the NCKPLC interface is carried out in cyclic mode. A cyclic monitoring function is activated between PLC and NCK once boot-up and the first OB1 cycle have been completed. A PLC failure produces alarm "2000 Sign-of-life monitoring PLC".

PLC user program

The following organization blocks of the basic program contain the entry points for the appropriate parts of the PLC user program:

- OB100 (cold restart)
- OB1 (cyclic processing)
- OB40 (process alarm)

The following figure illustrates the structure of the PLC program:

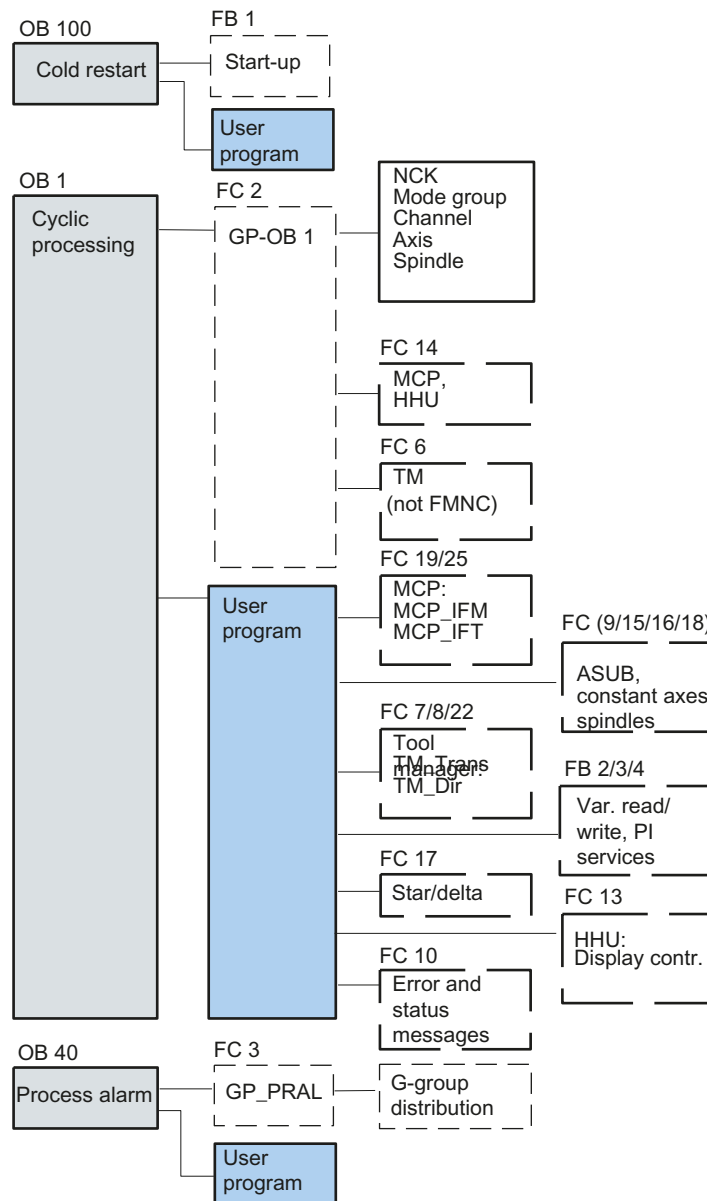


Figure 4-1 Structure of the PLC program

PLC status

The PLC always starts up in RESTART mode, i.e. the PLC operating system runs OB100 after initialization and starts cyclic operation at the beginning of OB1. No return is made to the interruption point (for example, in the event of a power failure).

Start-up behavior of the PLC

There are both remanent and non-remanent areas for the markers, timers and counters. The areas are continuous and are divided by a parameterizable limit, where the area with the higher-value address range is defined as the non-remanent area. Data blocks are always remanent.

Start-up mode COLD RESTART (OB 100)

If the remanent area has no battery backup (backup battery is empty) start-up is prevented. The following operations are performed during a cold restart:

- UStack, BStack and non-retentive flags, timers and counters are deleted
- The process output image (POI) is deleted
- Process and diagnostics alarms are canceled
- The system status list is updated
- Parameterization objects of modules (from SD100 onwards) are evaluated or default parameters are output to all modules in single-processor mode
- Execute cold restart (OB100)
- Read in process input image (PII)
- Cancel command ouptput inhibit (BASP)

4.3.1 Preconditions for creating the PLC user program

Software and hardware preconditions

The following conditions must be met for creating a PLC user program:

- SIMATIC STEP 7 V5.5 SP1
- SIMATIC STEP 7 is installed on the PG/PC
- Installing the toolbox (PLC basic program, slave OEM, GSD files)
- Editing the blocks in the PLC basic program
- Installing the PLC basic program library

To be able to use the blocks of the PLC basic program (OBs, FBs, DBs) in a SIMATIC S7 project, the library must first be installed in the SIMATIC Manager.

Editing the blocks in the PLC basic program

The operating sequence for the creation of a PLC program describes how to create a basic program. The SIMATIC STEP 7 documentation describes how to modify and extend a user program.

The individual blocks in the PLC basic program can be processed as follows in the SIMATIC Manager:

- Select the appropriate block, e.g. OB 100, in the folder blocks of the corresponding module
- Use the "Edit" > "Open object" menu command to open the block or double-click the block with the left mouse button
- Edit the block using the LAD/STL/CSF editor. Switch over to the block display using the "View" > "LAD" or STL or CSF menu command

4.3.2 Insert PLC basic program

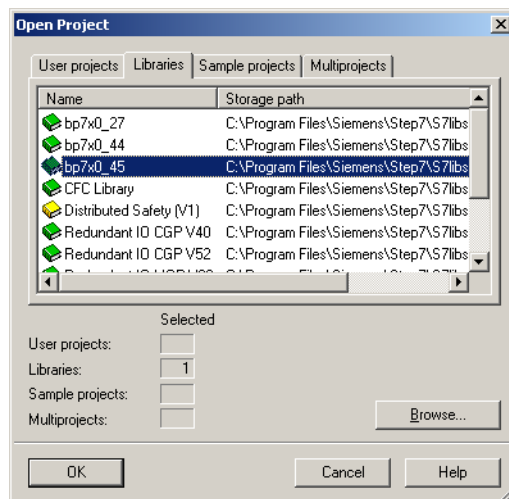
Introduction

You have performed the hardware configuration, have saved and compiled the project and have created the system data for the PLC. You have installed the Toolbox software that also contains the libraries for the PLC basic program of an NCU.

Operating sequence to open the library and copy sources, symbols and blocks

You are on the main screen of the SIMATIC Manager:

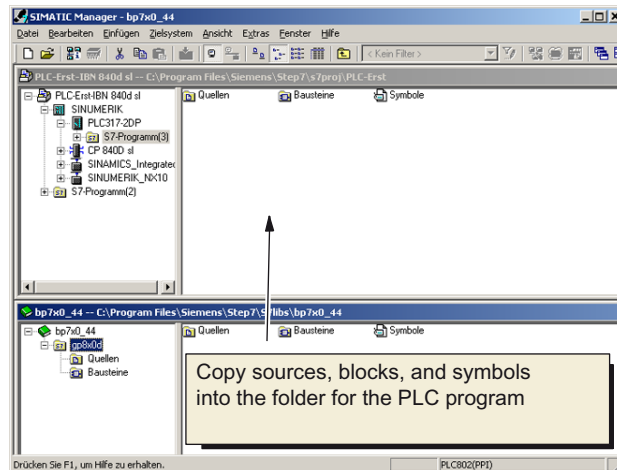
1. Select the "File" → "Open" menu and then click the "Libraries" tab.



4.3 Creating a PLC program

2. Select the library of the PLC basic program, e.g. "bp7x0_45" and confirm the dialog with "OK".

You have inserted the library and selected the PLC program from "SINU_840Ds" > "SINUMERIK" → "PLC 317 2DP" → "S7 program".



3. Copy the sources, modules and symbols to the PLC program.

Overwrite OB1

Inserting blocks overwrites the existing organization block OB1. Confirm the query as to whether you want to overwrite the block with "Yes".

You have now created the PLC basic program.

In the next section you will modify some of the data for the machine control panel in OB100.

4.3.3 Modifying machine control panel in OB100

Introduction

The PLC base program transfers the signals from the machine control panel. To ensure that the signals are transferred correctly to and from the machine control panel, enter the following parameters in the OB100 on the FB1.

Double-click OB100 the editor to configure the machine control panel below "Blocks".

Example: MCP1 is connected via Industrial Ethernet (IE).

Another example for the connection of the machine control panel via PROFIBUS DP can be found at:

Modifying PROFIBUS machine control panel in OB100 (Page 395)

Configuring the machine control panel

OB100

```
CALL "RUN_UP" , "gp_par"      FB1 / DB7 -- Startup Baseprogram/ Parameters for
Baseprogram

MCPNum :=1                      // An MCP is present
MCP1In :=P#E 0.0
MCP1Out :=P#A 0.0
MCP1StatSend :=P#A 8.0
MCP1StatRec :=
MCP1BusAdr :=192                // IP address: 192.168.214.192 - this
                                // address must also be set on the DIPFIX
                                // switch of the MCP.
MCP1Timeout :=
MCP1Cycl :=
MCP2In :=
MCP2Out :=
MCP2StatSend :=
MCP2StatRec :=
MCP2BusAdr :=
MCP2Timeout :=
MCP2Cycl :=
MCPMPPI :=FALSE
MCP1Stop :=FALSE
MCP2Stop :=
MCP1NotSend :=FALSE
MCP2NotSend :=
MCPSDB210 :=
MCPCopyDB77 :=
MCPBusType :=B#16#05           // Parameter [5] := ETHERNET

BHG :=
BHGIN :=
BHGOut :=

...

UDInt :=
UDHex :=
UDReal :=
IdentMcpType :=
IdentMcpLengthIn :=
IdentMcpLengthOut:=
//Insert User program from here
...
```

Result

You have completed the configuration of the PLC base program. In the next step, you will load the project to the PLC.

References

You can find additional information about the connection of components:
Function Manual, Basic Functions (P3), Section "Structure and functions of the base program"

Machine control panel with handwheel

If you have an Ethernet machine control panel with Ethernet handwheel, you must set the following machine data for the handwheel:

MD11350[0] \$MN_HANDWHEEL_SEGMENT = 7Ethernet

The following are true for a PROFINET machine control panel with handwheel:

MD11350[0] = 5 PROFIBUS/PROFINET

4.4 Download the project to the PLC

Introduction

For loading the configured PLC project, the following prerequisites must be fulfilled:

Precondition

- An Ethernet network connection exists between STEP7 and the PLC.
- The configuration to be loaded corresponds to the actual station configuration.
- The NCU is active:
 - NCK is in cyclic mode.
 - PLC in RUN or STOP mode.

Supplementary condition

The following supplementary conditions regarding the system data blocks must be observed when the configuration is loaded:

- HW Config

When loading the configuration via HW Config, only the system modules and their associated system data blocks selected in HW Config are loaded into the module. However, global data defined in SDB 210 is not loaded from the HW Config, for example.

You have loaded the HW Config to the module in the previous "End the hardware configuration and load to the PLC" chapter.

- SIMATIC Manager

When loading the configuration via the SIMATIC Manager all the system data blocks are loaded into the module.

Note

When the PLC program is loaded in the "RUN" mode, each block loaded becomes active immediately. This can result in inconsistencies when executing the active PLC program. It is therefore advised to place the PLC in the "STOP" mode before loading the configuration, if this has not already been done.

Operating sequence for loading system blocks into the module

1. To load the configuration of the system blocks change to the SIMATIC Manager.
2. In the SIMATIC Manager in the PLC directory, select the directory "Blocks" > right mouse button > "Target system" > "Load" (see figure below), or the "Load" symbol.

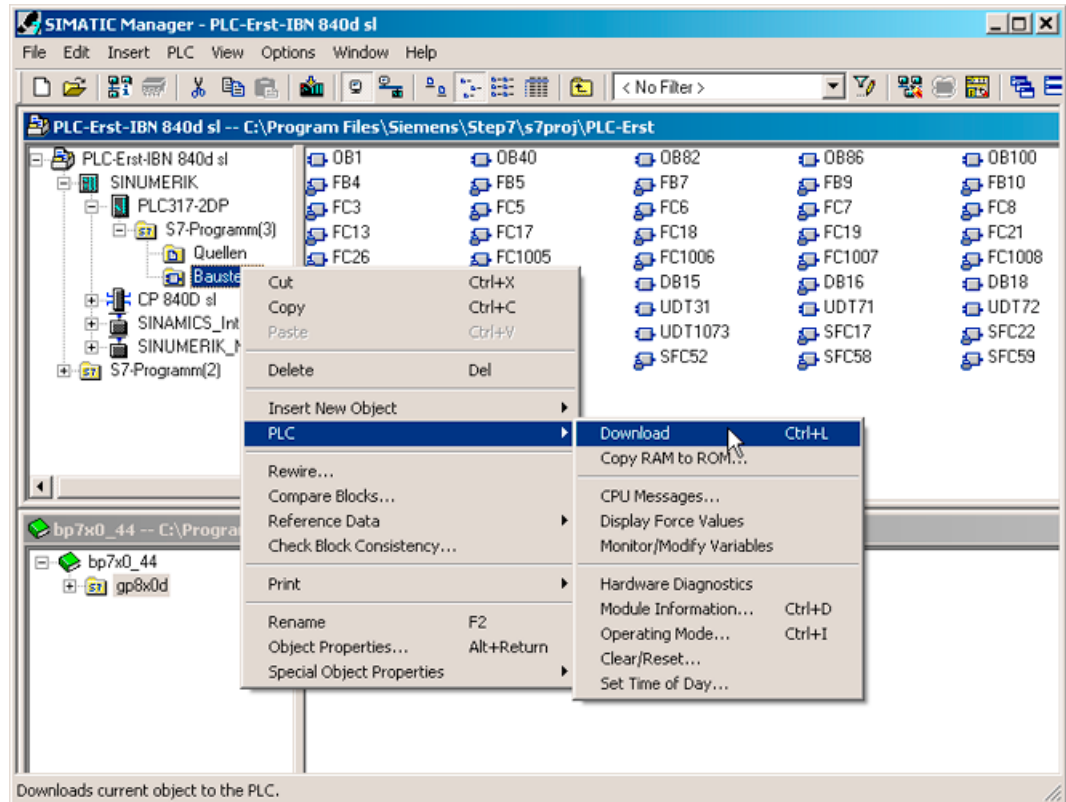


Figure 4-2 Loading system blocks

3. If there is no connection to the target system, you must confirm in sequence the following dialog requests with:
 - "OK" for "Check the required sequence of blocks for correct functioning"
 - "Yes" for "Do you want to load system data?"
 - "Yes" for "Must system data be deleted on the module and replaced by off-line system data?"
 - "No" for "The module is in STOP mode. Do you want to start the module (cold restart)?"

You have loaded the PLC program to the PLC; the PLC is in "STOP" mode.

Note

If the PLC is stopped via the SIMATIC Manager, then it also has to be started via the SIMATIC Manager. Starting via the PLC mode selector is also possible.

4.5 Loading PLC symbols to the controller

Preconditions

You require the SIMATIC STEP 7 software and the "PLC Symbols Generator" program that is provided in the toolbox.

For blocks that already have a symbolic name, these symbols cannot be overwritten by other user-defined designations. Only those symbols are transferred from the blocks to the control without preassigned symbols.

Generating PLC symbols

To edit PLC blocks via symbolic names, you can generate the symbols of the STEP 7 project for SINUMERIK Operate and store them on the CompactFlash card on the control.

Procedure:

1. Open the "PLC Symbols Generator" program and navigate to the corresponding PLC project.
2. To start the generation, first select the required language.
3. Save the "PlcSym.snh" and "PlcSym_xx.snt" files. xx is the language code specified when creating the file. The generation is then started.
4. Create the following directory on the CompactFlash card and store the generated files (PlcSym_xx.snt, PlcSym.snh) under the following path: **/oem/sinumerik/plc/symbols**
5. After restarting SINUMERIK Operate, the symbol tables are loaded when booting. Select the "Insert variables" softkey to display the imported symbols in the table of the "NC/PLC variables".

Note

The notation (upper/lower case) of the file name that the program created is mandatory and must not be changed.

Transmission protocol

For the generation and transfer of the symbols, a transfer log is created and stored under the following path: `../log/symbolimport.log`

Example:

```
...  
Error importing PLC symbols: skip vdi on 840d: Symbol number 16956  
...
```

4.6 First commissioning of the PLC completed

Initial commissioning of the PLC completed

Note

A reset (warm restart) of the NCK is required for PLC-NCK synchronization.

See also: Triggering a reset (warm restart) for NCK and drive system (Page 76)

The PLC and NCK are in the following state after a reset (warm restart):

- RUN LED illuminates GREEN continuously.
- Status display shows a "6" with a flashing point.

⇒ PLC and NCK are in cyclic operation.

You have completed the initial commissioning of the PLC.

Continue with the steps for "Guided commissioning" of SINAMICS drives.

You start with Reset (warm restart) for the NCK and drive system.

Note

Response of the PLC in the case of an NCK stop

For a stop of the NCK, the PLC normally continues to run and the type of stop response is the user's responsibility depending on the machine situation. In this special case, the NCK can no longer switch the outputs to zero and the current status is retained because the PLC is still running.

In order to switch off the outputs or to force a PLC stop, for example, the "NC READY" signal is evaluated in the PLC user program.

4.7 Configuring a network (NetPro) for PG/PC

4.7.1 Integrating PG/PC into NetPro

Preconditions

The following preconditions for integrating a PG/PC must be met:

- The NCU is inserted in the S7 project with the HW Config Inserting SINUMERIK NCU to the HW Config (Page 36).
- The properties of the network interfaces are configured Configure the network interfaces (Page 40).
- The PLC communication to the drive is configured.
- The machine control panel is inserted Modifying machine control panel in OB100 (Page 52).
- The configuration is saved and compiled End the hardware configuration and load it to the PLC (Page 47).
- A PLC program has been created.

Operating sequence for integrating the PG/PC in the S7 project

To carry out routing functions, it is necessary to integrate a PG/PC in the SIMATIC Manager under NetPro and to configure the interfaces.

To enable the communication between PG/PC ↔ HMI via Ethernet, the PG/PC should be included in the network configuration.

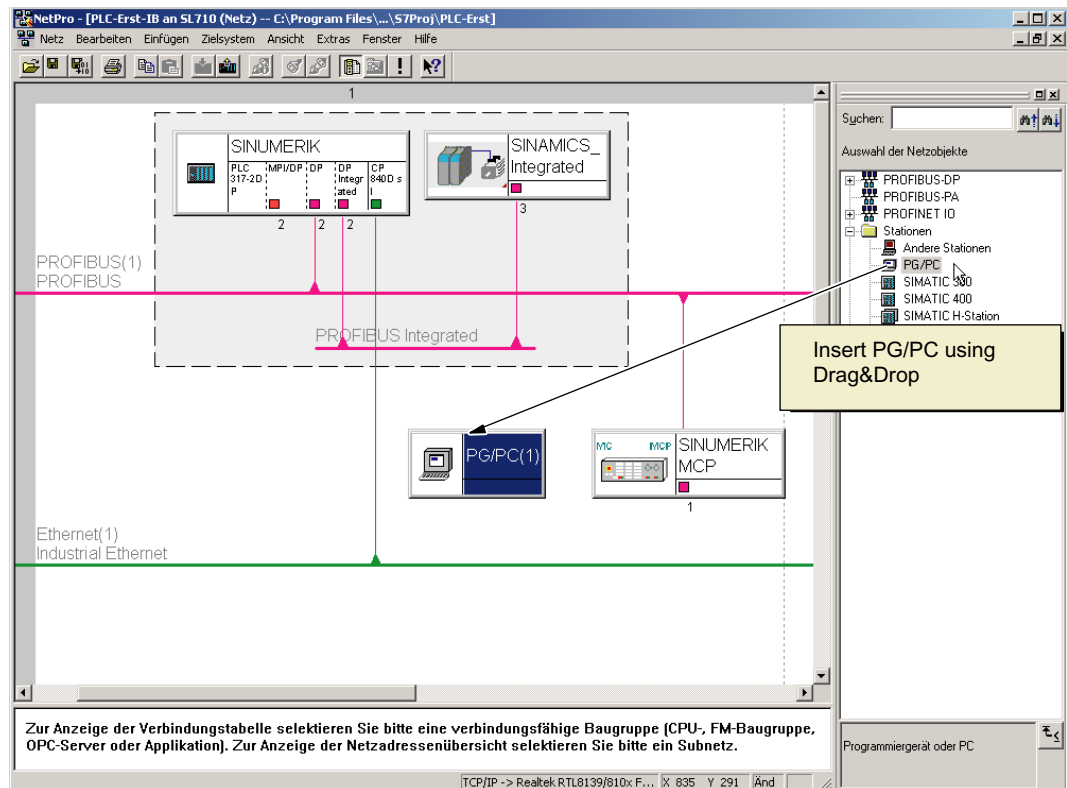
Procedure:

1. To integrate a PG/PC, open the S7 project in the SIMATIC Manager.
2. Select "Extras" → "Configure the network" in the menu or click the following button to start "NetPro":



4.7 Configuring a network (NetPro) for PG/PC

3. Insert the PG/PC with drag&drop under "Stations" from the catalog into the network configuration.



The inserted "PG/PC" station does not yet contain any interfaces. These are configured in the next step.

4.7.2 PG/PC interface configuration

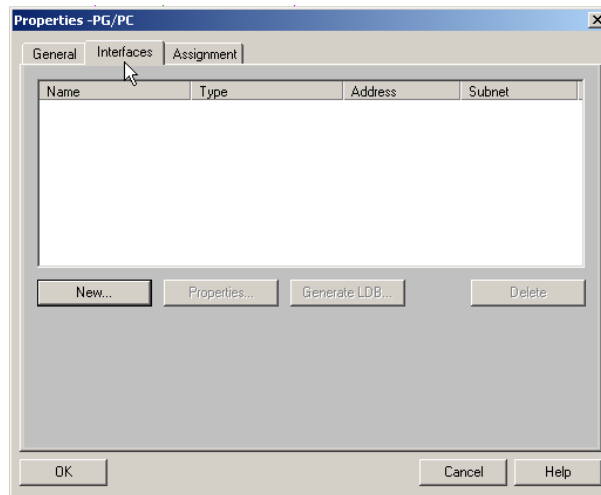
Introduction

Under NetPro, configure the interfaces required for commissioning at the PG/PC. These may include the following interfaces:

- Industrial Ethernet for communication via the service interface X127 on the NCU.
- PROFIBUS

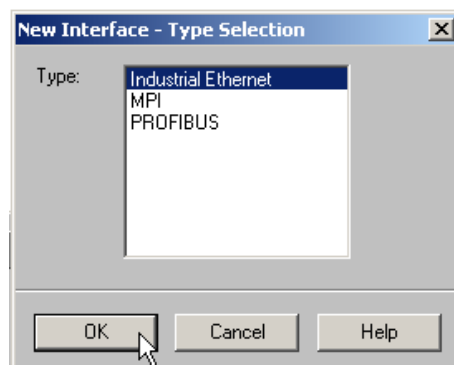
Operating sequence for configuring interfaces

1. Highlight the symbol "PG/PC" under NetPro.
2. Select "Object properties" <right-click>.
3. In the displayed "Properties - PG/PC" dialog, select the "Interfaces" tab to configure the required interfaces.



Operating sequence for configuring interfaces at the PG/PC

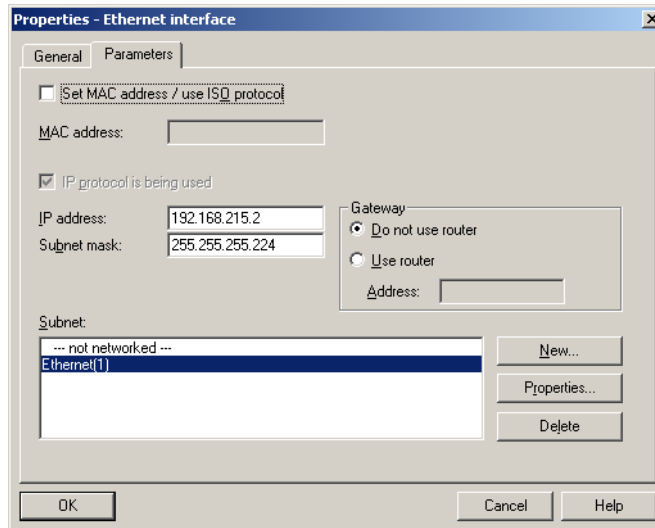
1. Click "New..." to configure the Ethernet interface first.
2. In the selection field, select "Industrial Ethernet".



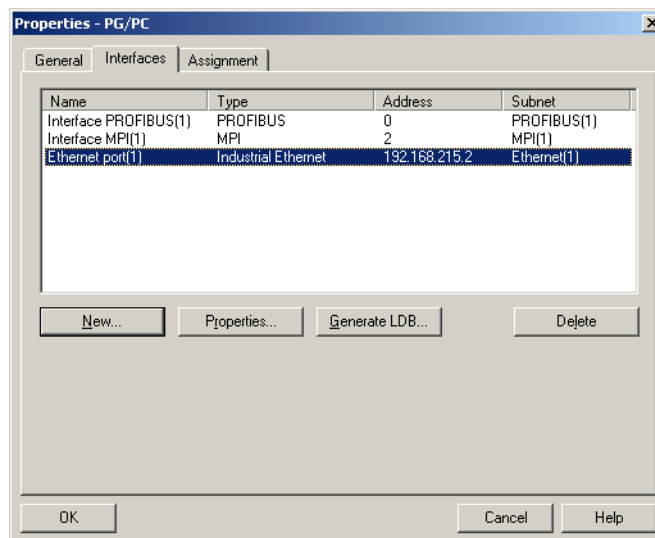
3. Click "OK".

4.7 Configuring a network (NetPro) for PG/PC

4. Select the subnet "Ethernet(1)" and enter the following IP address and subnet mask for the PG/PC:
 - IP address 192.168.215.2
 - Subnet mask 255.255.255.224



5. Deactivate the option "Set MAC address/Use ISO protocol" and confirm with "OK".
6. You can configure additional interfaces via "New".
7. If you have configured the interfaces, all the configured interfaces are visible under the "Interface" tab:



The configured interfaces must be assigned in a device-specific manner to the available hardware interfaces on the PG/PC. The sequence steps are laid out in the following section.

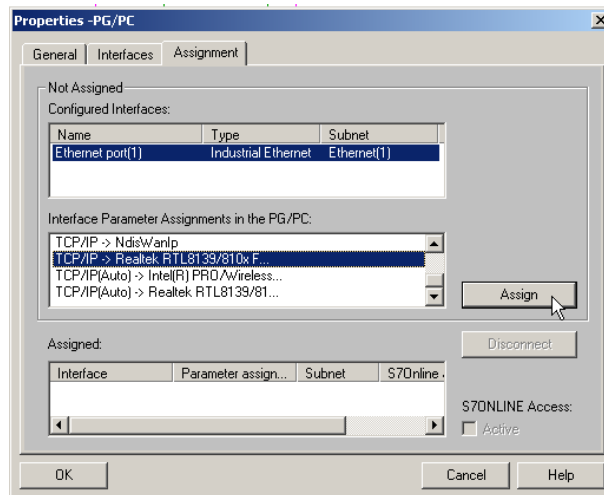
4.7.3 Assigning interfaces

Introduction

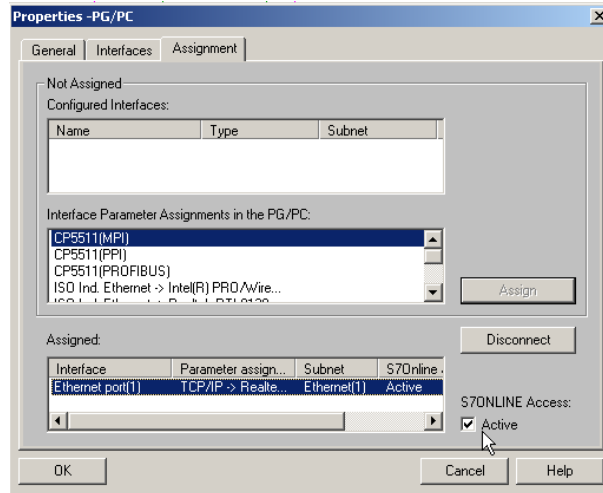
The interfaces configured in the previous chapter must now be assigned in a device-specific manner to the available hardware interfaces on the PG/PC.

Operating sequence for assigning an Ethernet interface

1. Select the "Assign" tab.
2. Select "Ethernet interface(1)" in the selection field "Configured interfaces".
3. Select in the "Interface parameter assignments in the PG/PC" selection field, the "TCP/IP -> Realtek RTL8139/810xF..." network card installed on the PG/PC.



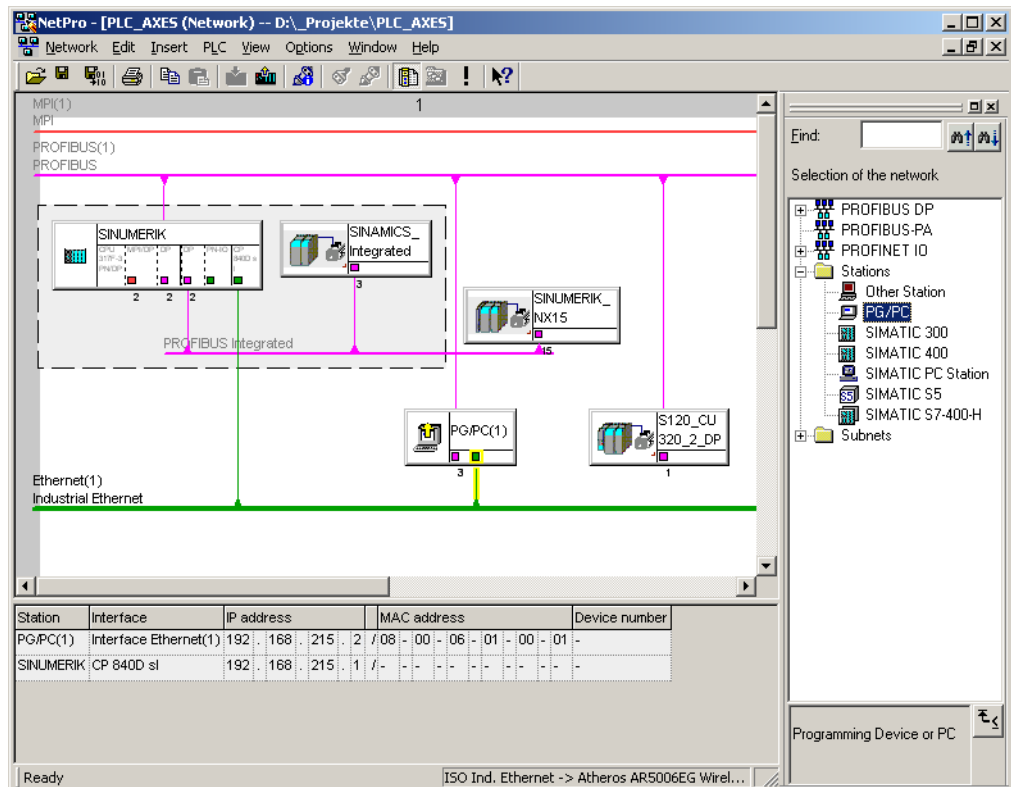
4. Click "Assign" and confirm the subsequent message on processing object properties with "OK". The assigned interfaces are deleted from the "Configured interfaces" field and these assigned interfaces are displayed in the "Assigned" field.



5. Now assign the remaining configured interfaces (PROFIBUS).
From those interfaces assigned, one must be marked as "active".
6. Select "Ethernet interface" in the "Assigned" field and mark the field next to it as "active".

7. Click "OK" to end the dialog "Properties - PG/PC".

In NetPro, the PG/PC interface declared as "active" has a yellow background.



8. Select "Save and compile → Save and check all" and confirm the process with "OK".

The next described operating sequence explains how to load this hardware configuration to the NCU.

4.7.4 Loading the HW config to NCU

Introduction

The newly created network configuration PG/PC must be introduced to the NCU.

You have established a connection to the Ethernet interface (X120 or X127) and you now load this configuration from the PG/PC to the NCU.

Operating sequence for loading HW config to the NCU

1. Change from "NetPro" to "HW Config".
2. Click the "Download to module" button.
The target module interactive screen form automatically displays both configured communication peers.
3. Confirm the load into the module with "OK".
4. Confirm the dialog boxes displayed subsequently with "OK" or "No" for the query "...Should the module be started now (restart)?".

Note

Loading the HW config to the NCU is only possible via the Ethernet interface.

Commissioning NC-controlled drives

Overview

You have the following options when commissioning NC-controlled SINAMICS drives:

- Guided commissioning

For "Guided commissioning", you are guided through the configuration / parameterization of the units, infeed(s) and drives (SERVO).

Note

We recommend that "Guided commissioning" is used when commissioning a drive system for the first time.

- Manual commissioning

For "Manual commissioning", you can select the steps of "Guided commissioning" in any sequence. You perform additional optional functions that are not part of "Guided commissioning" (e.g. PROFIBUS connection).

Note

"Manually commissioning" is recommended for experienced commissioning engineers.

The closed-loop drive control for SINAMICS S120 is integrated in the NCU. The drives connected to the internal virtual PROFIBUS can only be assigned to NC axes.

The assignment is realized using the axis machine data:

- MD30110 \$MA_CTRLOUT_MODULE_NR (setpoint channel)
- MD30220 \$MA_ENC_MODUL_NR (actual value channel)
- MD30130 \$MA_CTRLOUT_TYPE (type of output setpoint)
- MD30240 \$MA_ENC_TYPE (acquisition of actual value)
- MD13050 \$MN_DRIVE_LOGIC_ADDRESS (axis address)

The logical I/O addresses ≥ 4100 are determined in this machine data.

The NC axis assignment is also made using the above-mentioned machine data with the modified logical I/O address ≤ 4095 .

Note

A drive that can be assigned to an NC axis must be a standard slave according to the PROFIdrive profile version 4.1.

5.1 Configuration examples

5.1.1 Example: Configuration of the drive components

Configuration overview

The commissioning described in this manual is orientated on the following example configuration of the SINAMICS drive line-up.

- NCU 720.3 PN with:
 - A Single Motor Module for a motor with SMI (Sensor Module Integrated)
 - A Double Motor Module for two motors each with an SMC20 (Sensor Module Cabinet).
- NX 15.3 with:
 - A Single Motor Module for a motor with two SMC20 units for the encoders.
- Infeed (Active Line Module)

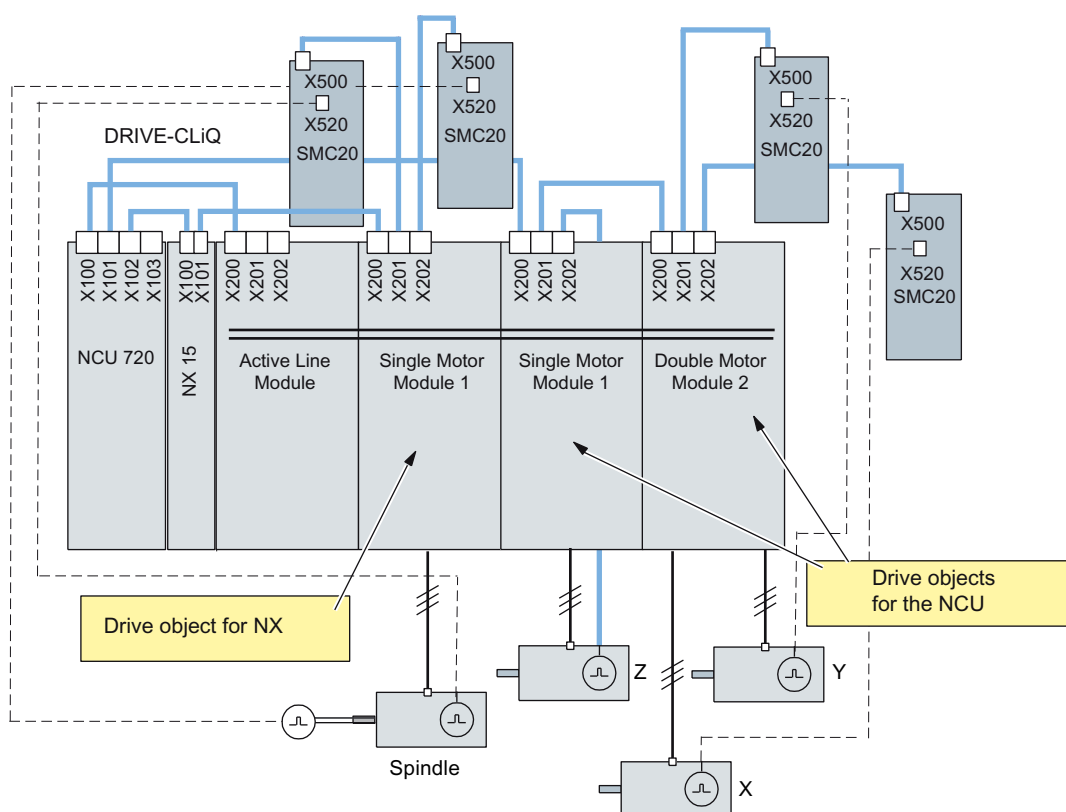


Figure 5-1 SINAMICS S120 example configuration

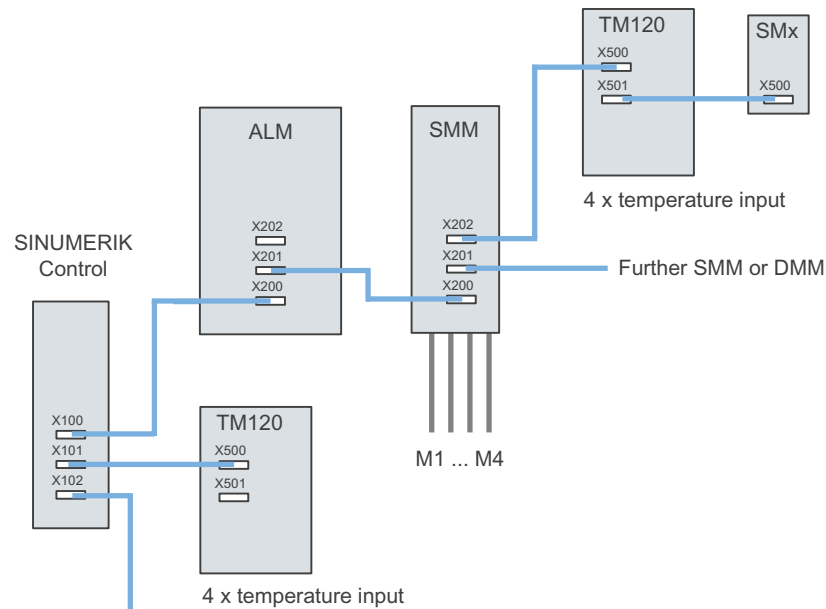
Literature

Additional DRIVE-CLiQ components of the SINAMICS drive line-up can be found in: SINAMICS S120 Equipment Manual for "Control Units and Additional System Components" /GH1/

5.1.2 Example: Parallel connection with TM120

Application: Four motors connected in parallel

Sample topology:



M1 ... M4	Motor 1 ... motor 4
	One KTY and three PTC in series are connected for each motor.
SMx	Sensor Module (motor encoder)
ALM	Active Line Module
DMM	Double Motor Module
SMM	Single Motor Module
TM120	Terminal Module

The shown topology requires four KTY sensors and four PTC sensors:

- Each primary section has one KTY sensor (Temp-F) and three series-connected PTC sensors (Temp-S).

Two TM120s are required:

- A TM120 is interconnected automatically in series between the Motor Module and the SMx sensor module.
- A TM120 is directly inserted into a Line Module: This requires a manual interconnection by the commissioning engineer.

Measures for the TM120:

1. **TM120 between the Motor Module and the SMx Sensor Module**

This TM120 evaluates four KTYs => sensor types must be selected by Servo-p4610/TM-p4100. The associated temperature is output by servo-r4620/TM120-r4105.

2. **TM120 directly on the Line Module**

This TM120 evaluates four PTCs => sensor types must be selected by TM-p4100. The associated temperature is output by servo-r4105.

Setting the threshold values in the PTC context:

- TM120-p4102[x]=251 => evaluation Off
- TM120-p4102[x]=120 => evaluation On

Assignment of the TM120 response using fault propagation on the drive => setting of the propagation by servo-p0609=BICO:<object number>TM120:4105.0

Assignment of the alarms to the motor

The occurring error messages are assigned to the motors as follows:

- Temperature channel on the TM120 in series connection with motor modules and encoders:

Alarm 207015 <location>drive: Motor temperature sensor warning

Alarm 207016 <location>drive: Motor temperature sensor fault

Alarm 235920 <location>TM: Temperature sensor channel 0 error

In this case, the output message with reference to the motor and to the temperature component shows the relevant motor.

- Temperature channel on the TM120 directly to the line module:

Alarm 235207 <location>TM: Temperature fault/alarm threshold channel 0 exceeded

Special feature with PTC:

TM120-r4105 = -50 temperature is below the nominal response temperature

TM120-r4105 = 250 temperature is above the nominal response temperature

In this case, a message is output only with reference to the temperature component.

The affected motor can be determined from the information concerning the TM120.

5.2 Terminal assignment

5.2.1 NCU 7x0.3 PN terminal assignment

The SINAMICS device configuration (Page 78) occupies the following terminals on an NCU 7x0.3 PN:

- X122
- X132
- X142

The following table lists the terminal assignments for the X122, X132 and X142 terminal blocks of the NCU.

5.2.2 X122 terminal assignment

Terminal	Signal name	Function	Pre-assignment
X122.1	DI 0	Input ON/OFF1 infeed (if one infeed with a DRIVE-CLiQ connection is operated at the NCU)	x
X122.2	DI 1	Input 2nd operating condition OFF3 drives "OFF3 rapid stop" Braking with a configurable OFF3 ramp (p1135, p1136, p1137); thereafter, pulse suppression and switching on inhibited. The drive stops controlled. The braking response can be set separately for each SERVO.	x
X122.3	DI 2	Selection safe standstill group 1 SH/SBC - Group 1 SINAMICS Safety Integrated (SH = p9601 release)	---
X122.4	DI 3	Selection safe standstill group 2 SH/SBC - Group 2 SINAMICS Safety Integrated (SH = p9601 release)	---
X122.5	DI16	Freely available	---
X122.6	DI17	Freely available	---
X122.7	Ground for terminals 1...6		
X122.8	Ground for terminals 9, 10, 12, 13		
X122.9	DI/DO 8	Status safe standstill group 1 SH/SBC - Group 1 SINAMICS Safety Integrated	---
X122.10	DI/DO 9	Status safe standstill group 2 SH/SBC - Group 2 SINAMICS Safety Integrated	---
X122.11	Ground for terminals 9, 10, 12, 13		---

5.2 Terminal assignment

Terminal	Signal name	Function	Pre-assignment
X122.12	DI/DO 10	Input, external zero mark Bero 1 – "equivalent zero mark"	---
X122.13	DI/DO 11	Input probe 1 - central measurement (Check that MD13210 = 0)	x
		Input probe 1 - distributed measurement (Check that MD13210 = 1)	---
X122.14	Ground for terminals 9, 10, 12, 13		

In the "pre-assignment" column, the signals for which the associated SINAMICS parameters are set when configuring a SINAMICS device are marked with "x".

5.2.3 X132 terminal assignment

Terminal	Signal name	Function	Pre-assignment
X132.1	DI 4	Freely available	---
X132.2	DI 5	Freely available	---
X132.3	DI 6	Freely available	---
X132.4	DI 7	Infeed line contactor feedback signal (if one infeed is operated with a DRIVE-CLiQ connection at the NCU)	---
X132.5	DI20	Freely available	---
X132.6	DI21	Freely available	---
X132.7	Ground for terminals 1...6		
X132.8	Ground for terminals 9, 10, 12, 13		
X132.9	DI/DO 12	Output: Infeed operation (if one infeed is operated with a DRIVE-CLiQ connection at the NCU)	x
		Input 2nd operating condition OFF2 drives	---
X132.10	DI/DO 13	Output: Status, infeed ready to start (if one infeed is operated at the NCU with a DRIVE-CLiQ connection)	x
		Input 2nd operating condition OFF2 drives	---
		Input, external zero mark 2	---
		Input probe 2 - central measurement	---
		Input probe 2 - distributed measurement	---
X132.11	Ground for terminals 9, 10, 12, 13		
X132.12	DI/DO 14	Input 2nd operating condition OFF2 drives	---
		Input, external zero mark 3	---
		Input probe 2 - central measurement	---
		Input probe 2 - distributed measurement	---
		Infeed, control line contactor	---
X132.13	DI/DO 15	Input 2nd operating condition OFF2 drives	---
		Input, external zero mark 4	---

Terminal	Signal name	Function	Pre-assignment
		Input probe 2 - central measurement	---
		Input probe 2 - distributed measurement	---
X132.14	Ground for terminals 9, 10, 12, 13		

In the "pre-assigned" column, the signals for which the associated SINAMICS parameters are set when configuring a SINAMICS device are marked with "x".

5.2.4 X142 terminal assignment

Terminal	Signal name	Function		Pre-assignment
X142.1	---	reserved		---
X142.2	---	reserved		---
X142.3	DI0	NC input	\$A_IN[1]	fixed
X142.4	DI1	NC input	\$A_IN[2]	fixed
X142.5	Ground for terminals X142.3, 4, 6, 7, 9, 10, 12, 13			---
X142.6	DI2	NC input	\$A_IN[3]	fixed
X142.7	DI3	NC input	\$A_IN[4]	fixed
X142.8	Power supply			---
X142.9	DO4	NC output	\$A_OUT[1]	fixed
X142.10	DO5	NC output	\$A_OUT[2]	fixed
X142.11	Ground for terminals X142.3, 4, 6, 7, 9, 10, 12, 13			---
X142.12	DO6	NC output	\$A_OUT[3]	fixed
X142.13	DO7	NC output	\$A_OUT[4]	fixed
X142.14	Ground for terminals X142.3, 4, 6, 7, 9, 10, 12, 13			---

5.2.5 NX 1x.3 terminal assignment

The table lists the assignments of the terminals on an NX 1x.3 for the X122 terminal strip.

The SINAMICS device configuration sets the following preassignment:

Number	Function	Signal	Pre-assignment
X122.1	DI 0	Input ON/OFF1 infeed (if one infeed with a DRIVE-CLiQ connection is operated at the NX)	x
		Input infeed operation - "infeed ready signal" (if no infeed with DRIVE-CLiQ connection is operated at the NX)	x
X122.2	DI 1	Input 2nd operating condition OFF3 drives	x
		Freely available	--

5.2 Terminal assignment

Number	Function	Signal	Pre-assignment
X122.3	DI 2	Selection safe standstill group 1 SH/SBC - Group 1 SINAMICS Safety Integrated (SH = p9601 release)	--
X122.4	DI 3	Selection safe standstill group 2 SH/SBC - Group 2 SINAMICS Safety Integrated (SH = p9601 release)	--
X122.5	DI 16	Freely available	--
X122.6	DI 17	Freely available	--
X122.7	Reference potential for terminals 1...6		
X122.8	Mass		
X122.9	DI/DO 8	Status safe standstill group 1 SH/SBC - Group 1 SINAMICS Safety Integrated	-
X122.10	DI/DO 9	Status safe standstill group 2 SH/SBC - Group 2 SINAMICS Safety Integrated	--
X122.11	Mass		
X122.12	DI/DO 10	Input, external zero mark BERO 1 – "equivalent zero mark"	--
X122.13	DI/DO 11	Input, external zero mark 2/1	--
		Input 2nd operating condition OFF2 drives	--
X122.14	Mass		

Those signals for which the associated SINAMICS parameters are set for the SINAMICS device configuration are marked with "x" in the "Pre-assigned" column.

See also

Automatic device configuration (Page 78)

5.2.6 Support for the terminal assignment

Support for terminal assignment

The following overview shows the terminal assignment of those drive units (NCU, NX) involved on the SINAMICS drive line-up, in the commissioning tool V7.7.

"Commissioning" > "Drive system" > "Drive units" > "Inputs/outputs" menu:

Start-up	RACK1003	JOG Ref	MPF0				
Channel interrupt			Program aborted				
Stop: No NC Ready			ROV				
8080 4 option(s) is/are activated without setting the license key							
Eingänge / Ausgänge				DP3.Slave3.CU_003[1]			
Signal	In/Out	0/1	Terminal	Terminal	0/1	In/Out	Signal
Input IN/OUT1 Infeed	In	0	X122.1	X132.1	0	In	Input \$A_IN[1]
Input 2. OUT3 Drives	In	0	X122.2	X132.2	0	In	Input \$A_IN[2]
?-Select Safe Stop (SH) Group 1	In	0	X122.3	X132.3	0	In	Input \$A_IN[3]
?-Select Safe Stop (SH) Group 2	In	0	X122.4	X132.4	0	In	Input \$A_IN[4]
?-Status of Safe Stop Group 1	In	0	X122.7	X132.7	0	Out	Status Infeed ready to operate
?-Status of Safe Stop Group 2	In	0	X122.8	X132.8	0	Out	Status Infeed supply ready
?-Input external zero mark	In	0	X122.10	X132.10	0	Out	?-Output \$A_OUT[2]
Input Probe 1 (central)	In	0	X122.11	X132.11	0	Out	Output \$A_OUT[1]
Signal Row X122.1 (DI 0)				ALM_3.3.2			
1 total targets							
Press 'Set Defaults' to use standard terminal wiring.							
Configuration	Topology	PROFIBUS link	Connections	Inputs / Outputs		Control unit MD	File functions

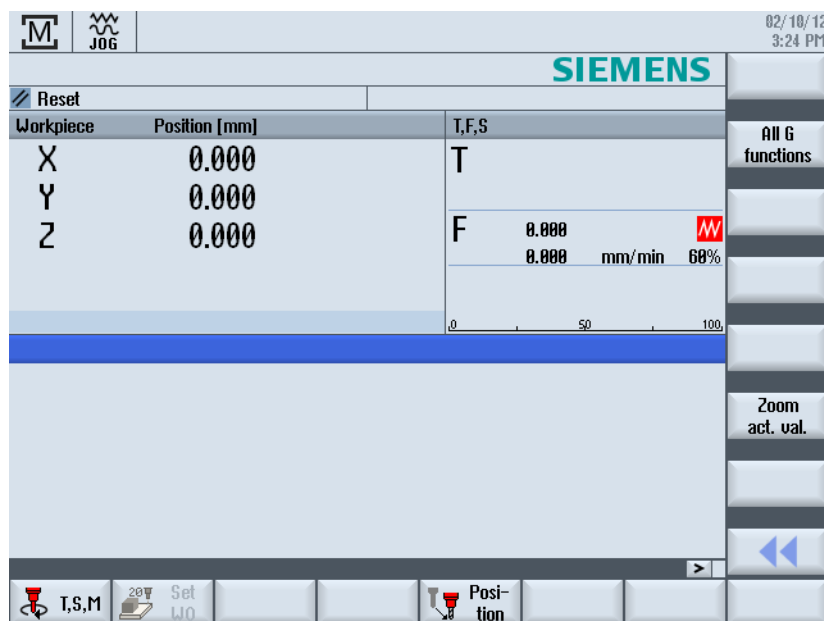
Figure 5-2 Interconnections of the digital inputs/outputs

5.3 Guided commissioning of SINAMICS drives

5.3.1 Triggering a reset (warm restart) for NCK and drive system

Introduction

After booting the system you will find yourself in the "Machine" operating area:



In the previous step before loading the project to the PLC (Page 55), this was brought into the STOP state. The NCK interprets this STOP state, with a corresponding alarm response, as failure of the PLC.

Alarm response

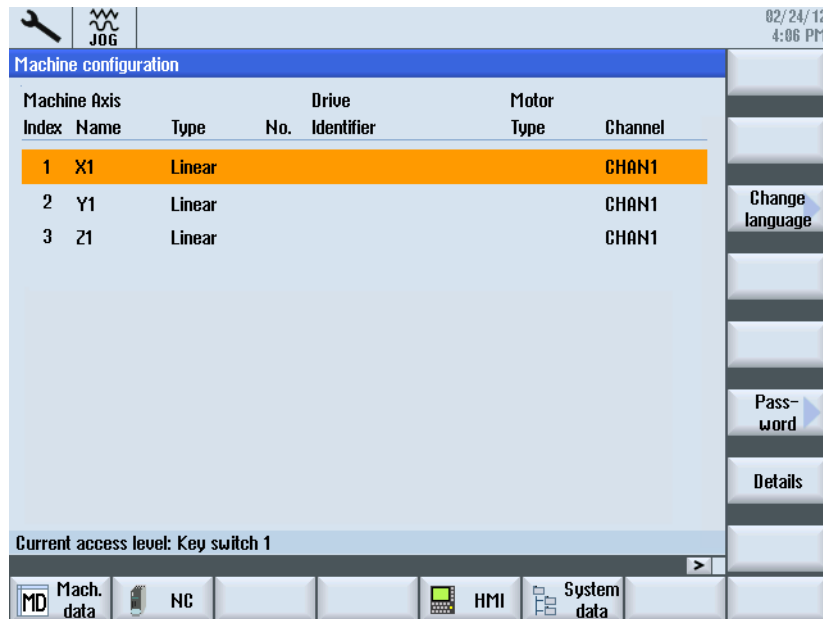
A "Reset (po)" (warm restart) is required for the PLC-NCK synchronization. This can cause alarm responses. The output of all alarms in form list can be found in the "Diagnostics" → "Alarms" operating area. Additional support for the diagnosis of the drive system is described in Section Drive system diagnostics (Page 123).

Operating sequence for initiating an NCK reset

1. Press the <MENU SELECT> key and select the "Commissioning" operating area.

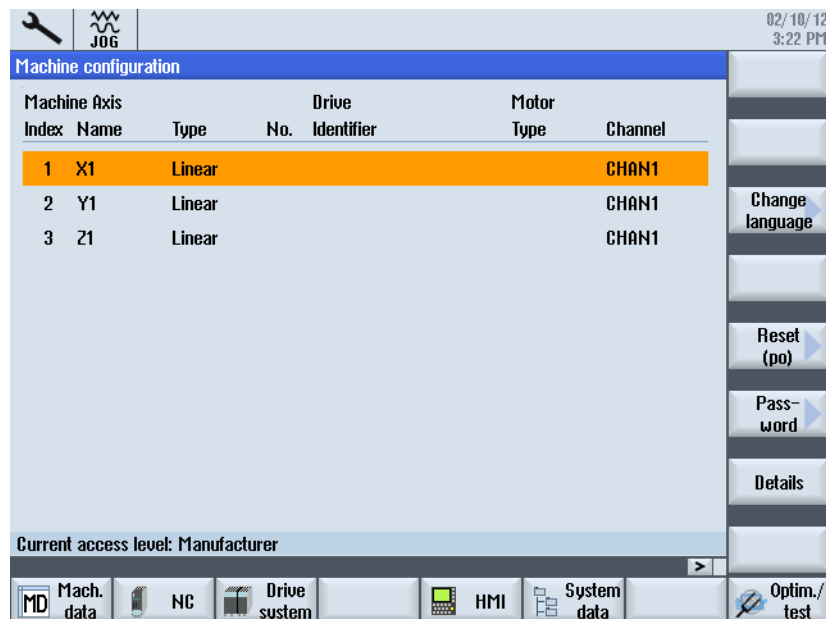


The commissioning operating area is displayed without password:



2. Press "Password...".
3. Press "Set password".
4. Enter the password for the "Manufacturer" access level.

5. Confirm with "OK".



6. Press the "Reset (po)" softkey.
7. Acknowledge the "Do you want to trigger a reset (warm restart) for the NCK and the entire drive system (all drive units)?" prompt with the "Yes" softkey.

The PLC goes to RUN mode. Guided commissioning of the SINAMICS drives is then started. Continue with the steps described in the following chapter.

5.3.2 Automatic device configuration

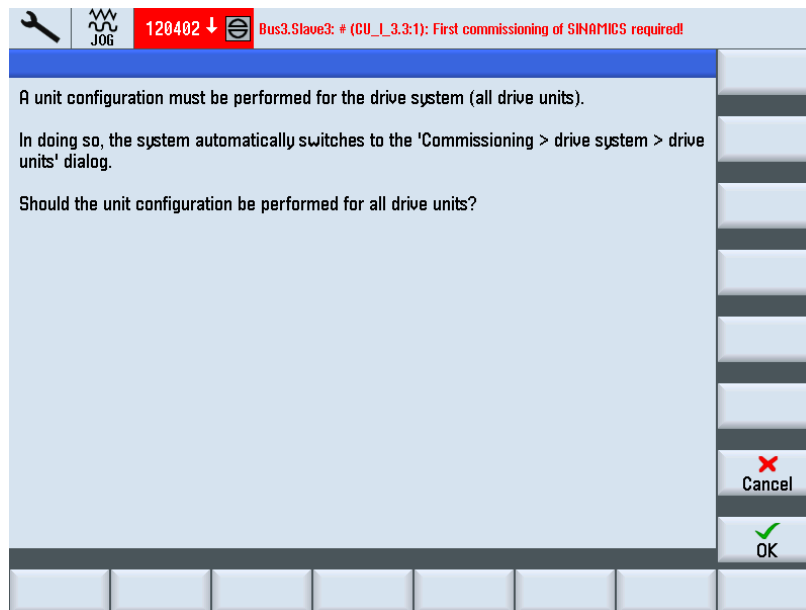
Automatic device configuration

Procedure:

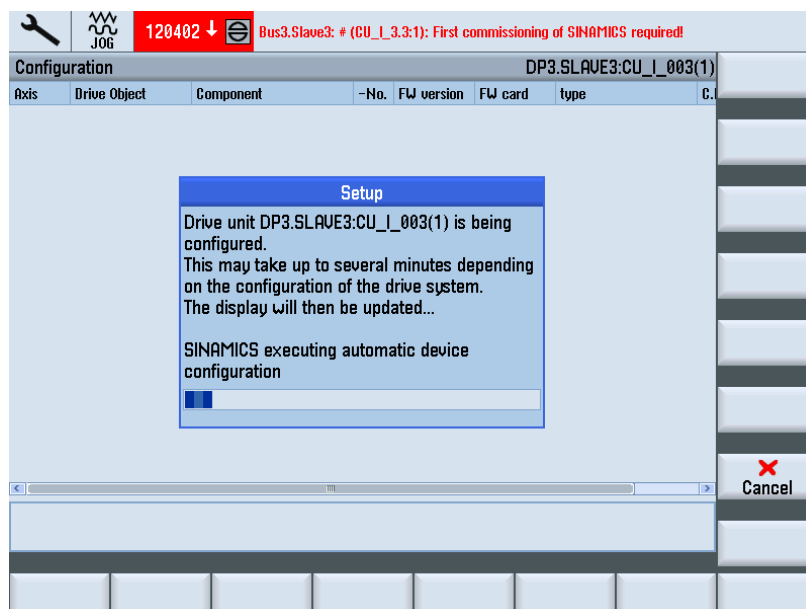
You have set the password for manufacturer and initiated a reset (warm restart). The following alarm is initiated:

"120402 ... SINAMICS initial commissioning required! "

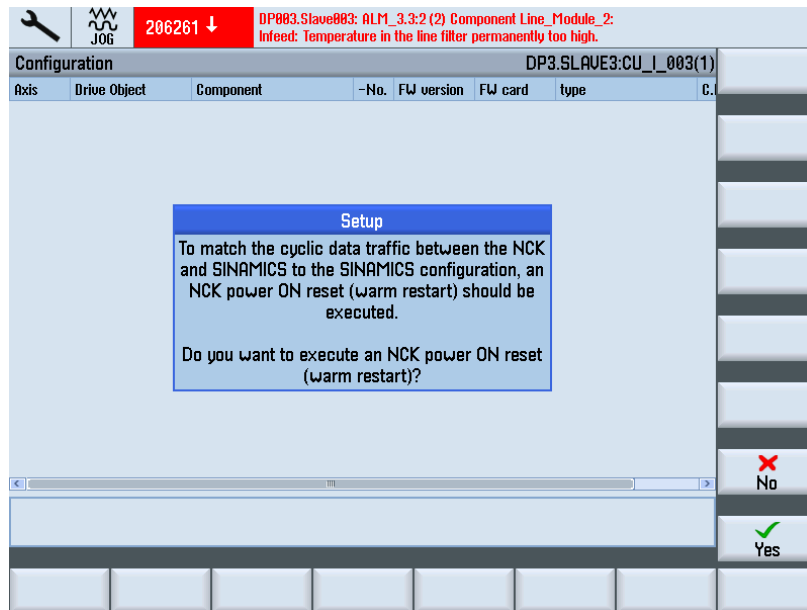
1. Once the complete drive system has powered-up, the following dialog for the automatic device configuration is displayed:



2. Press "OK".
If you press "Cancel", then you can manually perform the commissioning (see Chapter Manual commissioning of SINAMICS drives (Page 101)).
3. The individual steps for automatic device configuration are displayed one after the other in the following dialog box:



4. The following dialog box is displayed after the device has been configured:

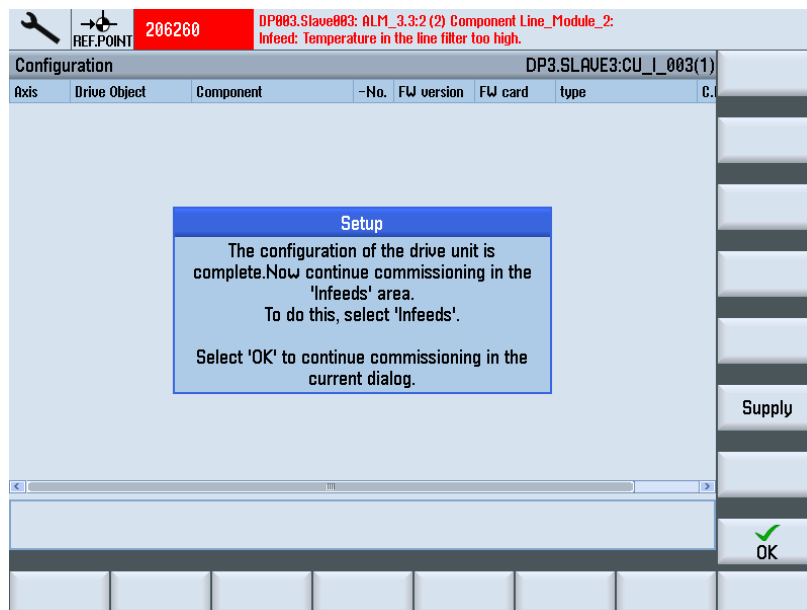


5. Press "Yes".

The following notes are displayed during the NCK power on reset:

- "Wait for communication with the NC"
- "Wait for communication to the drive"
- "Wait until communication is restored"

After the automatic device configuration, an automatic check is made which infeeds and drives (SERVO) still need to be parameterized/commissioned. Commissioning guides you using the following dialog box to the individual drive objects that have still not been commissioned.



6. Press the "Infeeds" softkey to continue with the parameterization of the infeed in the following section.

5.3.3 Parameterization of infeed

Operating sequence

The system detects that the infeed has not been commissioned and that a commissioning is required:

1. Select the "Commissioning" > "Drive system" > "Infeeds" menu.

DP083.Slave083: ALM_3.3:2 (2) Component Line_Module_2:
Infeed: Temperature in the line filter permanently too high.

.../Infeeds/Overview DP3.SLAVE3:ALM_3.3:2 (2)

Drive object name: ALM_3.3:2 (2)

Drive object type: ACTIVE INFEED CONTROL

PROFIBUS telegram: Free telegram configuration with BICO

Infeed has not been brought into operation.
Infeed commissioning can be performed with 'Change'

ALM_3.3:2.Line_Module_2 (Supply)

Supply type: LM_ACDC

Order number: 6SL3130-7TE21-6AA3

Code number: 10015

Serial number: T-W12091061

Component number: 2

Rated output: 16.00 kW

DC link voltage setpoint: 600.00 U

Switch the Line Module LED to make it flash for recognition: ☐

Configuration Infeed parameter

2. The commissioning is performed with the "Change" vertical softkey.

The wizard guides you step-by-step through the commissioning when you press the "Next step" softkey.

DP083.Slave083: ALM_3.3:2 (2) Component Line_Module_2:
Infeed: Temperature in the line filter permanently too high.

.../Infeeds/Configuration DP3.SLAVE3:ALM_3.3:2 (2)

Recognized Line Module:

Type (order no.)	Rated output	Rated current	Code number
6SL3130-7TE21-6AA3	16.00 kW	27.00 A	10015

☐ Switch the Line Module LED to make it flash for recognition

Line filter: Wideband Line Filter Booksize 400 U 16 kW (6SL3000-0BE21-6AA0)

☐ Voltage Sensing Module available

☐ External braking module

Configuration Infeed parameter

Cancel Next step

3. Select the net filter: In this example, a Broadband Line Filter (16 kW) is available.

... \Infeeds \Configuration-Power data DP3.SLAVE3:ALM_3.3:2 (2)

☒ Line/DC link identification on first Power ON

(The determined values are saved powerfail-proof)

Notice:
If the DC link capacity of the drive group is subsequently modified (devices removed/added), a new identification will have to be performed.

Device supply voltage: 400 U

Line rated frequency: 50-60 Hz

Note:
With a device supply voltage of over 415V, the Active Line Module is operated as open-loop control supply/feedback.

Previous step

Cancel

Next step

Configur- ation Infeed parameter

4. Accept the default setting (see also: Check the power system data of the infeed (Page 147)).

... \Infeeds \Configuration-Terminal wiring DP3.SLAVE3:ALM_3.3:2 (2)

☒ Configuration conforms to SINUMERIK

☐ Use standard terminal wiring

☒ SINAMICS-internal line contactor control

Output terminal supply control line contactor: X132.12

Input terminal supply checkback line contactor: X132.4

Previous step

Cancel

Next step

Configur- ation Infeed parameter

5. Select the terminal wiring.

DP883.Slave883: ALM_3.3:2 (2) Component Line_Module_2:
Infeed: Temperature in the line filter permanently too high.

... \Infeeds\Configuration-Summary DP3.SLAVE3:ALM_3.3:2 (2)

The following supply data have been entered:

Supply:

- Drive object name: ALM_3.3:2
- Line Module name: Line_Module_2
- PROFIBUS telegram: Free telegram configuration with BICO
- Component number: 2
- Drive object type: LM_ACDC
- Order number: 6SL3130-7TE21-6AA3
- Rated output: 16.00 kW
- DC link voltage setpoint: 600.00 U
- Code number: 10015
- Serial number: T-W12091061
- Line filter: Wideband Line Filter Booksize 400 U 16 kW (6SL3000-0BE21-6AA0)

Line rated data:

- Line/DC link identification on first Power ON
- Device supply voltage: 400.00 U
- Line rated frequency: 50-60 Hz

Terminal wiring:

BICO connections for standard terminal wiring

☒ Save text in file /user/sinumerik/hmi/log/config/ALM_3.3.2.txt:

Previous step

Cancel

Finished

Check the configuration in the summary. You have now completed configuring the infeed. Optionally, you can save the configuration data in a text file.

6. Press the "Finish >" softkey.

DP883.Slave883: ALM_3.3:2 (2) Component Line_Module_2:
Infeed: Temperature in the line filter permanently too high.

... \Infeeds\Configuration-Summary DP3.SLAVE3:ALM_3.3:2 (2)

The following supply data have been entered:

Supply

The configuration of infeed ALM_3.3:2 has been completed.

The data must be stored in a non-volatile manner if the configuration of infeed ALM_3.3:2 is to be retained after a restart.

Would you like to store the data of infeed ALM_3.3:2 in a non-volatile manner?

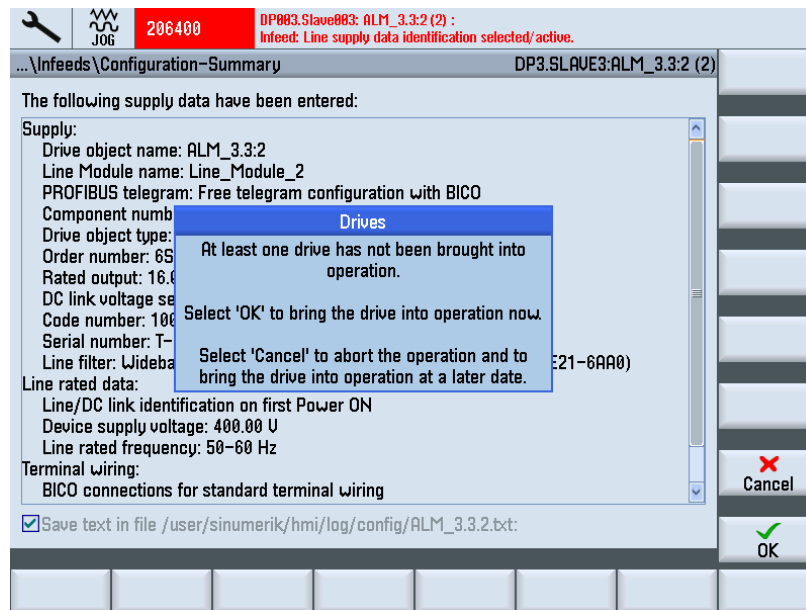
Cancel

No

Yes

7. Press "Yes" to save the data to the non-volatile memory.

8. After commissioning the infeed, an automatic check is made for which drives (SERVO) still need to be commissioned. The following dialog appears:



9. Press the "OK" softkey to continue with the steps to commission the drives (see also: Parameterization of the drives (Page 85)).

The overview screen of the infeed is displayed if "Cancel" was pressed:

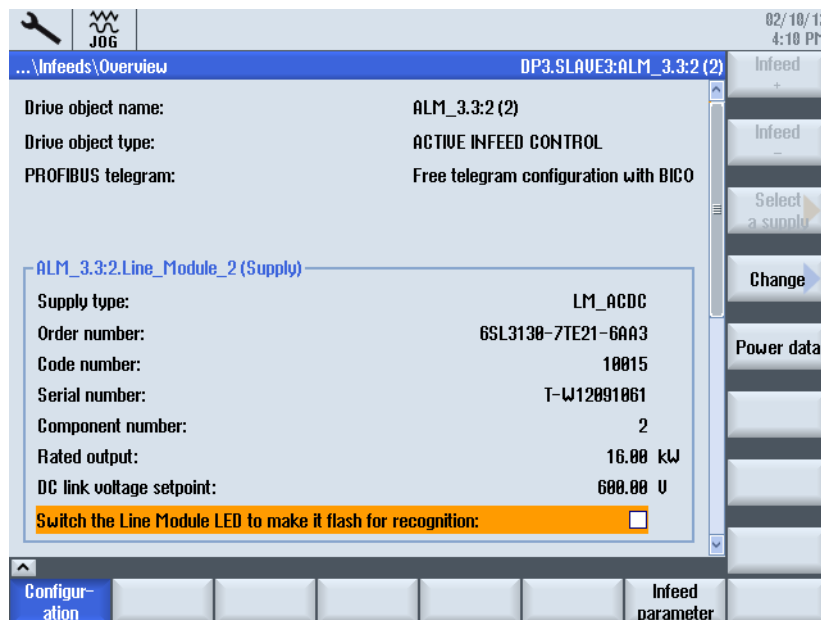


Figure 5-3 Infeeds/overview (page 1)

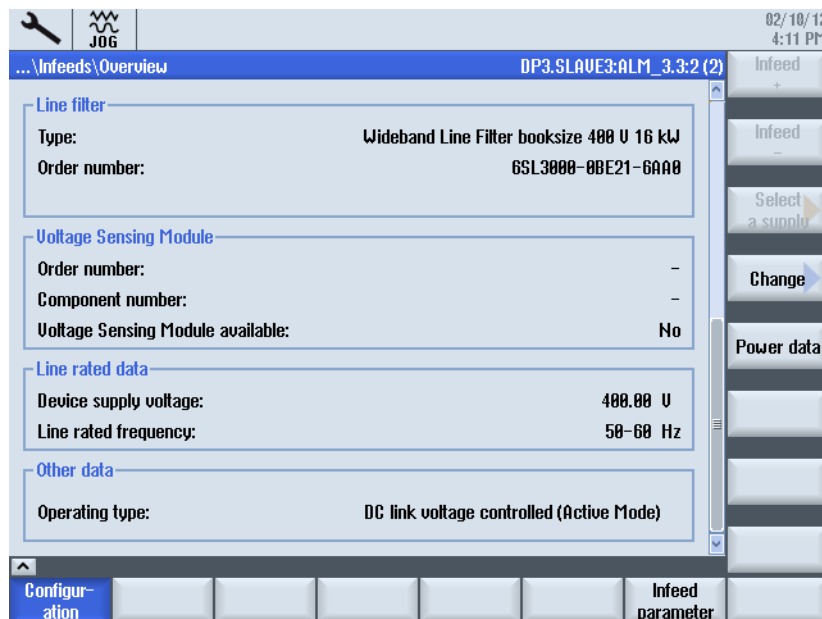


Figure 5-4 Infeeds\overview (page 2)

Note

The "Guided commissioning" ends here. Using " Manual commissioning (Page 101) " you can now perform additional commissioning steps.

5.3.4 Parameterization of the drives

Introduction

The following components are parameterize/configured with the drive wizard:

- Motor
- encoder
- Interface signals

Parameterizing/configuring

Guided commissioning navigates you through the commissioning of SINAMICS drives with motors without SMI (Sensor Module Integrated).

For motors without SMI, when parameterizing/configuring, a distinction is made between the following motor types:

- Catalog motors (standard motors, listed with associated motor data) (Page 86)
- Third-party motors (Page 93)

Note

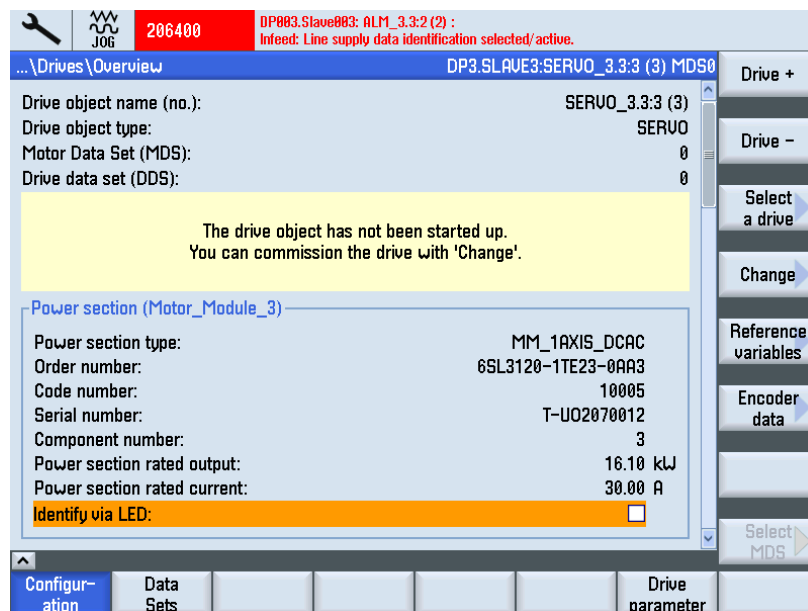
Motors with SMI (DRIVE-CLiQ) are automatically configured by the drive unit during the device configuration with a drive data set (DDS), but only with the motor measuring system; i.e. motors with SMI only have to be configured with the drive wizard when more than one drive/motor data set (DDS/MDS) or a second (direct) measuring system is required.

5.3.4.1 Commissioning of listed motor and encoder via SMC

Operating sequence

In our example a power section is to be configured with a listed motor and encoder. You are in the "Commissioning" → "Drive system" → "Drives" menu:

1. The system detects that the drive object has not been commissioned and that an initial commissioning is required:



2. Press the "Change" vertical softkey.

Type (order no.)	Rated output	Rated current	Code number
6SL3120-1TE23-0Axx	16.10 kW	30.00 A	10005

☐ Switch the Motor Module LED to make it flash for recognition

Function modules:

- ☐ DSC with spline
- ☐ Advanced Positioning Control (APC)
- ☐ Extended Stopping and Retraction
- ☐ Moment of inertia estimator

Navigation buttons: Configuration, Drive parameter, Cancel, Next step

3. The motor module type is detected and output. Activate the available function modules.

Motor select: ☒ Select a standard motor from the list
☐ Enter motor data ☐ Template from list

Motor type: 1PH7 induction motor

Select motor Find:

Type (order no.)	Connection type	Rated output	Rated current	Rated speed	Rated frequency
<input type="checkbox"/> 1PH7105-xxFxx-xLxx	Star	7.00 kW	17.38 A	1500.00 U/min	51.66 Hz
<input type="checkbox"/> 1PH7103-xxGxx-xLxx	Star	7.00 kW	17.12 A	2000.00 U/min	68.94 Hz
<input type="checkbox"/> 1PH7103-xxFxx-xLxx	Star	5.50 kW	13.00 A	1500.00 U/min	52.70 Hz
<input type="checkbox"/> 1PH7103-xxDxx-xLxx	Star	3.70 kW	9.60 A	1000.00 U/min	35.60 Hz
<input checked="" type="checkbox"/> 1PH7101-xxFxx-xLxx	Star	3.70 kW	9.76 A	1500.00 U/min	51.61 Hz
<input type="checkbox"/> 1PH7186-xxBxx-xxxx	Star	26.50 kW	67.00 A	500.00 U/min	17.30 Hz
<input type="checkbox"/> 1PH7186-xxLxx-xxxx	Star	106.00 kW	235.00 A	2500.00 U/min	84.10 Hz
<input type="checkbox"/> 1PH7186-xxFxx-xxxx	Star	85.00 kW	169.00 A	1750.00 U/min	59.00 Hz
<input type="checkbox"/> 1PH7137-xxBxx-xxxx	Star	9.00 kW	22.30 A	500.00 U/min	18.20 Hz

Navigation buttons: Previous step, Cancel, Next step, Configuration, Drive parameter

4. Select the "Select standard motor from list" option.
5. Select the motor with the "Cursor up / Cursor down" keys.

6. Press "Next step >".

7. You can select brake control in the "Configuration - motor holding brake" dialog. If a connected brake is detected during the unit configuration, the system will automatically activate the brake control and will by default display "Brake control according to procedural control" here.
8. Press "Next step >".

An identification of the selected encoders is triggered (Encoder 1).

The drive unit can identify encoders with EnDat protocol. These encoders are selected in the encoder list in the follow-up dialog boxes ("Configuration - Encoder 1" menu).

Encoder: Encoder_15
Sensor Module: SMx module sin/cos: SM_14 (14) X500

Select a motor encoder

Encoder type	Code number
<input checked="" type="checkbox"/> 2048, 1 Upp, A/B	2001
<input type="checkbox"/> 2048, 1 Upp, A/B	2002
<input type="checkbox"/> 256, 1 Upp, A/B R	2003
<input type="checkbox"/> 400, 1 Upp, A/B R	2004
<input type="checkbox"/> 512, 1 Upp, A/B R	2005
<input type="checkbox"/> 192, 1 Upp, A/B R	2006
<input type="checkbox"/> 480, 1 Upp, A/B R	2007
<input type="checkbox"/> 800, 1 Upp, A/B R	2008
<input type="checkbox"/> 18000, 1 Upp, A/B R Abstandscodiert	2010
<input type="checkbox"/> 2048, 1 Upp, A/B, EnDat, Multiturn 4096	2051
<input type="checkbox"/> 192, 1 Upp, A/B, EnDat, Multiturn 4096	2052

Select 'Identify', so that the drive unit identifies the connected encoder. This is conditional upon the encoder supporting the drive unit.

OK

The entry "No encoder" is selected in the encoder list for encoders that the drive unit cannot identify. The connected encoder must be configured.

Encoder: Encoder_15
Sensor Module: SMx module sin/cos: SM_14 (14) X500

Select a motor encoder

Encoder type	Code number
<input type="checkbox"/> Kein Geber	0
<input type="checkbox"/> Resolver 1-Speed	1001
<input type="checkbox"/> Resolver 2-Speed	1002
<input type="checkbox"/> Resolver 3-Speed	1003
<input type="checkbox"/> Resolver 4-Speed	1004
<input checked="" type="checkbox"/> 2048, 1 Upp, A/B C/D R	2001
<input type="checkbox"/> 2048, 1 Upp, A/B R	2002
<input type="checkbox"/> 256, 1 Upp, A/B R	2003
<input type="checkbox"/> 400, 1 Upp, A/B R	2004
<input type="checkbox"/> 512, 1 Upp, A/B R	2005
<input type="checkbox"/> 192, 1 Upp, A/B R	2006

Select 'Identify', so that the drive unit identifies the connected encoder. This is conditional upon the encoder supporting the drive unit.

Previous step
Identify
Enter data
Cancel
Next step

Configuration Drive parameter

- Select the motor encoder from the list: Select the encoder with the "Cursor up / Cursor down" keys. Alternatively, the encoder system can be parameterized manually using the "Enter data" softkey.

10. Press "Enter data".

Encoder data: Encoder 1 DP3.SLAVE3: SERVO_3.3:3 (3) MDS0

Encoder type: **Rotary**

Resolution: Pulse number per revolution 2048

Measuring system: Incremental sine/cosine

Encoder evaluation: SMx module sin/cos

Inversion: ☐ Invert speed actual value ☐ Invert position actual value

External zero mark: ☐ External zero mark

Input terminal: none

Zero marks: Configuration One zero mark/revolution, Offset 2048 Lines, Quantity 1

Buttons: Cancel, OK

Check the encoder data of the connected encoder and confirm with "OK".

- Encoder type
- Incremental tracks
- Zero marks
- Synchronization

11. Press "Next step >".

... \Drives \Configuration - CI-loop contr. type/set... DP3.SLAVE3: SERVO_3.3:3 (3) MDS0

CI-loop contr. type: Speed control (with encoder)

PROFIBUS PZD telegram: SIEMENS telegram 136, PZD-15/19

The PROFIBUS process data are interconnected with BICO parameters according to the telegram type selected. These BICO parameters cannot be changed at a later stage.

Number of DDSs for this MDS: 1

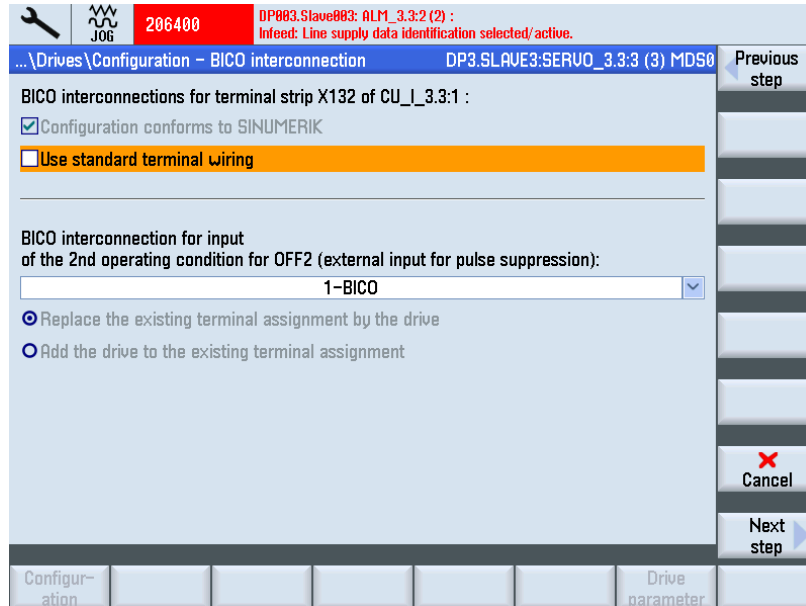
Buttons: Previous step, Cancel, Next step

12. Set the number of required drive data sets (DDS). The default setting is one drive data set.

13. You can change the settings for the control mode and the PROFIBUS telegram type.

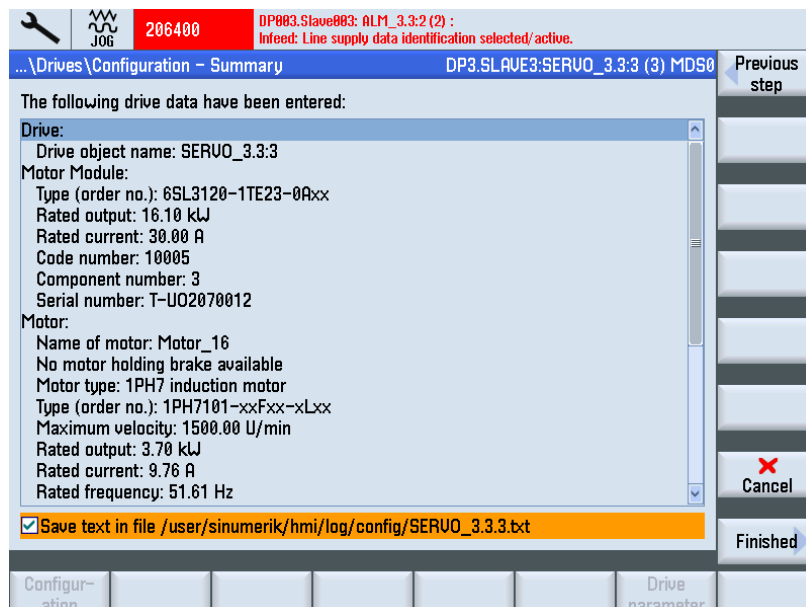
The control mode and the PROFIBUS telegram are generally correctly pre-assigned by the drive wizards.

14. Press "Next step >".



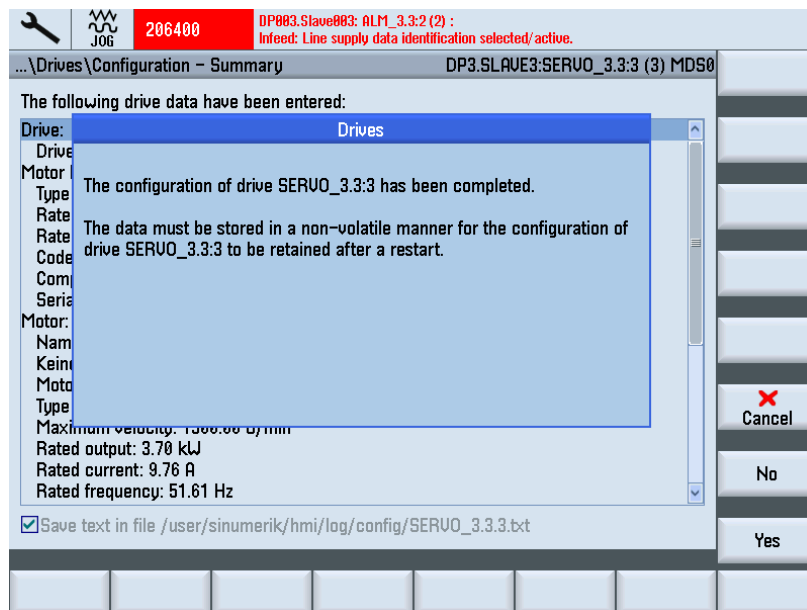
15. You can select the 2nd operating condition Input 2nd OFF2 (Page 71) (external input for pulse cancellation)

16. Press "Next step >".



17. The configuration of a drive with listed motor has completed. You can check the configuration in the summary.

18. Press the "Finish >" softkey.



19. Confirm the query with "Yes".

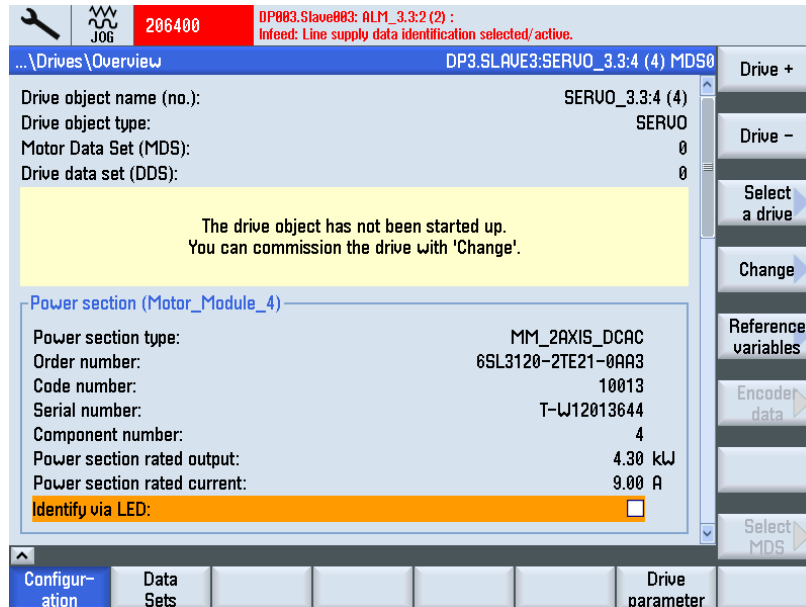
20. The next section describes how you can configure a drive with a third-party motor and a second encoder.

5.3.4.2 Commissioning a third-party motor with encoder via SMC

Operating sequence

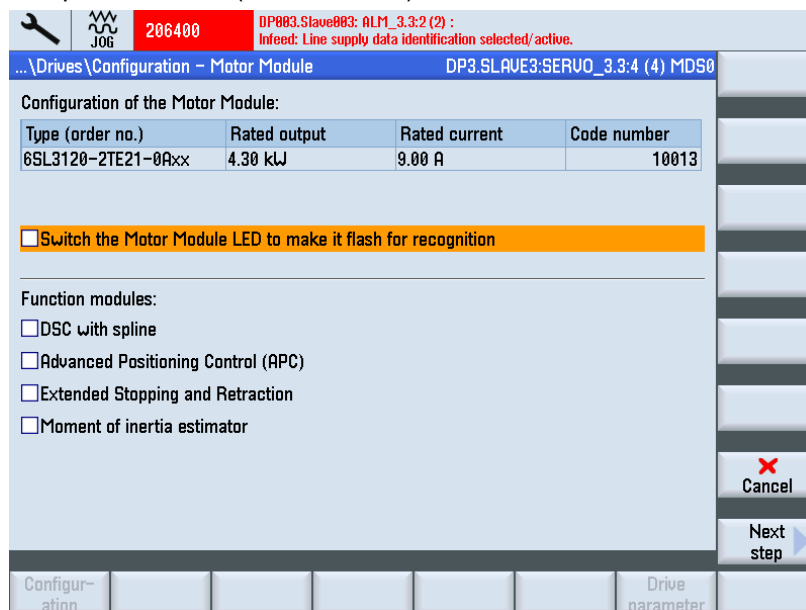
In our example a power section is to be configured with third-party motor and encoder. You are in the "Commissioning" → "Drive system" → "Drives" menu:

1. The system detects that the drive object has not been commissioned and that an initial commissioning is required:



2. Press the "Change" vertical softkey.

The power section (motor module) will be identified:



3. Press "Next step >".

DP003.Slave003: ALM_3.3:2 (2) :
Info: Line supply data identification selected/active.

206400

...\\Drives\\Configuration - Motor DP3.SLAVE3:SERVO_3.3:4 (4) MDS0

Motor selec.: ☐ Select a standard motor from the list
☒ Enter motor data ☐ Template from list

Motor type: Induction motor (rotating)

Previous step

Cancel

Next step

Configur- ation Drive parameter

4. Select the "Enter motor data" option to select the motor type.
5. Press "Next step >" to select the type of the brake control in the next dialog.

DP003.Slave003: ALM_3.3:2 (2) :
Info: Line supply data identification selected/active.

206400

...\\Drives\\Configuration - Other motor data DP3.SLAVE3:SERVO_3.3:4 (4) MDS0

Motor holding brake configuration

No motor holding brake available

☐ Expanded brake control

Previous step

Cancel

Next step

Configur- ation Drive parameter

If a connected brake is detected during the unit configuration, the system will automatically activate the brake control and displays "Brake control according to procedural control".

6. Press "Next step >".

Parameter	Value
p304[0] Rated motor voltage	400 Ueff
p305[0] Rated motor current	9.00 Aeff
p307[0] Rated motor power	4.80 kW
p308[0] Rated motor power factor	0.820
p310[0] Rated motor frequency	50.00 Hz
p311[0] Rated motor speed	1455.0 rpm
p322[0] Maximum motor speed	1500.0 rpm
p335[0] Motor cooling type	[1] Forced cool...
p604[0] Mot_temp_mod 1/KTY alarm threshold	120.0 °C
p605[0] Mot_temp_mod 1/2 threshold	155.0 °C

Motor data must be input completely!

☒ Do you want to input the equivalent circuit diagram data?

Next step >

7. Enter the data for the connected motor.

8. If you have activated the "Replacement circuit diagram data" option, press "Next step >" to open the following dialog:

Parameter	Value
p320[0] Motor rated magnetizing current/short-circuit...	0.000 Aeff
p326[0] Motor stall torque correction factor	100 %
p338[0] Motor limit current	0.00 Aeff
p341[0] Motor moment of inertia	0.019405 kgm²
p342[0] Ratio between the total and motor moment of ...	1.000
p344[0] Motor weight (for the thermal motor model)	42.6 kg
p348[0] Speed at the start of field weakening Udc = 6...	1455.0 rpm
p352[0] Cable resistance	0.00000 Ohm
p353[0] Motor series inductance	0.000 mH

Optional motor data need not be input completely.
Data that are not known can be left as their default values.

Next step >

9. You can enter additional motor data here.

10. Press "Next step >".

DP003.Slave003: ALM_3.3:2 (2) :
Info: Line supply data identification selected/active.

206400

... \Drives \Configuration - Motor data DP3.SLAVE3:SERVO_3.3:4 (4) MDS0

Equivalent circuit diagram data, asynchron. motor (rotating)

p350[0]	Motor stator resistance, cold	1.05474 Ohm
p354[0]	Motor rotor resistance cold / damping resista...	0.60003 Ohm
p356[0]	Motor stator leakage inductance	6.32114 mH
p358[0]	Motor rotor leakage inductance / damping ind...	6.58472 mH
p360[0]	Motor magnetizing inductance/magn. inducta...	157.90971 mH

Replacement circuit diagram data must be input completely!

Note:
If the replacement circuit diagram data are not fully known, you can calculate them by pressing the softkey 'Calculate ESB data' on the right.

Previous step

Recalc ESB data

Cancel

Next step >

Configur- ation

Drive parameter

11. Press "Next step >".

DP003.Slave003: ALM_3.3:2 (2) :
Info: Line supply data identification selected/active.

206400

... \Drives \Configuration - Encoder assignment DP3.SLAVE3:SERVO_3.3:4 (4) MDS0

☒ Encoder 1

SERVO_3.3:5-Motor_Module_5.X200-SM_6-Encoder_7, EDS 0

Sensor Module: SMx module sin/cos: SM_6 (6) X500

Encoder data set number (EDS): 0

Switch the Sensor Module LED to make it flash for recognition ☐

☐ Encoder 2

Sensor Module:

Encoder data set number (EDS):

Switch the Sensor Module LED to make it flash for recognition ☐

☐ Encoder 3

Sensor Module:

Encoder data set number (EDS):

Switch the Sensor Module LED to make it flash for recognition ☐

Previous step

Cancel

Next step >

Configur- ation

Drive parameter

If more than one encoder has been selected, press "Next step >" successively to parameterize each individual encoder:

12. Press "Next step >".

An identification of the selected encoders is triggered (Encoder 1).

The drive unit can identify encoders with EnDat protocol. Select other encoders in the encoder list:

DP003.Slave003: ALM_3.3:2 (2) :
Infected: Line supply data identification selected/active.

206400

... \Drives \Configuration - Encoder 1 DP3.SLAVE3:SERVO_3.3:4 (4) MDS0

Encoder: Encoder_7
Sensor Module: SMx module sin/cos: SM_6 (6) X500

Select a motor encoder

Encoder type	Code number
<input type="checkbox"/> Kein Geber	0
<input type="checkbox"/> Resolver 1-Speed	1001
<input type="checkbox"/> Resolver 2-Speed	1002
<input type="checkbox"/> Resolver 3-Speed	1003
<input type="checkbox"/> Resolver 4-Speed	1004
<input checked="" type="checkbox"/> 2048, 1 Upp, A/B C/D R	2001
<input type="checkbox"/> 2048, 1 Upp, A/B R	2002
<input type="checkbox"/> 256, 1 Upp, A/B R	2003
<input type="checkbox"/> 400, 1 Upp, A/B R	2004
<input type="checkbox"/> 512, 1 Upp, A/B R	2005
<input type="checkbox"/> 1024, 1 Upp, A/B R	2006

Select 'Identify', so that the drive unit identifies the connected encoder. This is conditional upon the encoder supporting the drive unit.

Previous step
Identify
Enter data
Cancel
Next step

13. Press the "Input data" softkey to check or modify the encoder data.

DP003.Slave003: ALM_3.3:2 (2) :
Infected: Line supply data identification selected/active.

206400

Encoder data: Encoder 1 DP3.SLAVE3:SERVO_3.3:4 (4) MDS0

Encoder type: Rotary

Resolution: Pulse number per revolution 2048

Measuring system: Incremental sine/cosine

Encoder evaluation: SMx module sin/cos

Inversion: ☐ Invert speed actual value
☐ Invert position actual value

External zero mark

Input terminal: none

Zero marks: Configuration One zero mark/revolution
Offset 2048 Lines
Quantity 1

Cancel
OK

14. Confirm with "OK" and press "Next step >" to continue the commissioning.

DP003.Slave003: ALM_3.3:2 (2) :
Info: Line supply data identification selected/active.

...\\Drives\\Configuration - CL-loop contr. type/set... DP3.SLAVE3:SERVO_3.3:4 (4) MDS0

CL-loop contr. type: **Speed control (with encoder)**

PROFIBUS PZD telegram: **SIEMENS telegram 136, PZD-15/19**

The PROFIBUS process data are interconnected with BICO parameters according to the telegram type selected. These BICO parameters cannot be changed at a later stage.

Number of DDSs for this MDS: **1**

Previous step

Cancel

Next step

Configur-ation Drive parameter

The control mode and the PROFIBUS telegram are generally correctly pre-assigned by the drive wizards.

15. Set the number of required drive data sets (DDS). The default setting: 1 DDS can be accepted in most cases.
16. Press "Next step >".

DP003.Slave003: ALM_3.3:2 (2) :
Info: Line supply data identification selected/active.

...\\Drives\\Configuration - BICO interconnection DP3.SLAVE3:SERVO_3.3:4 (4) MDS0

BICO interconnections for terminal strip X132 of CU_I_3.3:1 :

☒ Configuration conforms to SINUMERIK

☐ Use standard terminal wiring

BICO interconnection for input of the 2nd operating condition for OFF2 (external input for pulse suppression):

1-BICO

☒ Replace the existing terminal assignment by the drive

☐ Add the drive to the existing terminal assignment

Previous step

Cancel

Next step

Configur-ation Drive parameter

You can select the 2nd operating condition Input 2nd OFF2 (Page 71) (external input for pulse cancellation)

17. Press "Next step >".

DP3.SLAVE3.SERVO_3.3:4 (4) MDS0

The following drive data have been entered:

Drive:
Drive object name: SERVO_3.3:4

Motor Module:
Type (order no.): 6SL3120-2TE21-0Axx
Rated output: 4.30 kW
Rated current: 9.00 A
Code number: 10013
Component number: 4
Serial number: T-W12013644

Motor:
Name of motor: Motor_13
No motor holding brake available
Motor type: Induction motor (rotating)

Encoder 1:
Name of encoder: Encoder_7
Sensor Module: SMx module sin/cos: SM_6 (6) X500
Serial No. SMx: T-T12006886
Serial No. Encoder: -

☒ Save text in file /user/sinumerik/hmi/log/config/SERVO_3.3.4.txt

Previous step

Cancel

Finished

The configuration of the drive (SERVO) with third-party motor is completed. You can check the configuration in the summary.

18. Press the "Finish >" softkey.

DP3.SLAVE3.SERVO_3.3:4 (4) MDS0

The following drive data have been entered:

Drive:
Drive object name: SERVO_3.3:4

Motor Module:
Type (order no.): 6SL3120-2TE21-0Axx
Rated output: 4.30 kW
Rated current: 9.00 A
Code number: 10013
Component number: 4
Serial number: T-W12013644

Motor:
Name of motor: Motor_13
No motor holding brake available
Motor type: Induction motor (rotating)

Encoder 1:
Name of encoder: Encoder_7
Sensor Module: SMx module sin/cos: SM_6 (6) X500
Serial No. SMx: T-T12006886
Serial No. Encoder: -

☒ Save text in file /user/sinumerik/hmi/log/config/SERVO_3.3.4.txt

The configuration of drive SERVO_3.3:4 has been completed.

The data must be stored in a non-volatile manner for the configuration of drive SERVO_3.3:4 to be retained after a restart.

Cancel

No

Yes

19. Confirm the query with "Yes".

If the system detects additional drive objects that have not yet been commissioned, you will be prompted to commission the next SERVO. Otherwise, the initial commissioning is complete.

5.3.5 First commissioning of SINAMICS drive ended

Initial commissioning of the drives completed

The initial commissioning of the SINAMICS S120 drives is completed.

The unit configuration and parameterization has been completed successfully:

- All upper LEDs of the drives (SERVO) illuminate green.
- The lower LEDs of the drives (SERVO) always continue to light yellow.

Continue with the steps for commissioning the NC.

See also

Communication between the NC and the drive (Page 155)

5.4 Manual commissioning of SINAMICS drives

5.4.1 Introduction to commissioning of SINAMICS drives

Machine configuration

Note

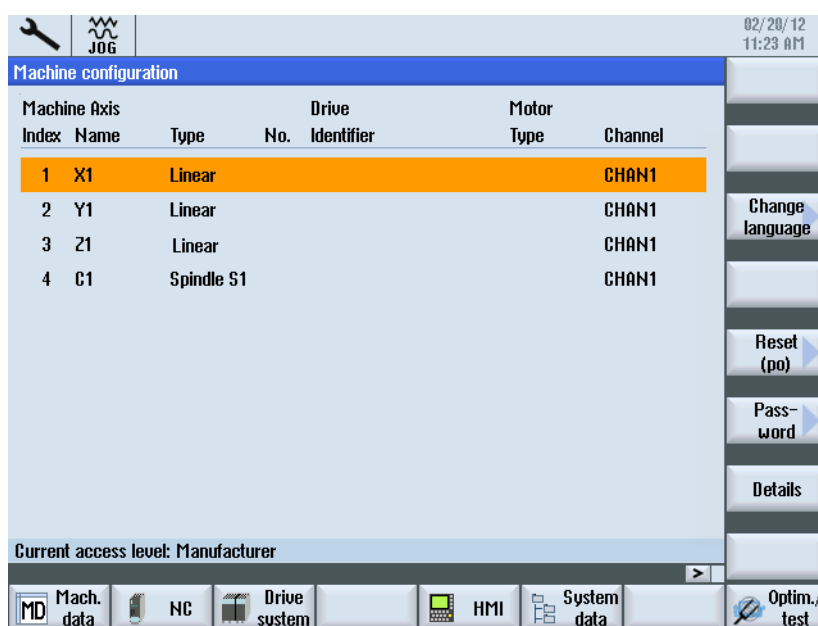
"Manually commissioning" is recommended for experienced commissioning engineers.

Procedure:

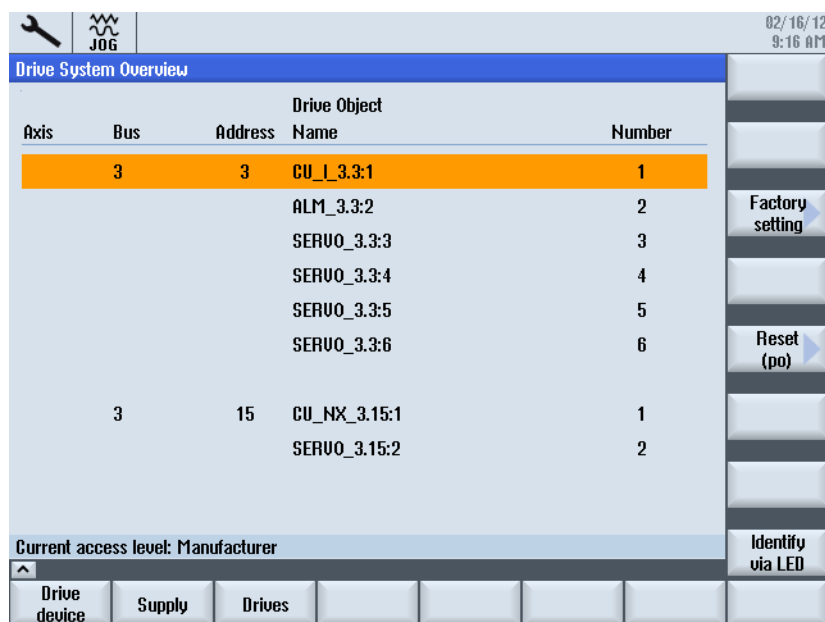
1. Press the <MENU SELECT> key.



2. Select the "Commissioning" operating area.



3. Press the "Drive system" softkey.



See also

The following functions for commissioning the SINAMICS drives can be performed manually:

- Restore the factory settings (Page 102)
- Update the component firmware (Page 104)
- Configure the infeed and drives
- Check and configure the PROFIBUS connection (Page 106)

5.4.2 Activate the factory settings

Introduction

After the commissioning, the "Factory setting >" function can be used reset the drive system to the factory settings.

NOTICE

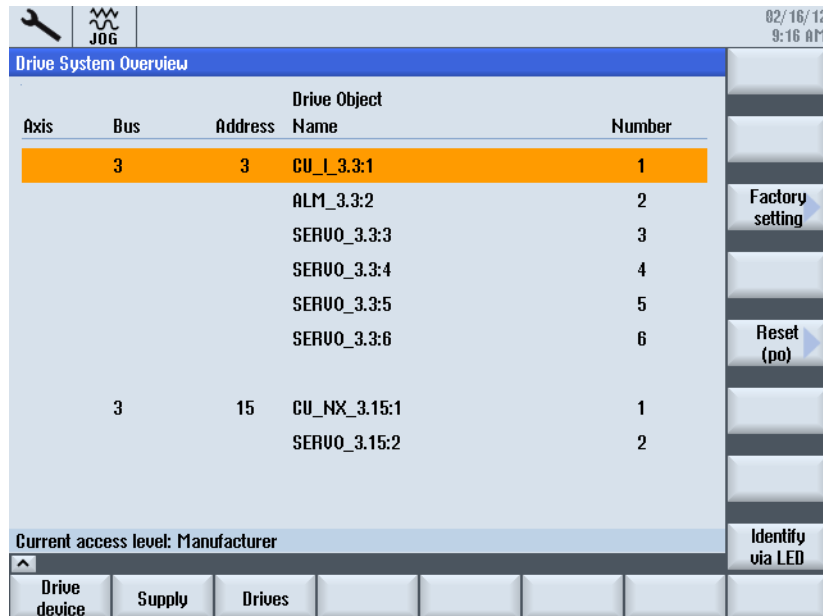
Check the voltage

Before restoring the factory settings, ensure that the EP terminal (Enable Pulses) of the infeed (booksize: X21, chassis: X41) is de-energized.

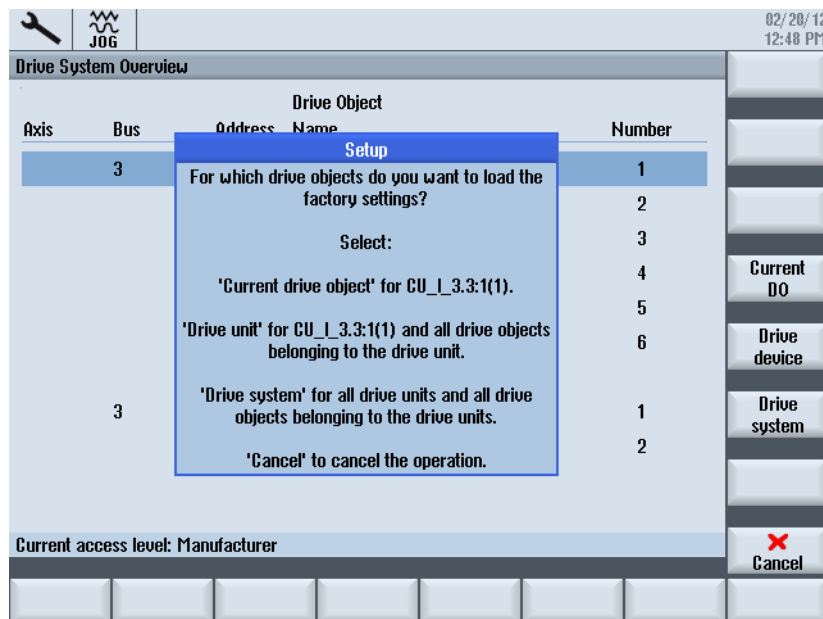
Loading the factory settings

Procedure:

1. You are in the "Commissioning" > "Drive system" operating area.



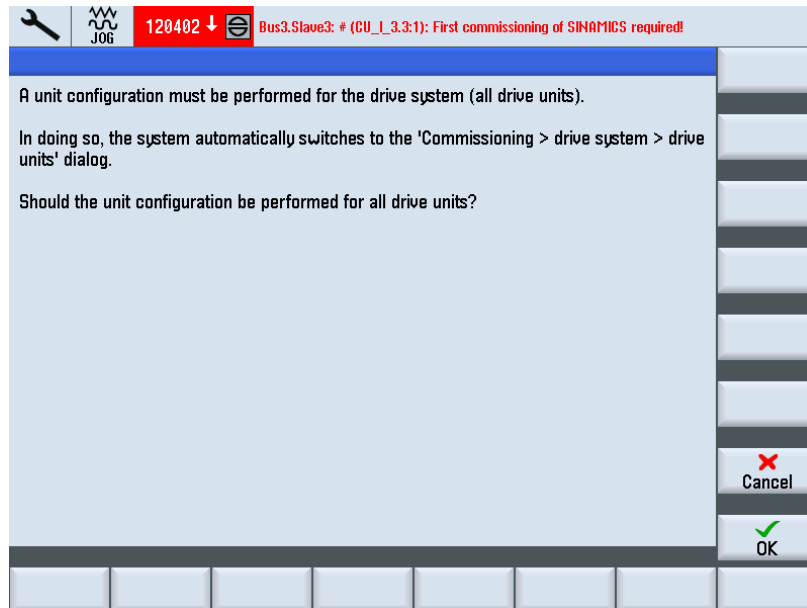
2. Press the "Factory settings >" softkey.



3. Press the "Drive system" softkey for this example to load the factory settings for all drive units used in the system (the NCU and NX module).

You must explicitly confirm another prompt with "OK" or "Cancel".

4. Switch the system (de-energized drive system) off and on again. Wait until communication has been established again with the NC.



5. A message appears that an initial commissioning is required (Alarm 120402).
You have the following options in this dialog:
 - If you press "OK", the "Guided commissioning" (Page 76) of the SINAMICS drives starts.
 - Press "Cancel" to continue the "Manual commissioning".

5.4.3 Firmware update of the drive components

Precondition

All NCU/NX components are connected via DRIVE-CLiQ.

Note

Automatic firmware update

As of SINAMICS V2.5, an automatic firmware update is undertaken when powering up the drive system if required.

The correct firmware update of the SINAMICS components is performed **ONLY** if **ALL** were inserted in the switched-off state. The subsequent insertion of components may **ONLY** be performed in the switched-off state.

Loading firmware for the entire drive system

Procedure:

1. Switch on the system.

During run-up, it will be detected that an older firmware version is present. This causes the update to start automatically and the firmware is loaded from the CompactFlash card to all DRIVE-CLiQ components of the drive system (NCU and NX).

Note

Depending on the configuration of the SINAMICS drive line-up, a complete update of the component firmware takes approximately 10 minutes. The firmware component currently being updated is indicated with a flashing LED.

2. While the firmware update is running, a progress bar informs you about the current process. In this case, the following messages are output:

Notice!

The process should not be interrupted! Please wait until the automatic firmware update completes!

A firmware update is performed for the following drive units of the DRIVE-CLiQ components:

CU_I_3.3:1 ... 39%

CU_NX_3.15:1 ... 50%

3. The following messages are output when the firmware update completes:

Firmware update of the DRIVE-CLiQ components completed.

Notice!

Switch the control system and the entire drive system (all hardware components) off and then on again to activate the firmware.

Then commissioning can be continued.

CU_I_3.3:1 ... 100%

CU_NX_3.15:1 ... 100%

4. Follow this prompt. You can then continue the commissioning of the drive components (infeed, motor modules, encoders).

Note

Loading firmware for individual components

If only certain components of the drive system have an older firmware version, the update also starts automatically and needs correspondingly less time.

5.4.4 Automatic device configuration

Introduction

The following unit configuration is performed during the initial commissioning of the drive units:

- Transfer of the DRIVE-CLiQ topology to the drive unit.

With the transfer of the topology, all components connected on the DRIVE-CLiQ are detected and the drive-internal data traffic is initialized.

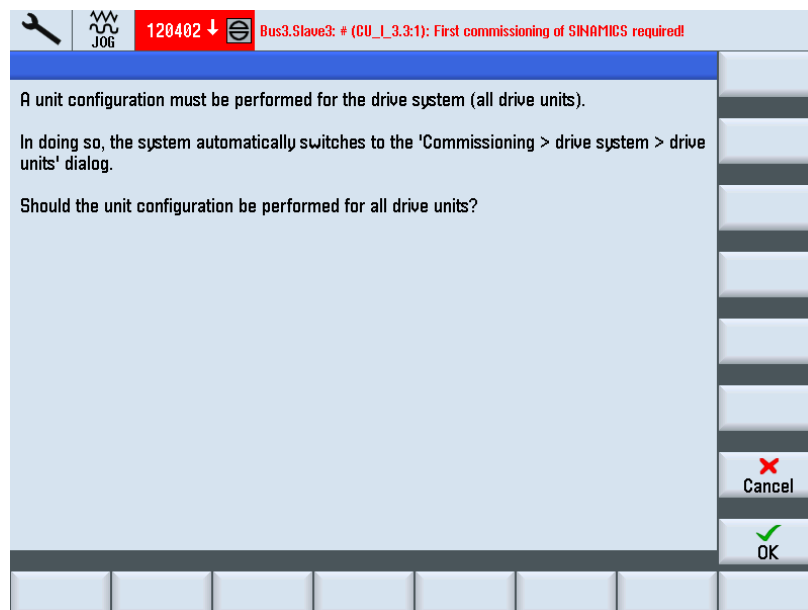
- Drive-object assignment for PROFIBUS connection.

The PROFIBUS connection via the relevant telegrams has been specified with the configuration in the HW Config.

Operating sequence

The drive unit is in the initial commissioning state.

1. Press the "Drive units" softkey in the "Commissioning" > "Drive system" menu.



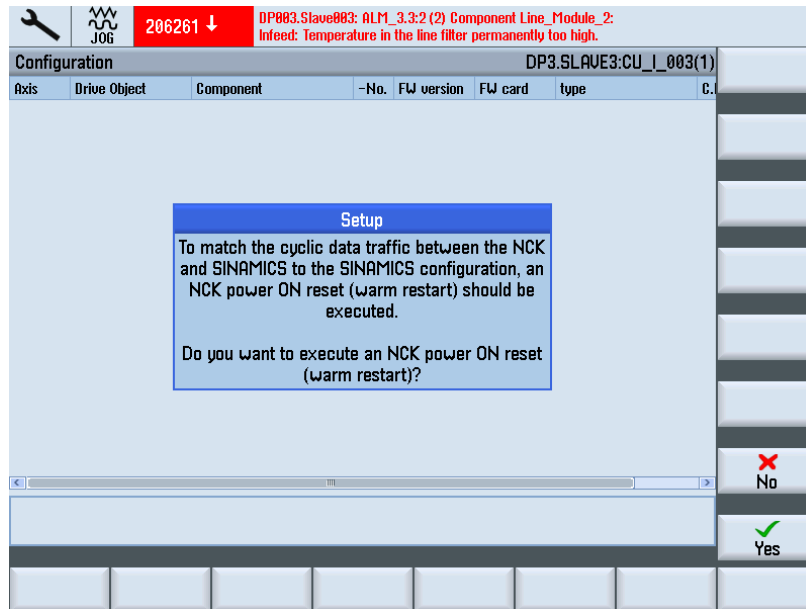
You are reminded that the drive unit is in the initial commissioning state and that a unit configuration must be performed for the drive system.

2. Confirm with "OK".

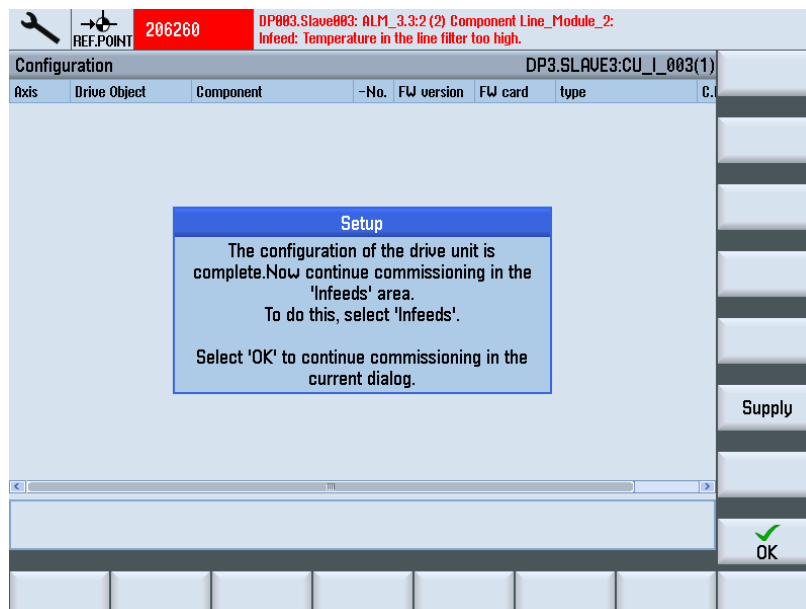
During the unit configuration, a succession of messages containing information on the respective configuration of the individual drive components is displayed.

Depending on the size of the drive system, this can take several minutes.

Before the configuration is completed, you must confirm the following prompt:



3. Press "Yes" to perform an NCK power on reset (warm restart).



The unit configuration for the drive units and drive components of the NCU has been completed.

4. Press "OK".

This means that you continue commissioning in the actual dialog box "Drive system" → "Drive units" → "Configuration". The associated components of the selected drive unit are displayed:

NC-axis	NC Telegram type	I-/O-addr.	Slot	SINAMICS-drive object	SINAMICS-telegram type
AX1:X1	SIEMENS 136	6700	4	SERVO_3.3:3(3)	SIEMENS 136
		6700	4		
		4100	5		
		4100	6		
AX2:Y1	--	6724	8	(255)	--
		6724	8		
		4140	9		
		4140	10		
AX3:Z1	--	6748	12	(255)	--
		6748	12		
		4180	13		
		4180	14		
AX4:A1	--	6772	16	(255)	--
		6772	16		
		4220	17		
		4220	18		
AX5:B1	--	6796	20	(255)	--
		6796	20		

5. If necessary, check and correct the settings in the "PROFIBUS" dialog.

NC-axis	NC Telegram type	I-/O-addr.	Slot	SINAMICS-drive object	SINAMICS-telegram type
AX1:X1	SIEMENS 136	6700	4	SERVO_3.3:3(3)	SIEMENS 136
		6700	4		
		4100	5		
		4100	6		
AX2:Y1	--	6724	8	(255)	--
		6724	8		
		4140	9		
		4140	10		
AX3:Z1	--	6748	12	(255)	--
		6748	12		
		4180	13		
		4180	14		
AX4:A1	--	6772	16	(255)	--
		6772	16		
		4220	17		
		4220	18		
AX5:B1	--	6796	20	(255)	--
		6796	20		

6. Press "Drive unit +".

If you have selected the NX, then the components belonging to the NX are displayed.

Axis	Drive Object	Component	-No.	FW version	type
	CU_NX_3.15:1	CU_LINK_1	1	4503000	NX15.3
	SERVO_3.15:2	Motor_Module_2	2	4503000	MM_1AXIS_DCAC
	SERVO_3.15:2	DRIVE-CLIQ-Encoder_3	3	4503000	DQEncoder
	SERVO_3.15:2	Encoder_4	4	---	Analog Sensor
	SERVO_3.15:2	SMI20_5	5	4503000	SMI20/DQI
	SERVO_3.15:2	Encoder_6	6	---	Analog Sensor
	SERVO_3.15:2	Motor_SMI_7	7	---	SMI-Motor

CU_NX_3.15:1.CU_LINK_1(1)

Configuration Topology PROFIBUS

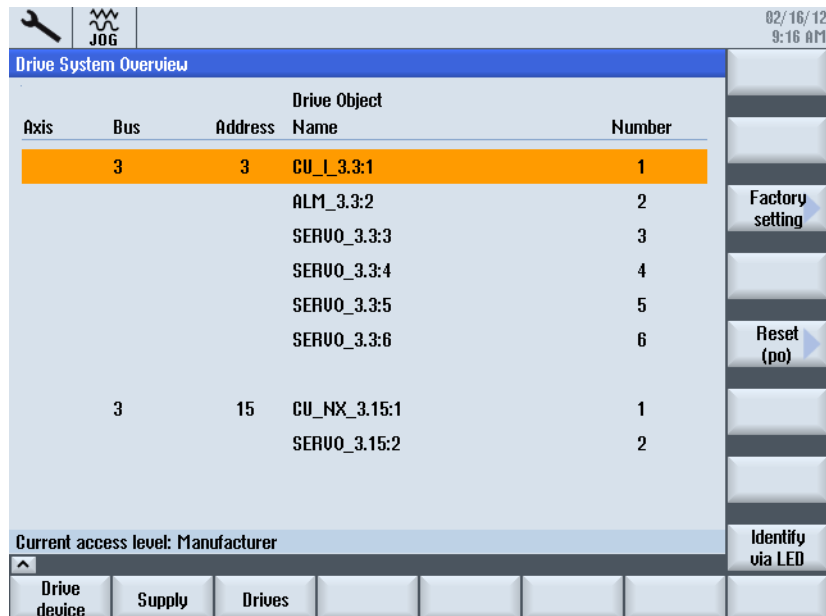
If necessary, you can correct or change the settings in the "PROFIBUS" dialog.

7. Press "PROFIBUS" → "Change>".

NC-axis	NC Telegram type	I/O-addr.	Slot	SINAMICS-drive object	SINAMICS-telegram type
AX7:U1	SIEMENS 136	6844	4	SERVO_3.15:2(2)	SIEMENS 136
		6844	4		
		4340	5		
		4340	6		
AX8:U1	--	6868	8	(255)	--
		6868	8		
		4300	9		
		4300	10		
AX9:AX9	--	6892	12	(255)	--
		6892	12		
		4420	13		
		4420	14		
AX10:AX10	--	6916	16	(255)	--
		6916	16		
		4460	17		
		4460	18		
AX11:AX11	--	6940	20	(255)	--
		6940	20		

Configuration Topology

8. Press "Cancel" to exit the dialog.
9. Press the menu back key.



Axis	Bus	Address	Drive Object Name	Number
	3	3	CU_I_3.3:1	1
			ALM_3.3:2	2
			SERVO_3.3:3	3
			SERVO_3.3:4	4
			SERVO_3.3:5	5
			SERVO_3.3:6	6
	3	15	CU_NX_3.15:1	1
			SERVO_3.15:2	2

Current access level: Manufacturer

Buttons: Drive device, Supply, Drives, [], [], [], [], []

Right side buttons: Factory setting, Reset (po), Identify via LED

5.4.5 Commissioning using a drive wizard

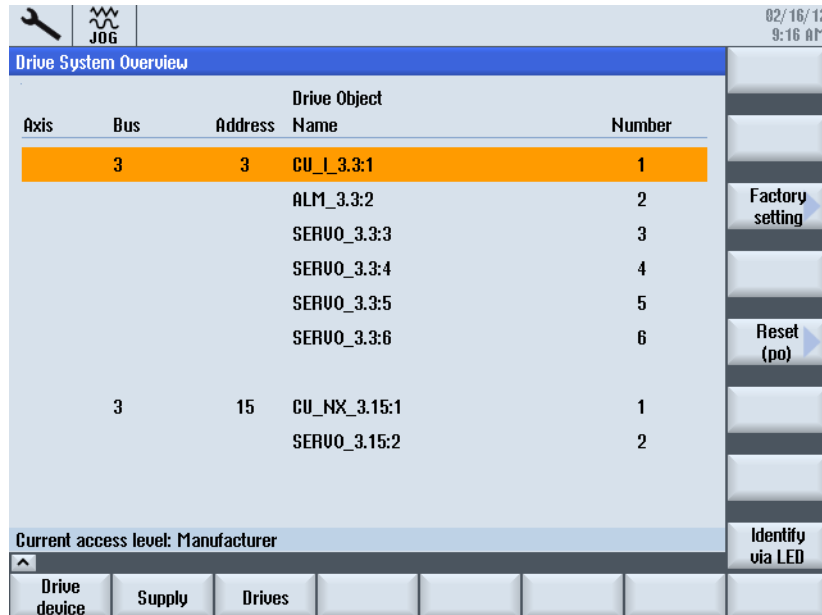
Introduction

Perform the drive configuration with a drive wizard. The following drive components are to be configured:

- Active Line Module (infeed)
- Motor Module, motor and encoders (drives)

Operating sequence for drive configuration

To start the drive configuration, select the "Commission" → "Drive system" operating area:



Procedure:

1. Press the corresponding softkey for the drive object to be configured.
 - "Infeeds"
 - "Drives" for the corresponding drive object (SERVO)

Configuration is performed in the following sequence:

2. Select the component with the "Infeed+/Infeed-" or "Drive+/Drive-" vertical softkey.
3. Press the "Change" vertical softkey and follow the drive wizard with the "Next step >" horizontal softkey.
4. Parameterize the appropriate configuration in the following dialogs.
5. Check the network data of the infeed with the "Network data (Page 147)" softkey.

See also

The individual dialogs are described at:

- "Parameterization of infeed (Page 81)"
- "Parameterization of the drives (Page 85)"

5.5 Configuring data sets

Precondition

Note

The particular drives must have been already commissioned.

Data sets

The data sets are configured in the "Commissioning" → "Drive system" → "Drives" → "Data sets" operating area. The following prompts lead you through the sequences:

- "Add data set"
- "Remove data set" if an additional data set has already been created
- "Modify data set"

Number of configurable data sets:

- Motor data set → MDS0...3 (max. 4)
- Drive data set → DDS0...31 (max. 8 per MDS)
- Encoder data sets → EDS0...2 (max. 3)

References

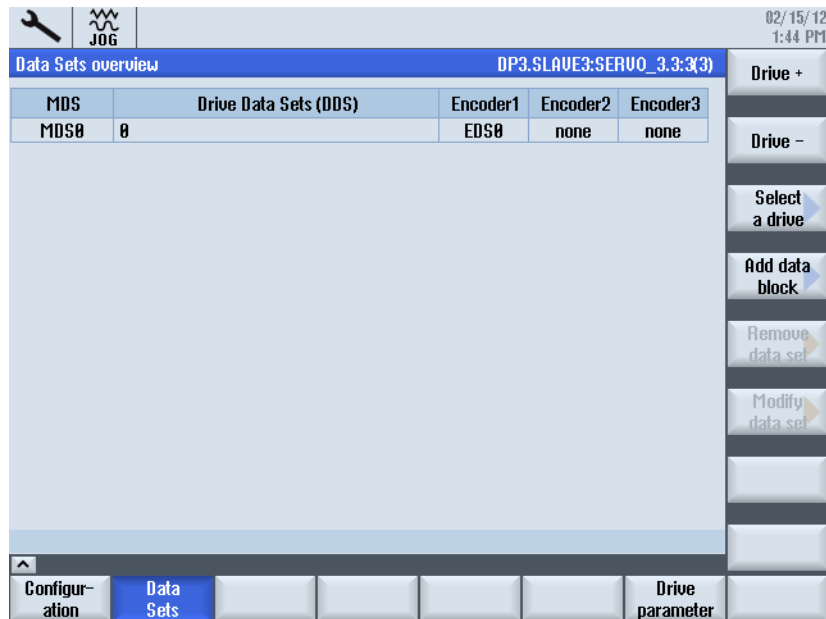
You can find additional information in:

SINUMERIK 840D sl/828D Basic Functions Function Manual, various NC/PLC interface signals and functions (A2)

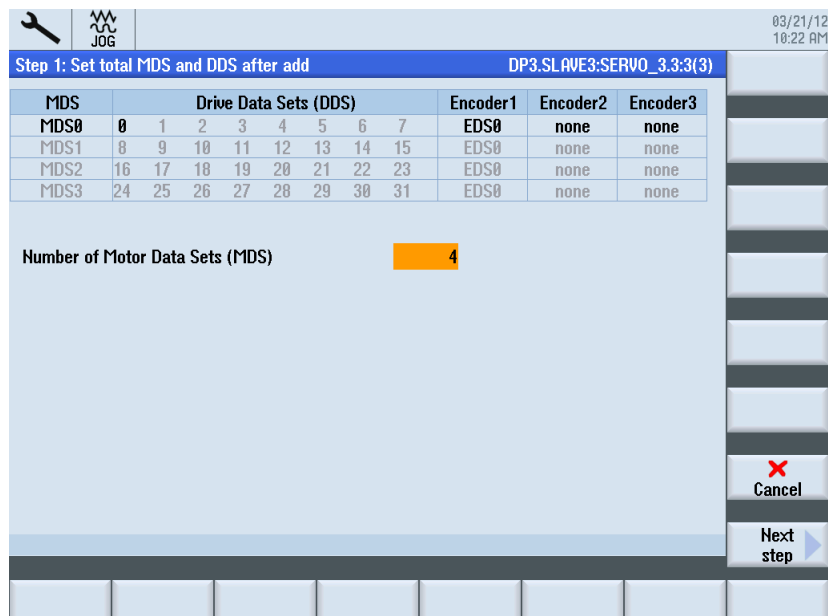
5.5.1 Adding a data set

Adding a data set operating sequence

The default factory setting specifies an MDS0 motor data set with a DDS0 drive data set and an EDS0 encoder data set:



1. Press "Add data set". In the example, the maximum number of four MDSeS are created.



2. Press "Next step >".

In the first step, the DDS1 to DDS7 drive data sets are created in the MDS0.

Step 2 of 7: Define MDS0 DP3.SLAVE3:SERVO_3.3:3(3)

MDS	Drive Data Sets (DDS)								Encoder1	Encoder2	Encoder3
MDS0	0	1	2	3	4	5	6	7	EDS0	none	none
MDS1	8	9	10	11	12	13	14	15	EDS0	none	none
MDS2	16	17	18	19	20	21	22	23	EDS0	none	none
MDS3	24	25	26	27	28	29	30	31	EDS0	none	none

☐ copy MDS data from

☒ copy DDS data from

☐ array ☒ single DDS0

source DDS

0	0	0	0	0	0	0	0
---	---	---	---	---	---	---	---

↓ ↓ ↓ ↓ ↓ ↓ ↓ ↓

MDS0	1	2	3	4	5	6	7	EDS0	EDS1	none
target MDS	target DDS							encoder of target MDS		

☒ Start drive assistant to configure data sets

Cancel Next step

3. Press "Next step >". The MDS1 motor data set is created.

Step 3 of 7: Define MDS1 DP3.SLAVE3:SERVO_3.3:3(3)

MDS	Drive Data Sets (DDS)								Encoder1	Encoder2	Encoder3
MDS0	0	1	2	3	4	5	6	7	EDS0	none	none
MDS1	8	9	10	11	12	13	14	15	EDS0	none	none
MDS2	16	17	18	19	20	21	22	23	EDS0	none	none
MDS3	24	25	26	27	28	29	30	31	EDS0	none	none

☒ copy MDS data from MDS0

☒ copy DDS data from

☐ array ☒ single DDS0

source MDS source DDS

MDS0	0	0	0	0	0	0	0	0
------	---	---	---	---	---	---	---	---

↓ ↓ ↓ ↓ ↓ ↓ ↓ ↓

MDS1	8	9	10	11	12	13	14	15	EDS0	EDS1	none
target MDS	target DDS							encoder of target MDS			

☒ Start drive assistant to configure data sets

Cancel Next step

4. Press "Next step >". The MDS2 motor data set is created.

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Step 4 of 7: Define MDS2 DP3.SLAVE3:SERVO_3.3:3(3)

MDS	Drive Data Sets (DDS)								Encoder1	Encoder2	Encoder3
MDS0	0	1	2	3	4	5	6	7	EDS0	none	none
MDS1	8	9	10	11	12	13	14	15	EDS0	none	none
MDS2	16	17	18	19	20	21	22	23	EDS0	none	none
MDS3	24	25	26	27	28	29	30	31	EDS0	none	none

☒ copy MDS data from MDS0

☒ copy DDS data from

☐ array ☐ single DDS0

source MDS source DDS

MDS0	0	0	0	0	0	0	0	0
↓	↓	↓	↓	↓	↓	↓	↓	↓

MDS2	16	17	18	19	20	21	22	23	EDS0	EDS1	none
↓	↓	↓	↓	↓	↓	↓	↓	↓	↓	↓	↓

target MDS target DDS encoder of target MDS

☒ Start drive assistant to configure data sets

Cancel Next step

5. Press "Next step >". The MDS3 motor data set is created.

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Step 5 of 7: Define MDS3 DP3.SLAVE3:SERVO_3.3:3(3)

MDS	Drive Data Sets (DDS)								Encoder1	Encoder2	Encoder3
MDS0	0	1	2	3	4	5	6	7	EDS0	none	none
MDS1	8	9	10	11	12	13	14	15	EDS0	none	none
MDS2	16	17	18	19	20	21	22	23	EDS0	none	none
MDS3	24	25	26	27	28	29	30	31	EDS0	none	none

☒ copy MDS data from MDS0

☒ copy DDS data from

☐ array ☐ single DDS0

source MDS source DDS

MDS0	0	0	0	0	0	0	0	0
↓	↓	↓	↓	↓	↓	↓	↓	↓

MDS3	24	25	26	27	28	29	30	31	EDS0	EDS1	none
↓	↓	↓	↓	↓	↓	↓	↓	↓	↓	↓	↓

target MDS target DDS encoder of target MDS

☒ Start drive assistant to configure data sets

Cancel Next step

6. Press "Next step >". You need to create a complete MDS as shown in the following diagram, or as an option, enter the number of DDS for the MDSx:

Step 6 of 7: Adjust DDS on MDS3 (optional) DP3.SLAVE3:SERVO_3.3:3(3)

MDS	Drive Data Sets (DDS)								Encoder1	Encoder2	Encoder3
MDS0	0	1	2	3	4	5	6	7	EDS0	none	none
MDS1	8	9	10	11	12	13	14	15	EDS0	none	none
MDS2	16	17	18	19	20	21	22	23	EDS0	none	none
MDS3	24	25	26	27	28	29	30	31	EDS0	none	none

Number of DDS on MDS3 8

Cancel Next step

7. Press "Next step >" to check in the summary the changes to be performed.

Step 7 of 7: Summary of proposed changes DP3.SLAVE3:SERVO_3.3:3(3)

Press "Finish" to make the following changes

The number of MDS will be increased from 1 to 4.
 For existing MDS0, the number of DDS per MDS will be increased from 1 to 8.
 The number of DDS for MDS3 will be set to 8.

The new configuration will contain 4 MDS (MDS0...MDS3).
 Every MDS will contain 8 DDS.

Cancel Finished

8. Press "Finish >" to accept the changes.

03/21/12 10:24 AM

DP3.SLAVE3:SERVO_3.3:3(3)

MDS	Drive Data Sets (DDS)							Encoder1	Encoder2	Encoder3	
MDS0	0	1	2	3	4	5	6	7	EDS0	none	none
MDS1	8	9	10	11	12	13	14	15	EDS0	none	none
MDS2	16	17	18	19	20	21	22	23	EDS0	none	none
MDS3	24	25	26	27	28	29	30	31	EDS0	none	none

Save to non-volatile memory?

Data Set configuration changes have not been saved to non-volatile storage.

Save Data Set configuration changes now?

Cancel OK

9. Confirm with "OK" to save the data in non-volatile memory.

The saving/writing of the parameters can take several minutes.

10. The "Drives" → "Overview" dialog of the drive object is displayed. The "Select MDS >" softkey is now available. Press "Select MDS...".

03/21/12 10:24 AM

DP3.SLAVE3:SERVO_3.3:3(3) MDS0

Drive object name (no.): SERVO_3.3:3 (3)

Drive object type: SERVO

Motor Data Set (MDS): 0

Drive data set (DDS): 0..7

PROFIBUS P2D telegram: SIEMENS telegram 136, P2D-15/19

CL-loop contr. type: Speed control (with encoder)

Power section (Motor_Module)

Power section type: MM_1AXIS_DCAC

Order number: 6SL3120-1TE23-0AA3

Code number: 10005

Serial number: T-U02070012

Component number: 3

Power section rated output: 16.10 kW

Power section rated current: 30.00 A

Identify via LED: ☐

Direct selec. Motor data set

MDS0:DDS0..7

MDS1:DDS8..15

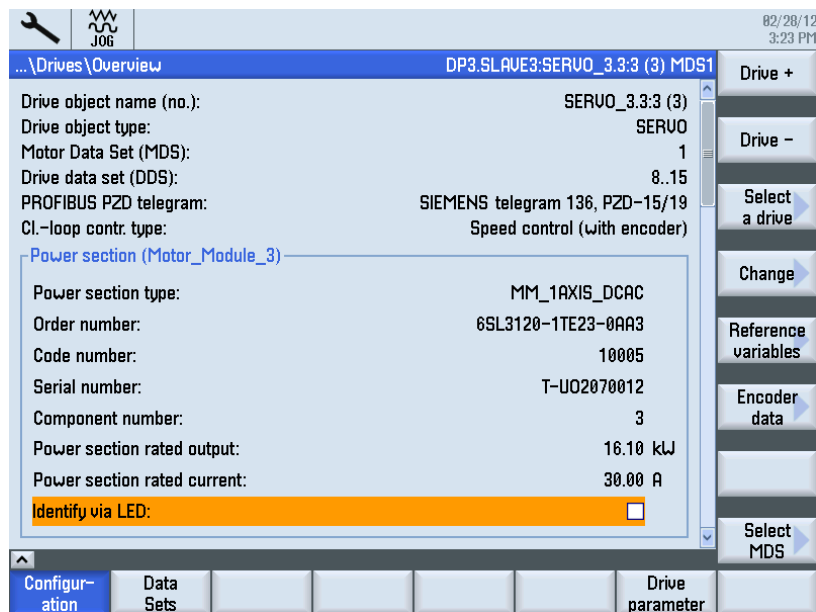
MDS2:DDS16..23

MDS3:DDS24..31

Cancel OK

In the direct selection, select the motor data set, e.g. in this case MDS1.

11. Press "OK" to display the new motor data set for the drive object.



The drive is now operational.

5.5.2 Modify data set

Precondition

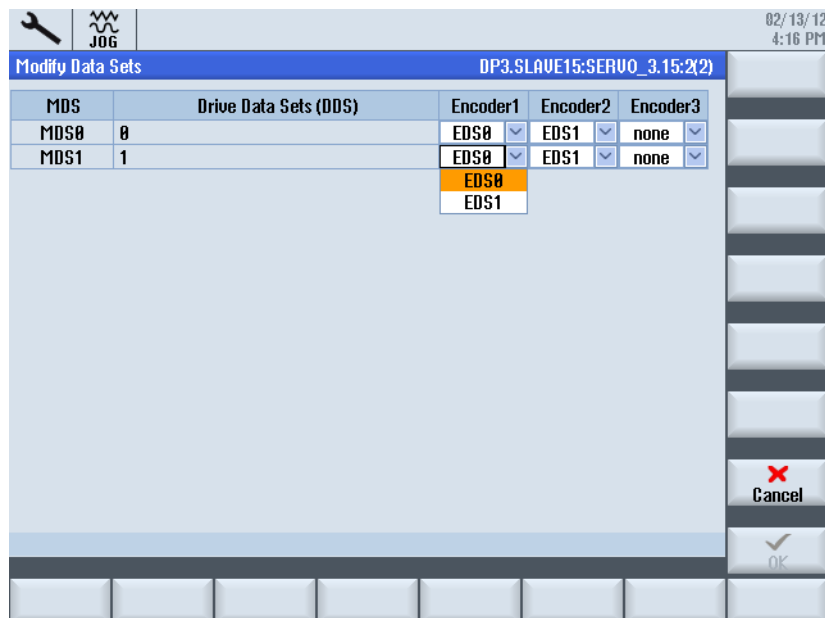
If more than one encoder is assigned to the drive object (SERVO), additional encoder data sets (EDS0 ... 2) will be created.

Modify data set

To change the assignment of these encoder data sets for the associated encoder, select the "Modify data sets" softkey:



This activates the edit function in order to subsequently modify the assignment of EDSes to the encoders:



5.5.3 Remove data set

Precondition

To remove data sets, the following conditions must be met:

- Number of DDS > 1 in the MDS ⇒ DDSes can be removed.
- Number of MDS > 1 ⇒ MDSes can be removed.

Operating sequence to remove a data set

1. Select "Remove data set":

Step 1 of 3: Select MDS(s) to remove DP3.SLAVE3:SERVO_3.3:3(3)

	Before						After				
	Motor	Drive	Enc1	Enc2	Enc3	?	Motor	Drive	Enc1	Enc2	Enc3
<input type="checkbox"/>	MDS0	DDS0...7	EDS0	none	none		MDS0	DDS0...7	EDS0	none	none
<input type="checkbox"/>	MDS1	DDS8...15	EDS0	none	none		MDS1	DDS8...15	EDS0	none	none
<input type="checkbox"/>	MDS2	DDS16...23	EDS0	none	none		MDS2	DDS16...23	EDS0	none	none
<input checked="" type="checkbox"/>	MDS3	DDS24...31	EDS0	none	none						

Ready to remove: MDS3

Cancel Next step

In the first column, select the MDS to be removed by marking the row with a check mark. Several data sets can also be selected.

2. Press "Next step >".

Step 2 of 3: Adjust DDS on MDS2 (optional) DP3.SLAVE3:SERVO_3.3:3(3)

MDS	Drive Data Sets (DDS)								Encoder1	Encoder2	Encoder3
MDS0	8	1	2	3	4	5	6	7	EDS0	none	none
MDS1	8	9	10	11	12	13	14	15	EDS0	none	none
MDS2	16	17	18	19	20	21	22	23	EDS0	none	none

Number of DDS on MDS2: 3

Buttons: Cancel, Next step

As an option, you can remove the remaining DDSes from MDS2 by entering the number of DDS drive data sets that should remain in the MDS: By entering 3 DDS in MDS, five DDSes are removed.

3. Press "Next step >".

Step 3 of 3: Summary of proposed changes DP3.SLAVE3:SERVO_3.3:3(3)

Press "Finish" to make the following changes

MDS3 will be removed.

The number of DDS for the last MDS will be set to 3.


The new configuration will contain 3 MDS (MDS0...MDS2).
Every MDS will contain 8 DDS, except for MDS2 which will contain 3 DDS.

Buttons: Cancel, Finished

"Cancel" terminates this process and the data set overview with MDS0 ... MDS3 is displayed.

4. Press "Finish >" to accept the changes.

The data is written to the parameters. The results are then displayed:



JOG

02/15/12
1:58 PM

Data Sets overview

DP3.SLAVE3.SERVO_3.3.333

MDS	Drive Data Sets (DDS)								Encoder1	Encoder2	Encoder3
MDS0	0	1	2	3	4	5	6	7	EDS0	none	none
MDS1	8	9	10	11	12	13	14	15	EDS0	none	none
MDS2	16	17	18						EDS0	none	none

^

Configuration

Data Sets

Drive parameter

Drive +

Drive -

Select a drive

Add data block

Remove data set

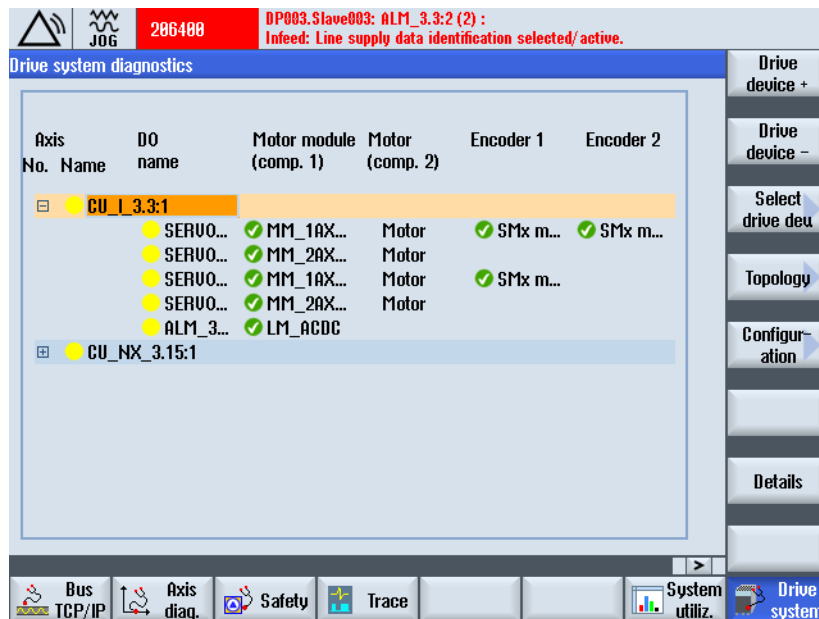
Modify data set

When you exit this dialog, press "Yes" to confirm the prompt to save the data to the non-volatile memory.

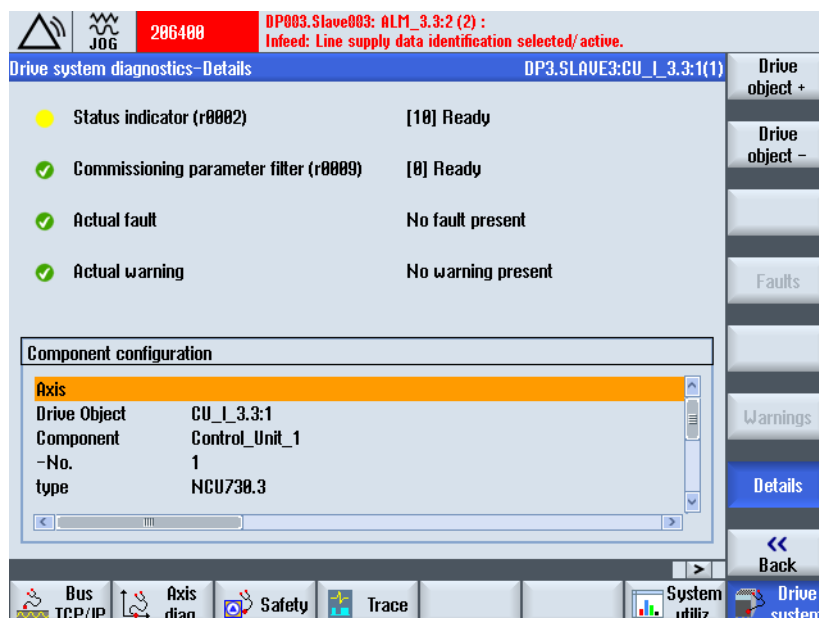
5.6 Drive system diagnostics

Operating sequence

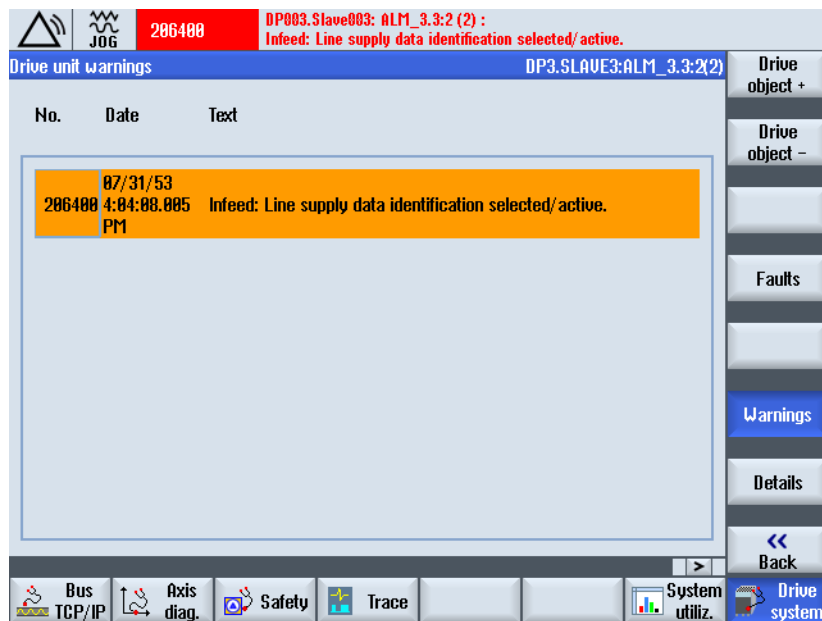
1. To check warnings and faults of the drive, select the "Diagnostics" → "Drive system" operating area:



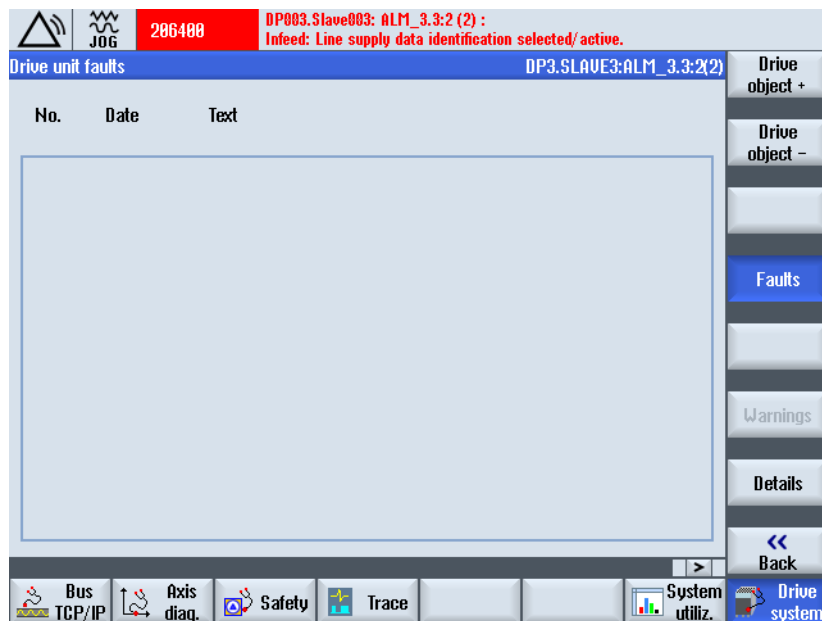
2. Select the relevant drive component with the cursor in the overview of the drive states.
3. Press the "Details" softkey:



4. Press "Warnings". The warnings for this drive component are listed.



5. Press "Faults": No faults are present for this drive component.



See also

Adding components (Page 141)

Check topology (Page 132)

Warnings/faults

SINAMICS alarms can be the warning (A) or fault (F) type.

- Pending **warnings** are indicated by parameter r2122 of the relevant drive components.
- The number of warnings that have occurred after the last reset is available in parameter p2111 of the drive components.

p2111 = 0 This results in the deletion of all existing warnings of this component and updates the current warnings still pending. This parameter is reset to zero at POWER ON.
- The parameter r0945 shows the numbers of **faults** that have occurred.
- To activate the fault and warning buffer output for SINAMICS, set MD13150 \$MN_SINAMICS_ALARM_MASK to the hexadecimal value "D0D". This automatically outputs the pending warnings/faults of the SINAMICS S120 in the message line.

5.7 Modular machine

5.7.1 What does "modular machine" mean?

Modular machine

The modular machine concept is based on a maximum target topology created offline. The maximum design of a particular machine type is referred to as the maximum configuration in which all the machine components that may be used are pre-configured in the target topology. By deactivating/deleting drive objects (p0105 = 2), sections of the maximum configuration can be removed.

If a component fails, the sub-topology can also be used to allow a machine to continue running until the spare part is available. In this case, however, no BICO source must be interconnected from this drive object to other drive objects.

NOTICE

Data backup

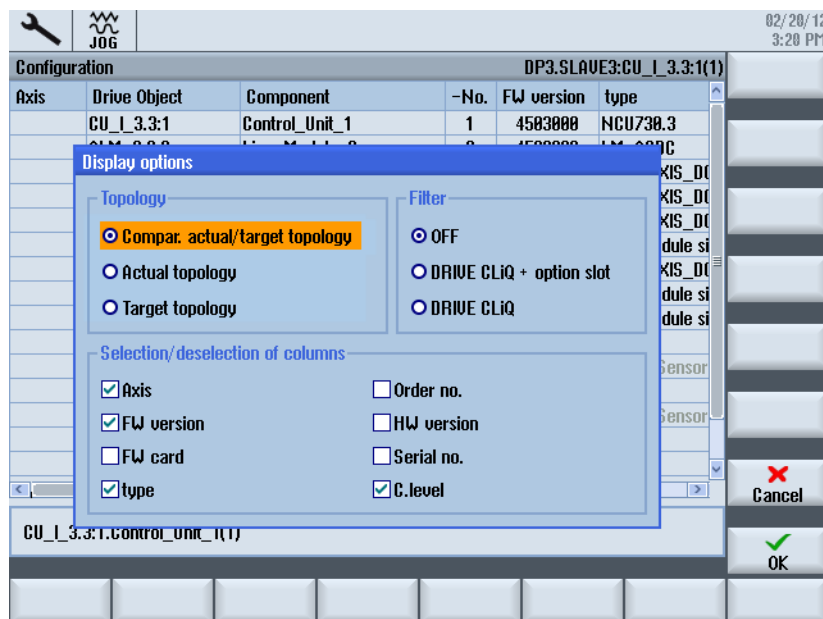
To prevent data loss, save the drive data in a commissioning archive (Page 319), before you make any changes!

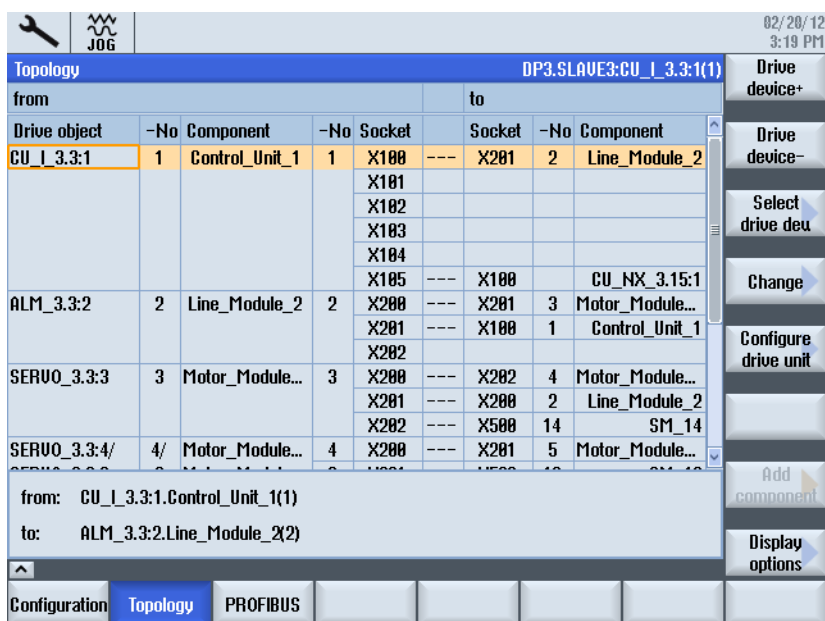
Drive unit - Configuration

							02/28/12 3:17 PM
Configuration							DP3.SLAVE3:CU_I_3.3:1(1)
Axis	Drive Object	Component	-No.	FW version	FW card	type	HL
	CU_I_3.3:1	Control_Unit_1	1	4503000	Equal	NCU730.3	
	ALM_3.3:2	Line_Module_2	2	4503000	Equal	LM_0C0C	
	SERVO_3.3:3	Motor_Module_3	3	4503000	Equal	MM_1AXIS_0C0C	
	SERVO_3.3:4	Motor_Module_4	4	4503000	Equal	MM_2AXIS_0C0C	
	SERVO_3.3:5	Motor_Module_5	5	4503000	Equal	MM_1AXIS_0C0C	
	SERVO_3.3:6	SM_6	6	4503000	Equal	SMx module sin/cos	
	SERVO_3.3:6	Motor_Module_9	9	4503000	Equal	MM_2AXIS_0C0C	
	SERVO_3.3:6	SM_10	10	4503000	Equal	SMx module sin/cos	
	SERVO_3.3:3	SM_14	14	4503000	Equal	SMx module sin/cos	
	CU_LI_3.3_TO_3...	CU_LINK_17	17	4503000	Equal	NX15.3	
							Drive device+
							Drive device-
							Select drive dev.
							Change
							Details
							Sort
							Display options
CU_I_3.3:1.Control_Unit_1(1)							
Configuration	Topology	PROFIBUS					

The "Commissioning" → "Drive system" → "Drive unit" operating area provides the following functions under "Configuration":

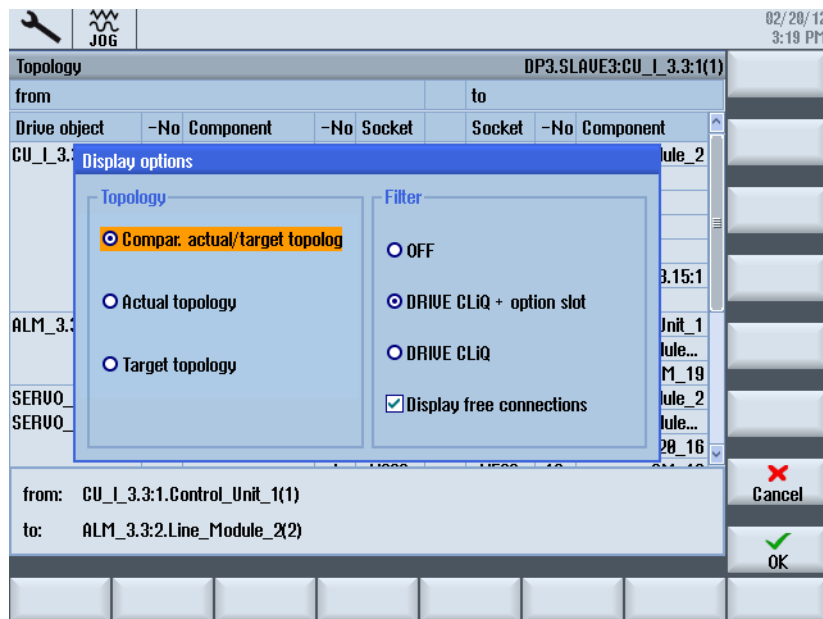
- "Configuration" > "Change >" (Page 130)
 - Change the name of the drive object
 - Change the name of the component
 - Change the comparison level
- "Configuration" > "Sort >": (Page 130)
- "Configuration" → "Display options >":





- "Topology" → "Change >"
 - Delete a drive object
 - Delete the component
 - Enable/disable drive objects
 - Drive object: Change name/number
 - Component: Change name/number
- "Topology" > "Add component >" (Page 141)

- "Topology" → "Display options >":



Example: Select filter "off" to also display the components that are not connected via DRIVE-CLiQ:



Note

No initial commissioning is required after changing the topology.

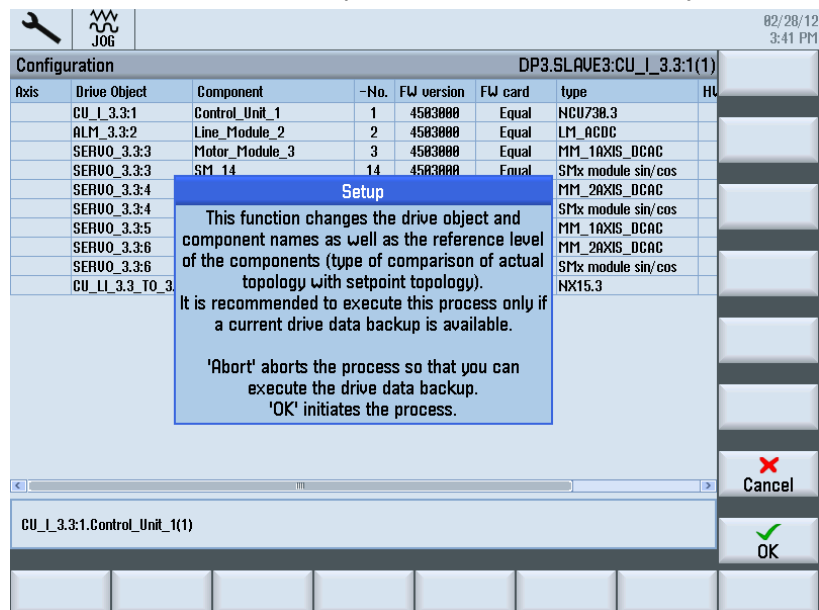
5.7.2 Modify configuration

Drive unit - Configuration "Change >"

Procedure:

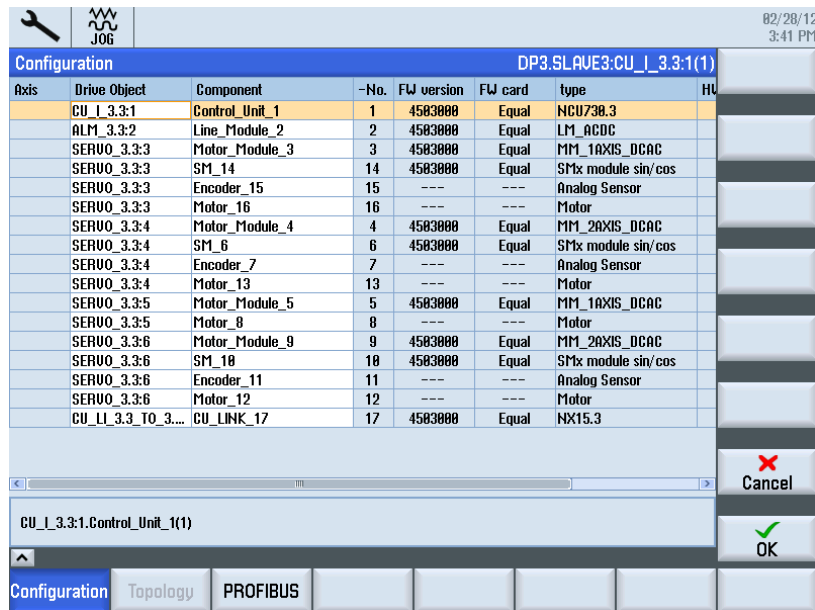
1. Press the "Change >" softkey to change the configuration.

"Cancel" can be used backup the drive data if it does not yet exist.



2. If a data backup is available, confirm with "OK".
3. Navigate with the arrow keys to the drive object / component that is to be changed.

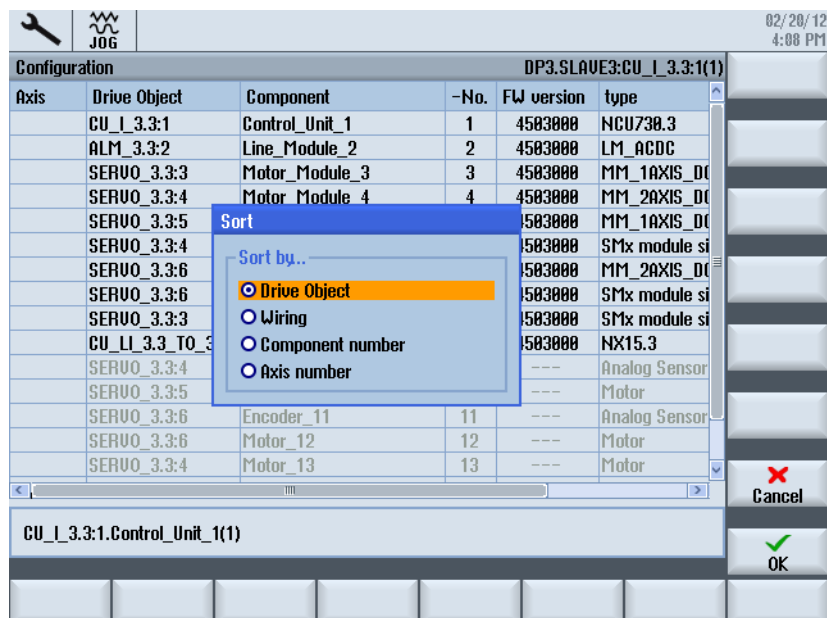
4. Press the "INSERT" key to enter the new designation.



Drive unit - Configuration "Sort >"

Procedure:

1. Press the "Sort >" softkey to open the display of the sort criteria.



2. Select one of the following sort criteria for the display from:
 - Drive object: The display is sorted according to the drive object number.
 - Wiring: The display is sorted according to wiring of the drive components in the drive system.
 - Component number: The display is sorted according to the component number.
 - Axis number: The display is sorted according to the axis number.

5.7.3 Check topology

Comparing topologies

Once you have parameterized the drive components, you can check the topology:

1. Select "Commissioning" → "Drive system" → "Drive unit" → "Topology" in the operating area.
2. Set the actual/reference topology comparison for "Display options".

The topology of individual drive components is displayed:

Drive object	-No	Component	-No	Socket	Socket	-No	Component
CU_I_3.3:1	1	Control_Unit_1	1	X100	X201	2	Line_Module_2
				X101			
				X102			
				X103			
				X104			
				X105	X100		CU_NX_3.15:1
ALM_3.3:2	2	Line_Module_2	2	X200	X201	3	Motor_Module...
				X201	X100	1	Control_Unit_1
				X202			
SERVO_3.3:3	3	Motor_Module...	3	X200	X202	4	Motor_Module...
				X201	X200	2	Line_Module_2
				X202	X500	14	SM_14
SERVO_3.3:4	4	Motor_Module...	4	X200	X201	5	Motor_Module...

from: CU_I_3.3:1.Control_Unit_1(1)
to: ALM_3.3:2.Line_Module_2(2)

3. This means you are supported during the check whether the displayed reference topology matches the actual topology of the system.

Note

You will need the component numbers in order to configure direct measuring systems manually.

See also

Drive system diagnostics (Page 123)

5.7.4 Changing topology

Drive unit - Topology "Change >"

Procedure:

1. Press the "Change >" softkey to change the topology.

"Cancel" can be used to backup the drive data if it does not yet exist.

02/28/12
3:23 PM

DP3.SLAVE3:CU_I_3.3:1(1)

Drive object	-No.	Component	-No.	Socket	Socket	-No.	Component
CU_I_3.3:1	1	Control_Unit_1	1	X100	---	X201	2
ALM_3.3:2	2						
SERVO_3.3:3	3						
SERVO_3.3:4/ SERVO_3.3:6	4/ 6						
SERVO_3.3:3	3	SM_14	14	X500	---	X202	3

from: CU_I_3.3:1.Control_Unit_1(1)
to: ALM_3.3:2.Line_Module_2(2)

Cancel
OK

2. If a data backup is available, confirm with "OK".

3. Navigate with the arrow keys to the drive object / component that is to be changed.
4. Press the "INSERT" key to enter the new designation.

In the example, the drive object is changed from "number "3" to number "30".

28.02.12 15:36

Topologie DP3.SLAVE3:CU_L_3.3:1(1)

von				nach			
Antr.objekt	-Nr.	Komponente	-Nr.	Buchse	Buchse	-Nr.	Komponente
CU_L_3.3:1	1	Control_Unit_1	1	X100	---	X201	2
				X101			
				X102			
				X103			
				X104			
				X105	---	X100	CU_NX_3.15:1
ALM_3.3:2	2	Line_Module_2	2	X200	---	X201	3
				X201	---	X100	1
				X202			
SERVO_3.3:3	30	Motor_Module_3	3	X200	---	X202	4
				X201	---	X200	2
				X202	---	X500	14
SERVO_3.3:4	4	Motor_Module_4	4	X200	---	X201	5
SERVO_3.3:6	6	Motor_Module_9	9	X201	---	X500	18
			4	X202	---	X200	3
			9	X203			
SERVO_3.3:3	30	SM_14	14	X500	---	X202	3

von: SERVO_3.3:3.Motor_Module_3(3)

nach: SERVO_3.3:4.Motor_Module_4(4)

Konfiguration Topologie PROFIBUS

Antr.obj. akt./deak.
Komponente löschen
Antr.obj. löschen
Abbruch
OK

Note

Effect

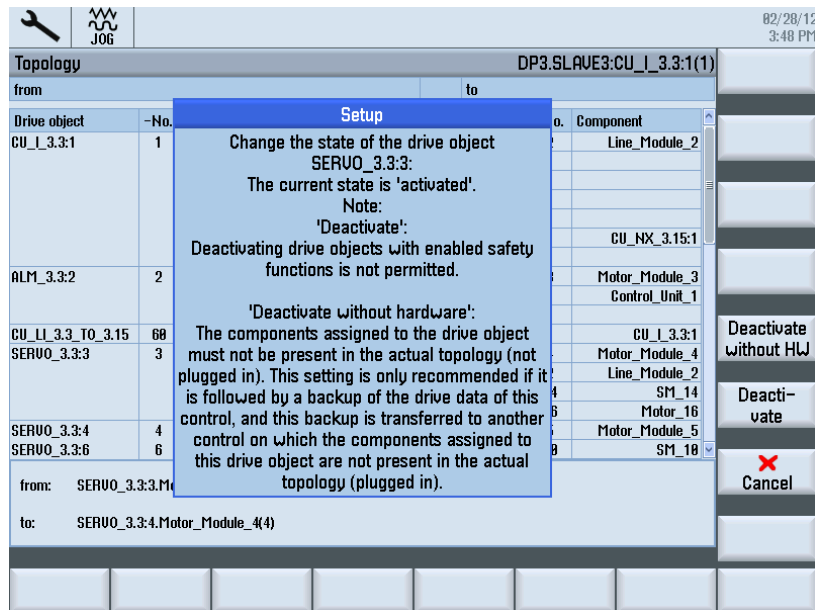
The change of the name and number is applied to the data in the reference and actual topologies of the drive software. Changing the comparison level affects the topology comparison in the drive software.

5.7.5 Activating or deactivating a drive object

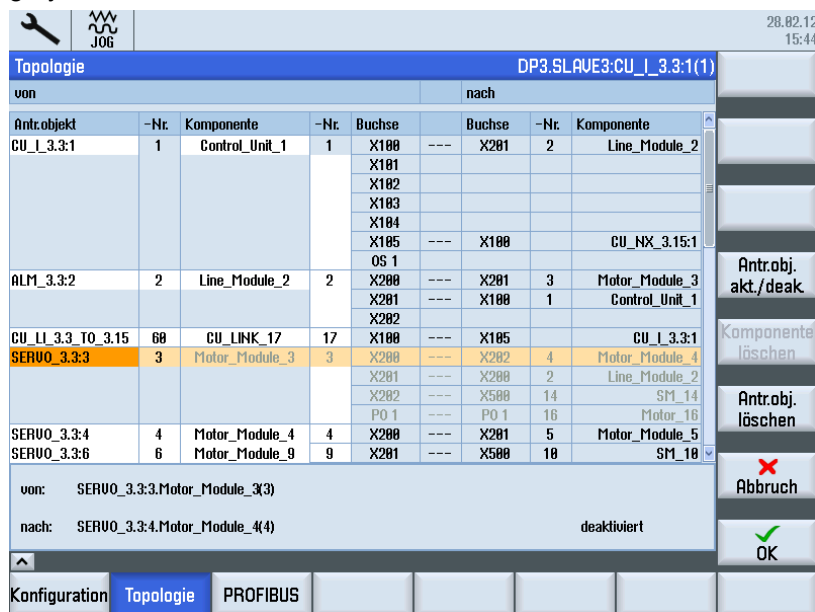
Activating/deactivating drive objects

Operating sequence:

1. Select with the arrow keys a drive object.
2. Press the "Activate/deactivate drive object" softkey



3. Follow the instructions in the information text.
4. Once successfully deactivated, the drive object and the associated components are grayed out.



5. If you want to reactivate the drive object, press the "Activate/deactivate drive object" softkey and follow the instructions in the information text.

Example series commissioning

When commissioning several machines (series) of the same type, a drive object that is not present is marked with $p0105 = 0$. This creates a commissioning archive that is transferred to the next machine.

To avoid triggering the alarm 201416, the serial number of this component must be deleted and the $p0105 = 2$ parameter of this component must be set to "Deactivate drive object and not present".

Note

General conditions for deactivating:

- If a component is deactivated, only the component with the correct serial number or none may be inserted.
 - If a component with a different serial number is inserted, this is by definition a different component. If no other component remains, it must certainly be an excess component. This component is marked as an additional component and alarm 201416 triggered.
-

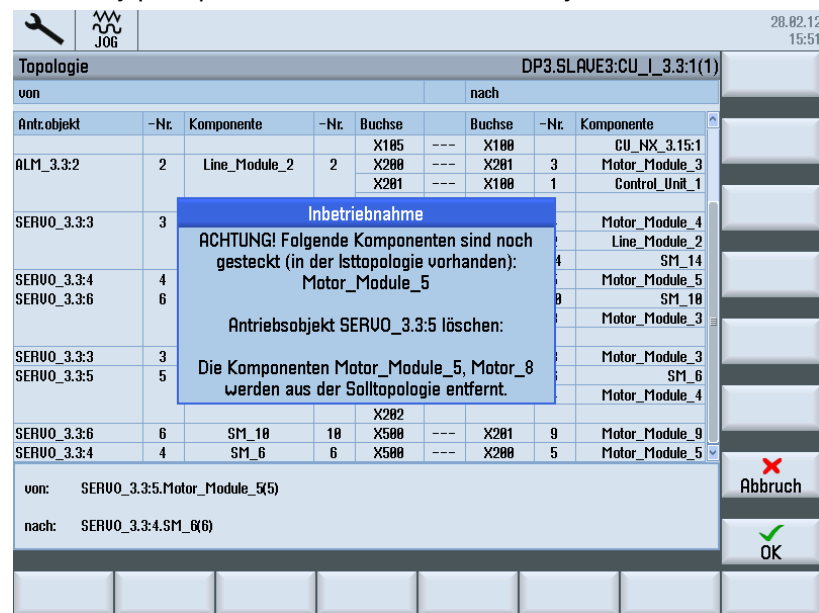
5.7.6 Deleting a drive object

Deleting a drive object

Procedure:

1. Navigate with the arrow keys to the drive object that is to be deleted.
2. Press the "Delete drive" softkey.

A security prompt follows to delete the drive object.



3. If a data backup is available, confirm with "OK".

The drive object is deleted from the reference topology.

4. To see the change in the topology, the "Actual/reference topology comparison" display options must be set:

201416 DP003.Slave003: CU_L_3.3:1 (1) Komponente 206:
Topologie: Vergleich Komponente zusätzlich in Isttopologie...

Topologie DP3.SLAVE3:CU_L_3.3:1(1)							
von				nach			
Antr.objekt	-Nr.	Komponente	-Nr.	Buchse	Buchse	-Nr.	Komponente
				X201	---	X100	1 Control_Unit_1
				X202			
SERVO_3.3:3	3	Motor_Module_3	3	X200	---	X202	4 Motor_Module_4
				X201	---	X200	2 Line_Module_2
				X202	---	X500	14 SM_14
SERVO_3.3:4	4	Motor_Module_4/	4	X200	---	X500	6 SM_6
SERVO_3.3:4	4	Motor_Module_9		X200	---	X201	206 <MM_1AXIS_DCAC>
			9	X201	---	X500	10 SM_10
			4	X202	---	X200	3 Motor_Module_3
			9	X203			
SERVO_3.3:3	3	SM_14	14	X500	---	X202	3 Motor_Module_3
SERVO_3.3:4	4	SM_6	6	X500	---	X200	4 Motor_Module_4
SERVO_3.3:6	6	SM_10	10	X500	---	X201	9 Motor_Module_9
		<MM_1AXIS_DCAC>	206	X200	---	X500	207 <SMx module sin/...
				X201	---	X200	4 Motor_Module_4
				X202			
		<SMx module sin/...	207	X500	---	X200	206 <MM_1AXIS_DCAC>
Istzustand							
von: SERVO_3.3:4.Motor_Module_4(4)							
nach: nicht zugeordnet.<MM_1AXIS_DCAC>(206)							

Konfiguration Topologie PROFIBUS

Antriebs-
gerät+
Antriebs-
gerät-
Antr.ger.
auswählen
Ändern
Antr.ger.
konfigur.
Komponente
hinzufügen
Anzeige-
optionen

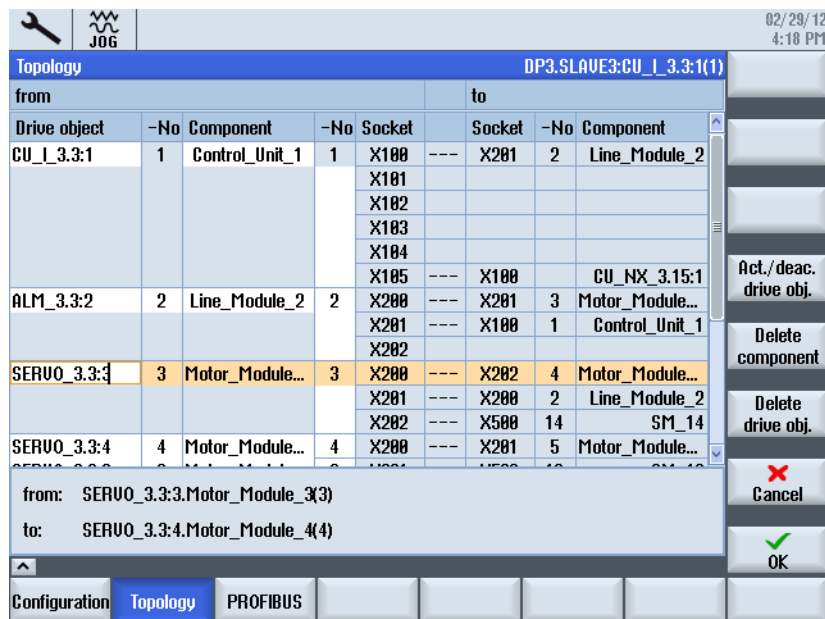
Result: The module can now be removed.

5.7.7 Delete the component

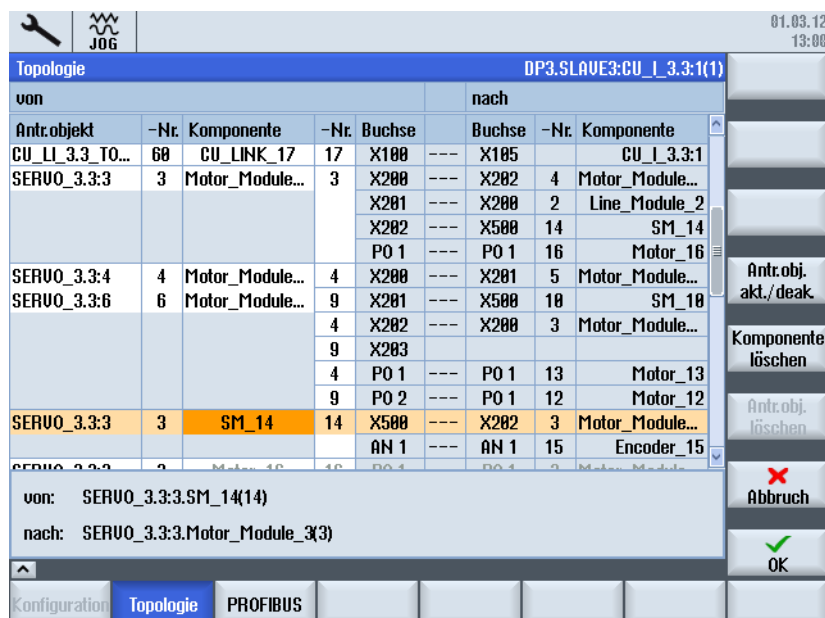
Delete the component

Procedure:

1. You are in the "Topology" dialog and have selected the "Change" mode:



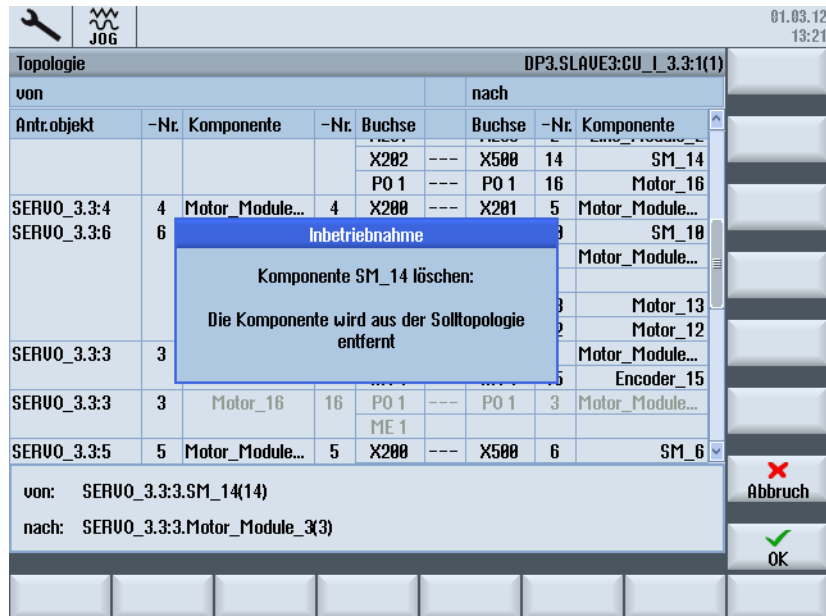
2. Navigate with the arrow keys to the component to be deleted.



If you select a component, the "Delete component" softkey is active.

- Press the "Delete component" softkey, in this example: Sensor SM_14 (sin/cos).

A security prompt follows to delete the component.



- If you are sure, confirm with "OK". The component is deleted from the reference topology.



If the component is not yet available in the actual topology, i.e. still connected, an alarm is output and the component highlighted in red. To see the change in the topology, the "Actual/reference topology comparison" display options must be set.

- Remove the module.

5.7.8 Adding components

Adding components

If you connect a new component (e.g. SMC20) via DRIVE-CLiQ to the drive system, SINAMICS detects the change in the actual topology and displays the actual/reference topology difference. The new component must then be configured and assigned to a drive object (Motor Module) using the drive wizard.

Operating sequence:

1. Select "Commissioning" → "Drive system" → "Drive unit" → "Topology" in the operating area. In the "Topology" dialog, start at an actual state.

The component has not been connected yet. Connect a new DRIVE-CLiQ component (e.g. SMC20) to a Motor Module.

Note

Only plug in (connect) components when the drive unit is switched off.

Topologie von				nach			
Antr.objekt	-Nr.	Komponente	-Nr.	Buchse	Buchse	-Nr.	Komponente
ALM_3.3:2	2	Line_Module_2	2	X200	---	X201	3 Motor_Module...
				X201	---	X100	1 Control_Unit_1
				X202			
SERVO_3.3:3	3	Motor_Module...	3	X200	---	X202	4 Motor_Module...
				X201	---	X200	2 Line_Module_2
				X202	---	X500	210 <SMx module ...
SERVO_3.3:4/ SERVO_3.3:6	4/ 6	Motor_Module...	4/ 6	X200	---	X201	5 Motor_Module...
				X201	---	X500	10 SM_10
				X202	---	X200	3 Motor_Module...
SERVO_3.3:5	5	Motor_Module...	5	X200	---	X500	6 SM_6
				X201	---	X200	4 Motor_Module...

von: SERVO_3.3:3.Motor_Module_3(3)
nach: nicht zugeordnet.<SMx module sin/cos>(210) Istzustand

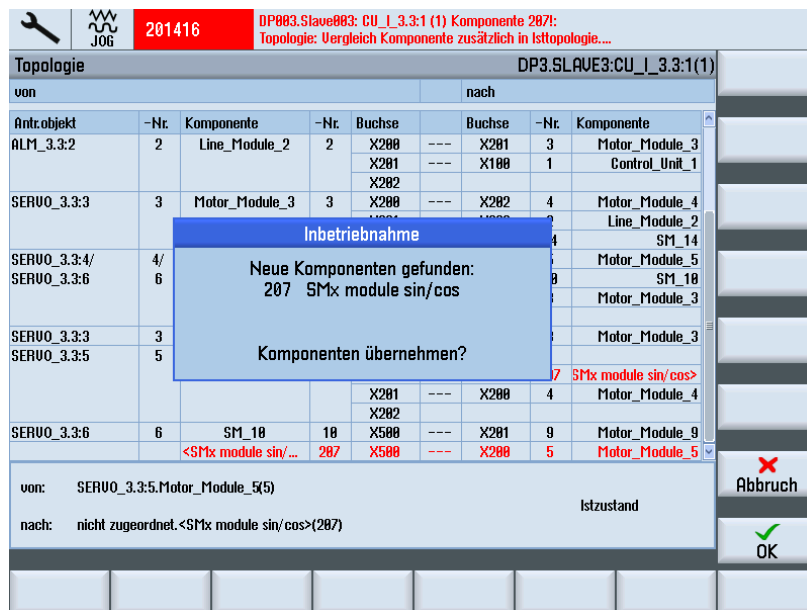
Konfiguration Topologie PROFIBUS

SINAMICS recognizes the change in the actual topology and displays the actual/reference topology difference:

- GRAY: Desired state, drive object/component not plugged in and/or deactivated in the drive system. Use the cursor keys to select the required line. The state is indicated in the bottom part of the window.
- RED: Actual state, drive object/component present in the actual topology.

New components that have not yet been commissioned have a component number > "200"; in this example, the number "210".

2. Navigate with the arrow keys to the component to be deleted. Press "Add component >".



The system recognizes the new component and outputs a message.

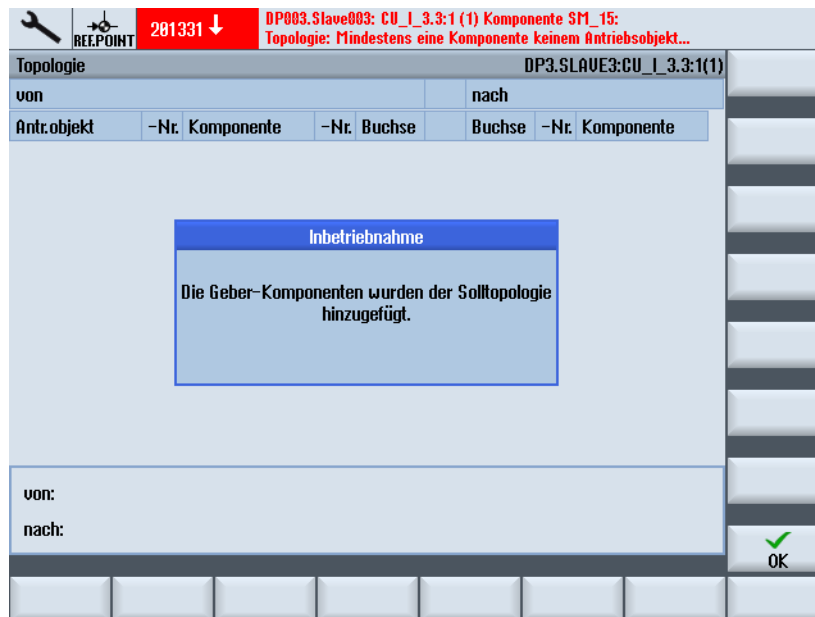
3. Press "OK" as confirmation to configure and accept this component.

Determining the device configuration may take several minutes. Depending on the device configuration, you will be prompted to perform further actions or to cancel:

To match the cyclic data traffic between the NCK and SINAMICS to the configuration of the SINAMICS, an NCK and drive reset should be performed.

Should an NCK and drive system reset be performed?

4. Press "OK" to confirm that an NCK and drive system reset should be performed. The following message will then appear:



The unit configuration is finished. The component has been accepted.

5. Press "OK" to include the component in the topology again although it is not yet assigned to any drive:
- Select "Drive unit" to open the drive wizard. Select the drive and assign the new encoder in the encoder configuration (Page 85) to the drive.
 - Press "OK" to assign this component to the drive later.

5.7.9 Replacing SINAMICS S120 components

Preconditions

There are two procedures for replacing components:

1. Replacing an existing Motor Module with a more powerful Motor Module.
2. Replacing SMI or SMx motor components.

The following preconditions are satisfied:

- The motor modules are of the same type.
- The serial number is different: ⇒ No further configuration is needed.
- The order number (MLFB) differs, for example, 9 A instead of 5 A.

Replacing an existing Motor Module with a more powerful Motor Module

Operating sequence:

Note

Do not make a permanent change in the drive system.

Before you replace the DRIVE-CLiQ component, change the comparison level.

1. Select the "Commissioning" → "Machine data" → "Control unit MD" dialog.
2. Change parameters p9907 (component number) and p9908 (comparison level of a component).
3. Save the changed drive data before switching off (power OFF).
4. Switch off the drive system: Power OFF.
5. Replace the component with a more powerful Motor Module.
6. Switch on the drive system: Power ON.
7. No further configuration is required because the Motor Module has been replaced in the switched-off status of the system. The new configuration and topology data is exported and the display refreshed.

Permanently replacing a Motor Module

Operating sequence:

1. Select the "Commissioning" → "Machine data" → "Control unit MD" dialog.
2. Set the "Device configuration" parameter to control unit: p0009 = 1
3. Transfer the new component: Control Unit: p9905 = 2
4. Wait until p9905 = 0 is automatically set again.
5. Set the "Device configuration" parameter to control unit: p0009 = 0
6. Save "All": set p977 = 1.
7. Ensure that you wait until p977 is automatically set to "0" again. This can take as long as 40 seconds.

The replacement of a single SINAMICS component is automatically acknowledged by the system.

Replacing SMI or SMx motor components

Note

The new SMI/SMx motor component must not yet be inserted!

Operating sequence:

1. You have removed the previous SMI or SMx motor component.

This motor component is missing in the actual topology. SINAMICS indicates this in the form of a topology error alarm.

The "Commissioning" → "Drive system" → "Drive units" → "Topology" dialog shows the previous motor component to be replaced **"gray"**, i.e. present only in the reference topology.
2. In the "Commissioning" → "Drive system" → "Drive units" → "Topology" → "Change..." dialog, remove the SMI/SMx motor component awaiting replacement from the reference topology using the "Delete component" (Page 139) dialog.

Note

Save the changed drive data before switching off (power OFF).

3. Switch the drive system off and on (power OFF→ON).
4. In the "Commissioning" → "Drive system" → "Drive units" → "Topology" dialog, check whether the SMI/SMx motor component has been removed from the reference topology:
 - The alarm topology error is no longer pending.
 - The "Commissioning" → "Drive system" → "Drive units" → "Topology" dialog no longer shows any differences.
5. Switch off the drive system.
6. Plug in the new SMI/SMx motor component.
7. Switch on the drive system.
8. Add the new SMI/SMx motor component using the "Commissioning" → "Drive system" → "Drive units" → "Topology" → "Add component" (Page 141) dialog to the reference topology.
9. Assign the added SMI/SMx motor component via the "Commissioning" → "Drive system" → "Drives" (Page 85) drive wizard.

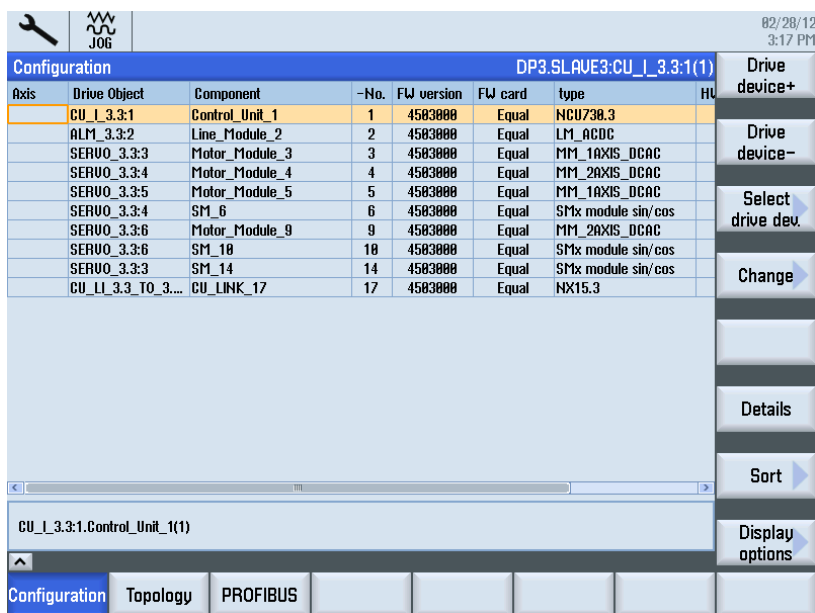
5.8 Tips for commissioning the SINAMICS drives

5.8.1 Firmware version display of drive components

Firmware version of the drive components

The versions of the drive components are output from "Commissioning" → "Drive system" → "Drive units" → Configuration" in the "FW version" column.

Example: 4503000 ⇒ Firmware version: 04.50.30.00



The screenshot shows the 'Configuration' window for a drive system. The title bar indicates 'DP3.SLAVE3:CU_I_3.3:1(1)'. The table lists various drive components with their respective firmware versions. The 'FW version' column shows values like 4503000, which corresponds to the example given in the text.

Axis	Drive Object	Component	-No.	FW version	FW card	type	HW
	CU_I_3.3:1	Control_Unit_1	1	4503000	Equal	NCU730.3	
	ALM_3.3:2	Line_Module_2	2	4503000	Equal	LM_0C0C	
	SERVO_3.3:3	Motor_Module_3	3	4503000	Equal	MM_1AXIS_DCAC	
	SERVO_3.3:4	Motor_Module_4	4	4503000	Equal	MM_2AXIS_DCAC	
	SERVO_3.3:5	Motor_Module_5	5	4503000	Equal	MM_1AXIS_DCAC	
	SERVO_3.3:6	SM_6	6	4503000	Equal	SMx module sin/cos	
	SERVO_3.3:6	Motor_Module_9	9	4503000	Equal	MM_2AXIS_DCAC	
	SERVO_3.3:6	SM_10	10	4503000	Equal	SMx module sin/cos	
	SERVO_3.3:3	SM_14	14	4503000	Equal	SMx module sin/cos	
	CU_LL_3.3_TO_3...	CU_LINK_17	17	4503000	Equal	NX15.3	

Below the table, there are buttons for 'Drive device+', 'Drive device-', 'Select drive dev.', 'Change', 'Details', 'Sort', and 'Display options'. At the bottom, there are tabs for 'Configuration', 'Topology', and 'PROFIBUS'.

Figure 5-5 "Drive units" - "Configuration"

Using certain parameters from individual drive components, it is also possible to view the relevant firmware version for:

- SINAMICS S120 system software in parameter r0018
- Firmware version of the drive components in parameter r0975[2,10]
- Firmware version of the Sensor Module in parameter r0148[0...2]

System software SINAMICS S120

The version of the SINAMICS S120 software available in the system can be found in the parameter r0018 for the Control Unit machine data:

Example: r0018 = 45030000 ⇒ System software: 04.50.30.00

Firmware version of the drive components

The firmware version of all individual components can be individually fetched from the parameters r975[2] and r975[10] for each drive component (NCU, ALM, power section).

Example:

r0975[2] = 450, r0975[10] = 3000 \Rightarrow Firmware version: 04.50.30.00

Firmware version of all Sensor Modules

The firmware version of all Sensor Modules can be fetched from the parameter r0148[0...2] on the associated Motor Module.

Example: r0148[0] = 45030000 \Rightarrow Firmware version: 04.50.30.00 of the connected Sensor Module.

5.8.2 Check the power system data of the infeed

Introduction

The power supply data settings must be checked and possibly set in SINAMICS during commissioning.

Checking and setting the power supply data

The "Power supply data" softkey is active in the "Commissioning" \rightarrow "Drive units" \rightarrow "Infeed" operating area if the infeed has already been commissioned and the data has been saved in non-volatile memory:

DP883.Slave883: ALM_3.3:2 (2) Component Line_Module_2:
Infeed: Temperature in the line filter permanently too high.

... \Infeeds \Configuration-Power data DP3.SLAVE3:ALM_3.3:2 (2)

☒ Line/DC link identification on first Power ON
(The determined values are saved powerfail-proof)

Notice:
If the DC link capacity of the drive group is subsequently modified (devices removed/added), a new identification will have to be performed.

Device supply voltage: 400 U
Line rated frequency: 50-60 Hz

Note:
With a device supply voltage of over 415U, the Active Line Module is operated as open-loop control supply/feedback

Previous step
Cancel
Next step

Config-uration Infeed parameter

The following supply system data is configured:

- When the checkbox is selected, the supply system / DC-link identification is activated once the infeed pulse has been enabled (p3410). The infeed then switches to operational mode.

Note

DC-link identification

If the line supply environment changes or the components on the intermediate circuit change (e.g. after setting up the equipment at the customer site or after expanding the drive group), the checkbox must be set again: Hence the "Supply system data" softkey in the overview in order to restart the supply system / DC-link circuit identification.

If P3410 = 5 is saved in the commissioning archive then the supply system / DC-link identification starts automatically once the drive data is input into the archive.

Only then can it be guaranteed that the infeed operates with the optimum controller settings.

- Enter the device connection voltage: This is the basis for monitoring the supply voltage (p0281 - p0283), whereby an alarm is triggered in the case of an overshoot or undershoot. (Alarm threshold and shutdown threshold). The actual supply voltage is determined automatically and the adjustment is made based on this value.
- The actual network frequency for the infeed is determined automatically.

Set in parameter p0284, p0285 a threshold from which an alarm is triggered (default setting of the monitoring: 45 Hz to 65 Hz).

5.8.3 Identifying the infeed automatically or manually

Introduction

The control optimization in the ALM is also performed with the identification of the ALM. Here, the inductance and capacity of the DC link are determined and the optimum control data determined for the set-up converter.

Identification can only be performed after the controller and the drive have been put into operation.

Procedure for the automatic identification of the ALM

The identification of the ALM is performed automatically by the system in the current SINAMICS versions as soon as the first drive has been commissioned and the X122.1 enable terminal activated. This automatically starts an internal optimization sequence that takes approx. 20 seconds to complete.

During this optimization sequence, enable terminal X122.1 should not be deactivated; otherwise the optimization would be aborted. If optimization is aborted, identification may be carried out manually at a later stage by the user.

Procedure for the manual identification of the ALM

The identification of the ALM is performed as follows:

1. Disconnect release (AUS1) ALM (X122.1) by the commissioning engineer.
2. Select machine data for the infeed (ALM) in the "Commissioning" > "Machine data" > "Infeed MD" menu.
3. Initiate identification on the ALM: p3410 = 5.
4. Connect ALM enable (the enable must remain pending during the execution of the first step of the identification).
5. The ALM controller data is reset automatically and power supply identification starts.
6. After a successful identification, p3410 is automatically set to 0 and the values for the controller data of the ALM are saved automatically. Check: p3402 = 9 (Release has to remain during the execution of this step of the identification!).
7. Disconnect ALM enable (X122.1) by the commissioning engineer.
8. The optimized infeed data is saved automatically. The data does not need to be saved manually (p0977 = 1).

5.8.4 Topology rules for SMC40

Use of the SMC40

The SMC40 Sensor Module Cabinet-Mounted is used to convert encoder signals from absolute encoders with EnDat 2.2 to DRIVE-CLiQ. Two encoder systems with EnDat 2.2 can be connected to the SMC40. Their signals are converted independent of each other on two DRIVE-CLiQ encoder signals.

Connection conditions

To ensure that the SMC40 Sensor Module Cabinet-Mounted is integrated into the topology during the initial commissioning, you must absolutely observe the following rules:

- Connect at least one of the DRIVE-CLiQ interfaces X500/1 or X500/2 on the SMC40 using DRIVE-CLiQ.
- Connect one EnDat encoder to the corresponding encoder interface X520/1 (to X500/1) or X520/2 (to X500/2).
- Operate the SMC40 only in a star topology. The DRIVE-CLiQ X500/1 and X500/2 sockets cannot be used for a series connection.

NOTICE

Display in the "Topology" dialog

The SMC40 can be integrated in the actual topology only when the DRIVE-CLiQ X500/x interfaces and the corresponding encoder interfaces X520/x are assigned.

Without a connected encoder, it is also not possible to subsequently integrate the SMC40 in the topology.

5.8.5 Drive (SERVO) parameter RESET, individual

Operating sequence

Note

Not just the motor and encoder data are reset. All the configured BICO logic operations (enable signals, probe signals) and message frame type are also deleted.

The factory setting (parameter RESET) may be set for each drive (SERVO) individually:

1. Set the factory settings on the selected drive: p0010 = 30
2. Activate the factory settings on this drive: p0970 = 1
3. Device automatically carries out RESET of all parameters on this drive.
4. Save drive-specific: Set p0971 = 1
OR:
Save "All": Set p0977 = 1.
5. Wait until p0977/p0971 is automatically set to "0" again; this can take up to 40 seconds.

5.8.6 Drive-object assignment for PROFIBUS connection

Introduction

PROFIBUS telegrams (internal PROFIBUS, HW Config) are used to specify the process data to be exchanged between the NC and the drives. The sequence of the drive objects (configurable/configured using HW Config) involved in PROFIBUS process-data exchange is defined via a drive-object list.

List of drive objects

You usually configure eight drive objects: If you insert a drive object in HW Config, this is the default setting.

The drive objects have drive-object numbers and are entered in p0978[0...9] as a list of drive objects:

p0978[0] = 3	Motor Module 1
p0978[1] = 4	Motor Module 2
p0978[2] = 5	Motor Module 3
p0978[3] = 6	Motor Module 4
p0978[4] = 7	Motor Module 5
p0978[5] = 8	Motor Module 6
p0978[6] = 1	Control Unit
p0978[7] = 2	Infeed (ALM)
p0978[8] = 0	
p0978[n] = 0	

PROFIBUS telegram 370 for the infeed (ALM) is not supported by SINUMERIK. However, according to the SINAMICS rule, all DO from parameter p0101 have to be assigned in parameter p0978. For this reason, the DO number of the infeed should be entered in index **9**.

Note

The list of DO involved in process-data exchange is completed by entering the value "0".

The list of drive objects is already preassigned in the following sequence by the system upon initializing the drive (acceptance of topology): ALM, 1st Motor Module ... n, CU; e.g. 2-3-4-5-1.

Components that do not communicate via PROFIBUS automatically have "255" preassigned to them.

Drive-object numbers

The drive-object numbers (DO numbers) can be viewed under "Commissioning > Machine data > Control Unit MD/Infeed MD/Drive MD" in the component name line. An example of a Control Unit name might be: "DP3.Slave3:CU_003 (1)". The DO number appears inside the brackets "(...)".

Assigning drive objects

Using an example of an SINAMICS S120 component structure, the following table illustrates the drive object assignment for the drive parameters:

- One Control Unit (CU)
- One Active Line Module (ALM)
- Three Motor Modules

Assignment p0978[0...9] for supply **with** DRIVE-CLiQ connection:

Component	Index p0978	List of drive objects
1st Motor Module	0	3
2nd Motor Module	1	4
3rd Motor Module	2	5
not found	3	255 ¹⁾
not found	4	255 ¹⁾
not found	5	255 ¹⁾
CU	6	1
ALM, only if protocol 370 is available	7	255 ¹⁾
not found	8	0 ²⁾
ALM (Standard for SINUMERIK)	9	2

1) Not active

2) End of exchange of PZD

The following table describes the assignment of the drive objects in p0978[0...9] for an **infeed without DRIVE-CLiQ connection**. This assignment is also done for a drive group with NX module.

Assignment of p0978[0...9] for infeed **without** DRIVE-CLiQ connection:

Component	Index p0978	List of drive objects
1st Motor Module	0	2
2nd Motor Module	1	3
3rd Motor Module	2	4
not found	3	255 ¹⁾
not found	4	255 ¹⁾
not found	5	255 ¹⁾
CU	6	1
ALM, only if protocol 370 is available	7	255 ¹⁾
not found	8	0 ²⁾
not found	9	0

1) Not active

2) End of exchange of PZD

See also

Configuring the I/O address and telegram (Page 159)

5.8.7 Adjusting speed and brake behavior

Introduction

You can adjust the following parameters in the "Commissioning" → "Machine data" → "Drive MD" operating area for the purpose of drive optimization.

Speed adjustment

- Spindle drive:
p0500 = 102, speed setpoint in p0322 corresponds to setpoint 4000 0000hex
- Feed drive:
p0500 = 101, speed setpoint in p0311 corresponds to setpoint 4000 0000hex

The speed setpoint can be diagnosed in the relevant drive in r2050[1+2] and r2060[1].

Brake behavior OFF3

Depending on the requirements, the brake behavior for each drive can be adjusted to the signal 2nd OFF3.

Default setting p1135 = 0 brake with maximum current.

Using drive-specific parameterization, a flatter braking ramp can be set with the parameters p1135, p1136, p1137 .

Maximum braking ramp setting: 600 seconds.

Communication between the NC and the drive

6.1 Overview of NC and drive communication

What will be configured next?

The initial commissioning of the PLC and SINAMICS drives is completed.

The machine data that communicates with the drive is:

- General machine data

General machine data required for communication with the drive via PROFIBUS that has been preset with default values. These values can be taken over during the initial commissioning:

- The telegram type for transfer
- The logical addresses for the PLC

- Axis-specific machine data

The axis component for transfer of the setpoints and actual values for the relevant axis, is set in the axis machine data.

Assignment of machine data

Using the example of a SINAMICS S120 module structure (one NCU, one ALM, three Motor Modules (MM)), the following table illustrates the assignment of the machine data for input address/output address/telegram/setpoint/actual value.

6.1 Overview of NC and drive communication

SINAMICS S120	STEP 7 (HW Config) DP slave properties		General machine data			Axis machine data ²⁾	
	Message frame type and length	I/O address ¹⁾	MD13120[0] I/O address ¹⁾	MD13050 [0...5] I/O address ¹⁾	MD13060 [0...5] message frame type	MD30110/ MD30220 setpoint / actual value assignment	MD30130 Type of output Setpoint
MM1	136 - PZD-11/19	4100		4100	136	1	1
MM2	136 - PZD-11/19	4140		4140	136	2	1
MM3	136 - PZD-11/19	4180		4180	136	3	1
Not available	136 - PZD-11/19	4220		4220	136	--	0
Not available	136 - PZD-11/19	4260		4260	136	--	0
Not available	136 - PZD-11/19	4300		4300	136	--	0
CU	391 - PZD-3/7	6500	6500				
ALM	370 - PZD-1/1	6514					

¹⁾ Do not change preassignment.

²⁾ The axis-specific machine data for the configuration of the setpoints and actual values is pre-assigned using the "Assign axis" function.

6.2 Configuring the communication to the drive

Default settings

The telegram length in the hardware configuration is preassigned with the associated I/O addresses. This pre-assignment for SINAMICS corresponds to the following telegrams with the maximum possible telegram length:

- Telegram 136: for the axes
- Telegram 391: for the NCU
- Telegram 370: for the ALM

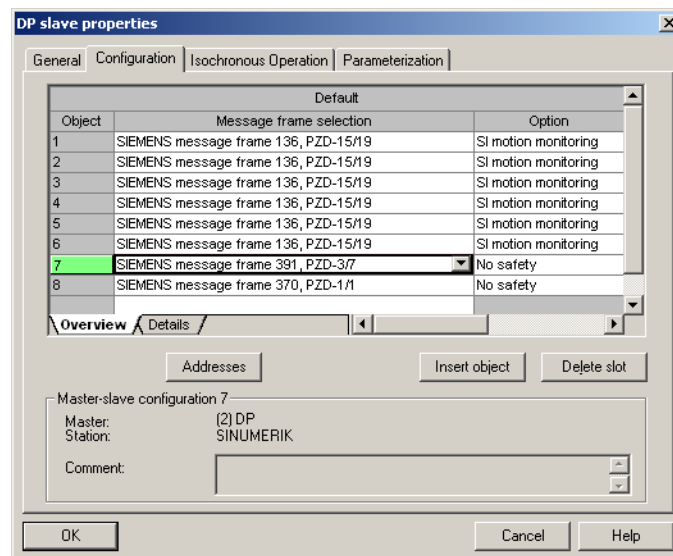
This ensures that all telegrams can be supplied without change.

Operating sequence for telegram length and I/O addresses

Procedure:

1. To view this configuration, click in the HW Config on the module "SINAMICS Integrated" and select "Object properties", using the <right mouse button>.
2. Select the "Configuration" tab and select the "Overview" tab to display the lengths of the preassigned telegrams.

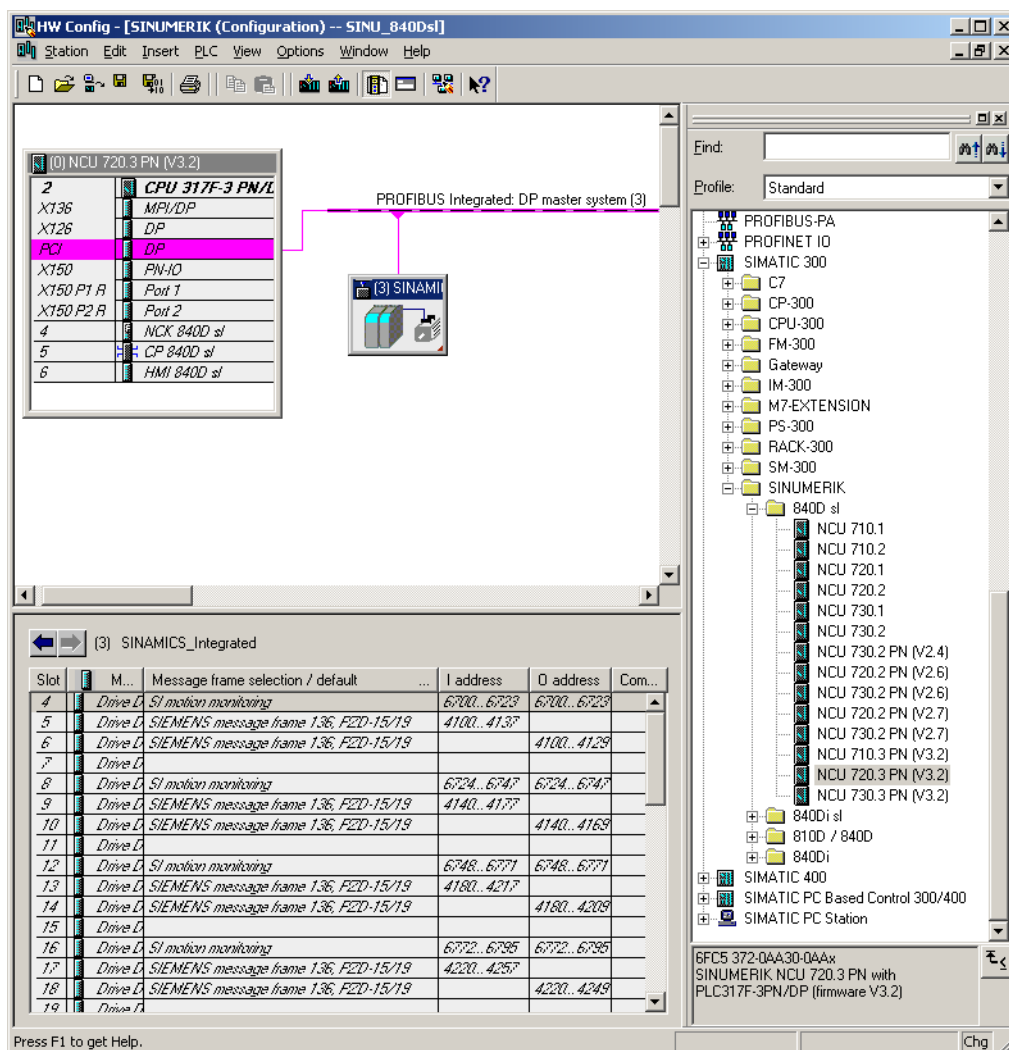
The figure shows the default setting of the telegrams for six axes:



3. Click "OK" to close the dialog.

Example

You can view the address areas in the station window in the detail view by clicking "SINAMICS Integrated". Here, for example, address 4100 corresponds to the address entered in MD13050 \$MN_DRIVE-LOGIC_ADRESS[0]. The addresses have a gap of 40 bytes. The following example shows the assignment of the pre-assignment of the I/O addresses of the PLC configuration to MD13050 \$MN_DRIVE-LOGIC_ADRESS[0 ... 5]:



Default setting in the NCK:

MD13050 \$MN_DRIVE-LOGIC_ADRESS[0] = 4100

MD13050 \$MN_DRIVE-LOGIC_ADRESS[1] = 4140

MD13050 \$MN_DRIVE-LOGIC_ADRESS[2] = 4180

MD13050 \$MN_DRIVE-LOGIC_ADRESS[3] = 4220

For the 1st axis

For the 2nd axis

For the 3rd axis

For the 4th axis ... etc.

Figure 6-1 Telegram lengths and I/O addresses

6.3 Configuring the I/O address and telegram

PROFIBUS connection

The following general machine data is also set by default for the PROFIBUS connection of the axes to the drive:

- MD13050 \$MN_DRIVE_LOGIC_ADDRESS (axis address)
- MD13060 \$MN_DRIVE_TELEGRAM_TYPE (telegram type)
- MD13120 \$MN_CONTROL_UNIT_LOGIC_ADDRESS (CU address)

The connection of the relevant axes to the drive via PROFIBUS is displayed in the "Commissioning" → "Drive system" → "Drive units" → "PROFIBUS" operating area.

Example for the connection of relevant axis to the drive:

NC-axis	NC Telegram type	I-/O-addr.	Slot	SINAMICS-drive object	SINAMICS-telegram type
AX1:X1	SIEMENS 136	6700	4	SERVO_3.3:3(3)	SIEMENS 136
		6700	4		
		4100	5		
		4100	6		
AX2:Y1	--	6724	8	(255)	--
		6724	8		
		4140	9		
		4140	10		
AX3:Z1	--	6748	12	(255)	--
		6748	12		
		4180	13		
		4180	14		
AX4:A1	--	6772	16	(255)	--
		6772	16		
		4220	17		
		4220	18		
AX5:B1	--	6796	20	(255)	--
		6796	20		

Figure 6-2 Drive units - PROFIBUS

6.3 Configuring the I/O address and telegram

To change the assignment, press the "Change >" softkey. Then use the arrow softkeys for the new assignment:

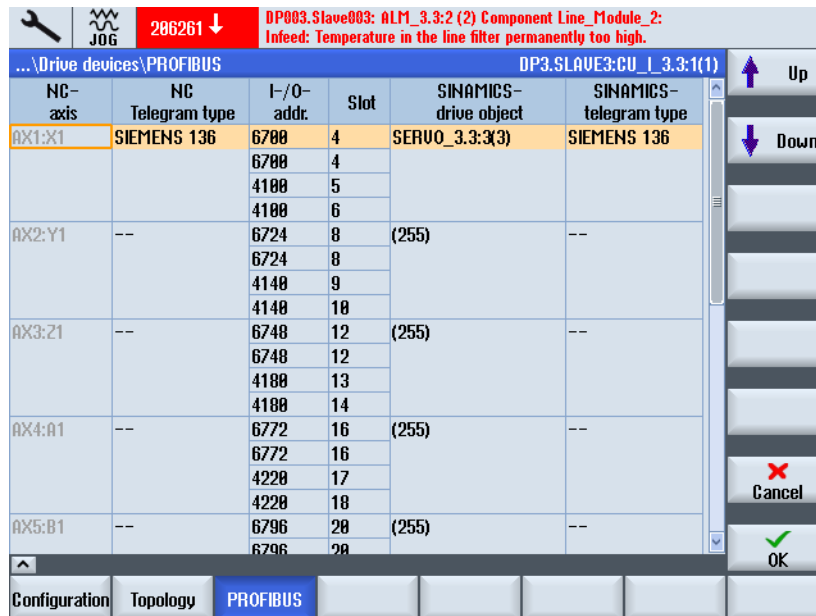


Figure 6-3 Change assignment

Note

Communication with the drive

To ensure the communication with the drive, the I/O addresses and telegram types set here must match the settings in the STEP 7 hardware configuration.

6.4 Configuring the setpoint / actual value

Introduction

The axis component for transfer of the setpoints and actual values for the relevant axis, is set in the axis machine data. The following axis machine data must be adapted for each axis:

- MD30110 \$MA_CTRLOUT_MODULE_NR (setpoint channel)
- MD30220 \$MA_ENC_MODUL_NR (actual value channel)
- MD30130 \$MA_CTRLOUT_TYPE (type of output setpoint)
- MD30240 \$MA_ENC_TYPE (acquisition of actual value)

The axis/machine data can be automatically adapted using the "Assign axis" function or directly using the "Axis MD" function.

Assigning setpoints and actual values

Procedure:

1. Select the "Axis MD" softkey in the "Commissioning > Machine data" in the operating area.
2. Select the corresponding axis using "Axis+".
3. For the setpoint channel, search for MD30110 \$MA_CTRLOUT_MODULE_NR.
4. Enter the drive number.
5. For the actual value channel, search for MD30220 \$MA_ENC_MODUL_NR.
6. Enter the drive number.
7. For the output setpoint, search for MD30130 \$MA_CTRLOUT_TYPE.
8. Enter "1".
9. For the actual-value acquisition, search for MD30240 \$MA_ENC_TYPE.
10. Enter "1" for incremental encoder or "4" for absolute value encoder.
11. Select the next axis in each case with **Axis+** and continue with Step 3 for the next drive.

6.5 Assigning axes

Operating sequence in the "Assign axis" menu

Procedure:

1. Select the "Commissioning" > "Drive system" > "Drives" menu.

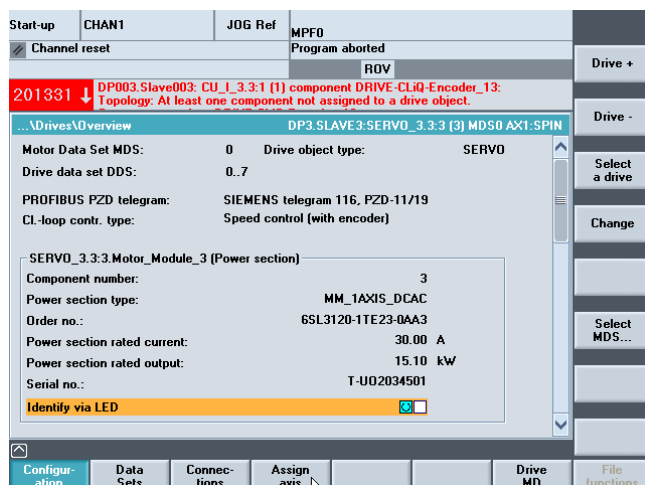


Figure 6-4 "Commissioning" > "Drive system" > "Drives" menu

Note

The "Assign axis" function can also be activated in the "Commissioning > Drive system" function using the vertical softkey bar. You must have selected a servo drive before doing this.

2. Press the "Assign axis" horizontal softkey

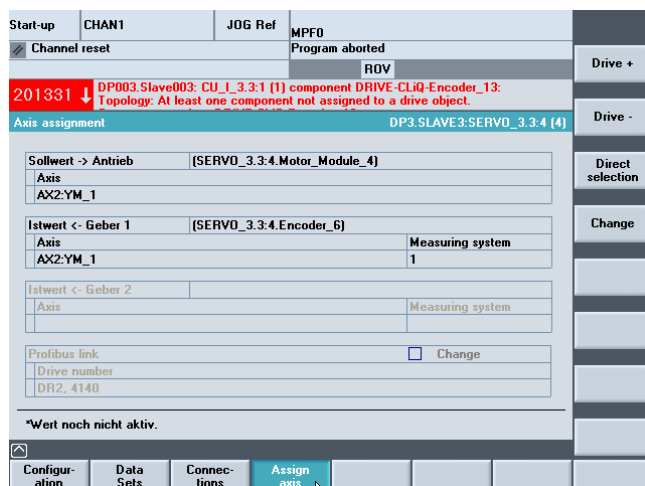


Figure 6-5 Assignment of setpoints and actual values for axes to drive

3. Use "Drive +"/"Drive -"/"Direct selection" to select the corresponding servo.

4. Press "Change".

Start-up	CHAN1	JOG Ref	MPF0
<input checked="" type="checkbox"/> Channel reset		Program aborted	
		ROV	
201331 ↓ DP003.Slave003: CU_L_3.3:1 (1) component DRIVE-CLIQ-Encoder_13: Topology: At least one component not assigned to a drive object.			
Axis assignment		DP3.SLAVE3:SERVO_3.3:4 (4)	
Sollwert -> Antrieb (SERVO_3.3:4.Motor_Module_4)			
Axis			
AX2:YM_1, DP3.SLAVE3:SERVO_3.3:4, <aktiv>			
AX3:			
AX1:SPIN, DP3.SLAVE3:SERVO_3.3:3			
AX2:YM_1, DP3.SLAVE3:SERVO_3.3:4, <aktiv>			
AX3:YM_2, DP15.SLAVE15:SERVO_3.15:2			
AX4:AM_1, DP15.SLAVE15:SERVO_3.15:3			
AX5:BB1, DP15.SLAVE15:SERVO_3.15:4			
AX6:CC1, DP15.SLAVE15:SERVO_3.15:5			
Profibus link		<input type="checkbox"/> Change	
Drive number			
DR2, 4140			
*Wert noch nicht aktiv.			
		Abort	
		Accept	

Figure 6-6 "Assign axis" > "Change" menu

5. Use the cursor keys to select the selection boxes for the setpoint or actual value.
6. Use the <INPUT> key to open the selection box.
7. Use the cursor keys to select the component.
8. Press "Transfer".

6.6 Ending the communications commissioning

Machine installed

You have commissioned the following components:

- PLC
- SINAMICS drives
- NC ↔ PLC communication

The commissioning is completed. You can now traverse the axes.

The next "NC commissioning" section describes the parameterization of the NC with regard to the connected machine by setting system variables.

Commissioning the NC

7.1 Machine and setting data

Parameterizing the NCK

Adaptation of the control at the machine is performed using the machine and setting data.

- The machine data (MD) is divided into the following areas:
 - General machine data
 - Channel-specific machine data
 - Axis-specific machine data
 - Machine data for control unit
 - Machine data for infeed
 - Machine data for drives
- The setting data (SD) is divided into the following areas:
 - General setting data
 - Channel-specific setting data
 - Axis-specific setting data

The following table provides an overview of the machine data and setting data areas:

Range	Name
from 9000 to 9999	Display machine data
from 10000 to 18999	General NC machine data
from 19000 to 19999	Reserved
from 20000 to 28999	Channel-specific machine data
from 29000 to 29999	Reserved
from 30000 to 38999	Axis-specific machine data
from 39000 to 39999	Reserved
from 41000 to 41999	General setting data
from 42000 to 42999	Channel-specific setting data
from 43000 to 43999	Axis-specific setting data
from 51000 to 51299	General configuration machine data
from 51300 to 51999	General cycle machine data
from 52000 to 52299	Channel-specific configuration machine data
from 52300 to 52999	Channel-specific cycle machine data
from 53000 to 53299	Axis-specific configuration machine data
from 53300 to 53999	Axis-specific cycle machine data

Effectiveness

The effectiveness of a machine data item specifies when the change becomes active:

- POWER ON (po) NCK RESET
- NEWCONF (cf)
 - "Set MD to active" softkey
 - <RESET> key on the MSTT
 - It is possible to modify block limits during program operation
- RESET (re)
 - At end of program M2/M30 or
 - <RESET> key on the MSTT
- IMMEDIATE (so)
 - After the input of a value

Changes to the setting data always take effect **immediately**.

References

You find a description of the machine data and the setting data in:

- Online help (context-related)
- SINUMERIK 840D sl List Manual "Lists 1" /LIS1/

7.2 Parameter sets of axis/spindle

Introduction

Six parameter sets are available for each machine axis:

- For an axis, the parameter sets are used to adapt the own dynamic response to another machine axis, e.g. when tapping or thread cutting on the relevant spindle.
- For a spindle, the parameter sets are used to adapt the position control to the modified properties of the machine during operation, e.g. when switching the gearbox.

Tapping, thread cutting

The following applies to axes:

- For machine axes that are not involved in tapping or thread cutting, the first set of parameters (index=0) is active in all cases. The further parameter sets need not be considered.
- For machine axes involved in tapping or thread cutting: the parameter set is activated in accordance with the current gear stage. All parameter sets must be parameterized in accordance with the gear stages of the spindle.

The following applies to spindles:

- With spindles, each gear stage is assigned a parameter set of its own.

For example, gear stage 1 - parameter set 2 (index 1). Spindles in axis operation (DB31, ... DBX60.0 = 0) use Parameter set 1 (Index 0). The active gearbox step can be read in the PLC via the signals DB31, ... DBX82.0-2 (gearbox step setpoint). The parameter set is selected from the PLC using the interface signal DB31, ... DBX16.0 - 16.2 (actual gear stage). All parameter sets must be parameterized in accordance with the gear stages of the spindle.

Validity of parameter sets for axis and spindle modes

The active parameter set of a machine axis is displayed under "Service axis" in the "Diagnostics" operating area. The active parameter set can be read in the PLC via the signals DB31, ... DBX69.0-2 (Controller parameter set)."

Parameter set number	Axis	Spindle	Spindle gear stage
0	Standard	Axis mode	Depending on the manufacturer's specification
1	Axis interpolates with spindle (G33)	Spindle mode	1.
2	Axis interpolates with spindle (G33)	Spindle mode	2.
3	Axis interpolates with spindle (G33)	Spindle mode	3.
4	Axis interpolates with spindle (G33)	Spindle mode	4.
5	Axis interpolates with spindle (G33)	Spindle mode	5.

Remarks on the "Axis" column: The switchover applies to G33 as well as for G34, G35, G331 and G332.

Parameter-set-dependent machine data

The following machine data of an axis depends on the parameter set:

MD	Name	Meaning
31050	\$MA_DRIVE_AX_RATIO_DENOM[n]	Denominator load gearbox
31060	\$MA_DRIVE_AX_RATIO_NUMERA[n]	Numerator load gearbox
32200	\$MA_POSCTRL_GAIN[n]	Kv factor
32810	\$MA_EQUIV_SPEEDCTRL_TIME[n]	Equivalent time constant speed control loop for feedforward control
32910	\$MA_DYN_MATCH_TIME[n]	Time constant for dynamic matching
35110	\$MA_GEAR_STEP_MAX_VELO[n]	Maximum speed for gear stage change
35120	\$MA_GEAR_STEP_MIN_VELO[n]	Minimum speed for gear stage change
35130	\$MA_GEAR_STEP_MAX_VELO_LIMIT[n]	Maximum speed of gear stage
35140	\$MA_GEAR_STEP_MIN_VELO_LIMIT[n]	Minimum speed of gear stage
35200	\$MA_GEAR_STEP_SPEEDCTRL_ACCEL[n]	Acceleration in speed control mode
35210	\$MA_GEAR_STEP_POSCTRL_ACCEL[n]	Acceleration in position-control mode
36200	\$MA_AX_VELO_LIMIT[n]	Threshold value for velocity monitoring

n = parameter set number (0 ... 5)

7.3 Parameterize axis data

7.3.1 Parameterizing the incremental-rotary measuring system

Rotary measuring system

The diagrams below show the general possibilities for arranging a rotary incremental measuring system with regard to motor and load, as well as the resulting values for the appropriate machine data.

The figures equally apply to rotary axes, modulo axis and spindles:

- Linear axis with encoder on the machine

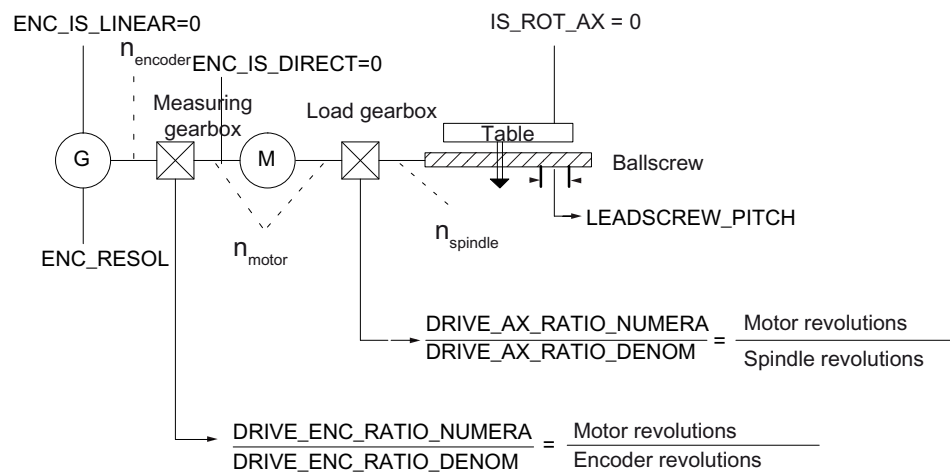


Figure 7-1 Linear axis with encoder on motor

- Linear axis with encoder on load

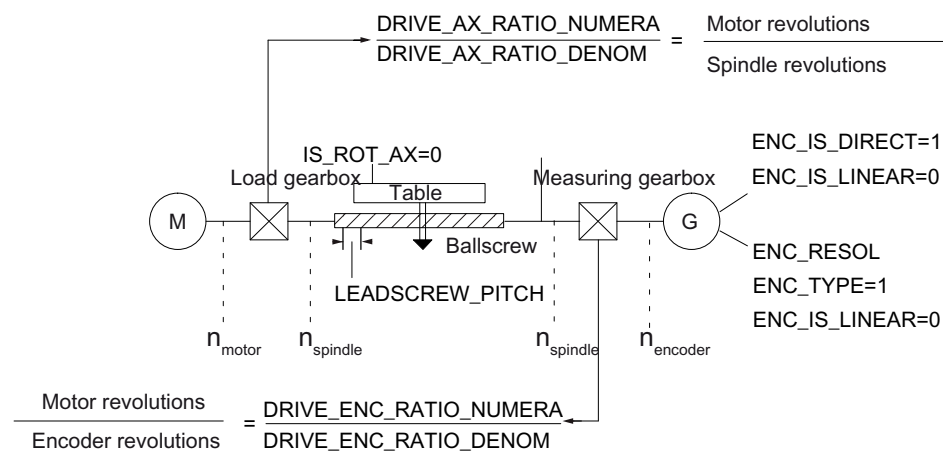


Figure 7-2 Linear axis with encoder on load

- Rotary axis with encoder on motor

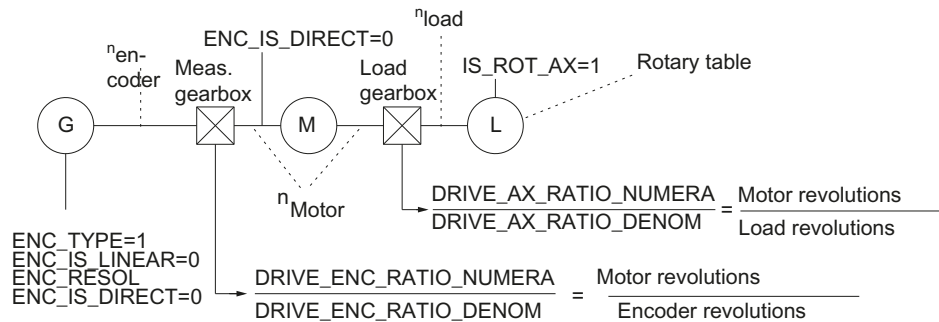


Figure 7-3 Rotary axis with encoder on motor

- Linear axis with encoder on the machine

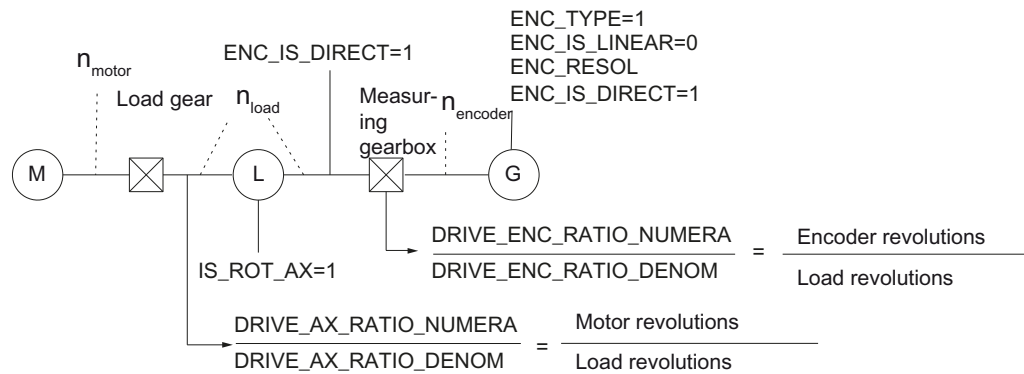


Figure 7-4 Linear axis with encoder on the machine

Machine data for incremental measuring systems

MD	Identifier	Comment
30240	\$MA_ENC_TYPE[n]	Actual-value acquisition modes: 1 = incremental raw signal generator
30242	\$MA_ENC_IS_INDEPENDENT[n]	Encoder is independent
30300	\$MA_IS_ROT_AX	Rotary axis
31000	\$MA_ENC_IS_LINEAR[n]	Direct measuring system (linear scale)
31020	\$MA_ENC_RESOL[n]	Encoder pulses per revolution
31030	\$MA_LEADSCREW_PITCH	Leadscrew pitch
31040	\$MA_ENC_IS_DIRECT[n]	Encoder is connected directly to the machine
31050	\$MA_DRIVE_AX_RATIO_DENOM[n]	Denominator load gearbox
31060	\$MA_DRIVE_AX_RATIO_NUMERA[n]	Numerator load gearbox
31070	\$MA_DRIVE_ENC_RATIO_DENOM[n]	Denominator of resolver gearbox
31080	\$MA_DRIVE_ENC_RATIO_NUMERA[n]	Numerator of resolver gearbox

7.3.2 Parameterizing the incremental-linear measuring system

Linear measuring system

The diagram below shows the general possibilities for arranging a linear incremental measuring system with regard to motor and load, as well as the resulting values for the respective machine data.

The representation applies equally to rotary axes, modulo axis and spindles:

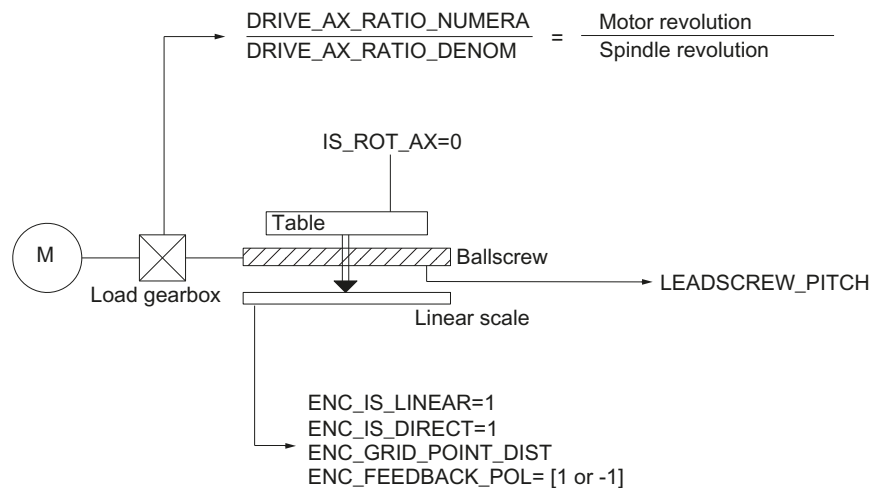


Figure 7-5 Linear axis with linear scale

Machine data for linear measuring systems

MD	Identifier	Comment
30240	\$MA_ENC_TYPE[n]	Actual-value acquisition modes 1 = incremental raw signal generator
30242	\$MA_ENC_IS_INDEPENDENT[n]	Encoder is independent
30300	\$MA_IS_ROT_AX	Rotary axis
31000	\$MA_ENC_IS_LINEAR[n]	Direct measuring system (linear scale)
31010	\$MA_ENC_GRID_POINT_DIST[n]	Distance between reference marks on linear scales
31030	\$MA_LEADSCREW_PITCH	Leadscrew pitch
31040	\$MA_ENC_IS_DIRECT[n]	Encoder is connected directly to the machine
31050	\$MA_DRIVE_AX_RATIO_DENOM[n]	Denominator load gearbox
31060	\$MA_DRIVE_AX_RATIO_NUMERA[n]	Numerator load gearbox
32110	\$MA_ENC_FEEDBACK_POL[n]	Sign actual value (feedback polarity)

7.3.3 Parameterizing the absolute measuring system

Encoder types

The following encoder types with EnDat protocol and incremental sinusoidal encoder signals A and B are currently supported:

- Single-turn absolute value encoder
- Multi-turn absolute value encoder

The absolute value encoder EQN 1325 from Heidenhain has the following properties:

- EnDat protocol
- PPR count: $2048 = 2^{11}$ (encoder fine resolution)
- Positions/revolution: 8192 (13 bits)
- Differentiable revolutions: 4096 (12 bits)
- Encoder signals A/B: 1Vpp sin/cos

Calibration

Convergence of the measuring system with the machine positions is performed by calibration of the absolute value encoder in absolute measuring systems.

- Linear axis with absolute value encoder on motor

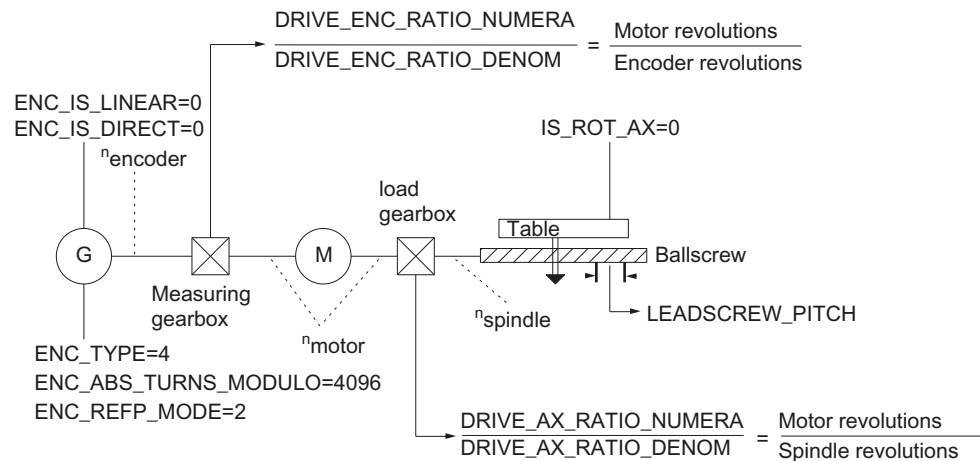


Figure 7-6 Linear axis with absolute value encoder on motor

- Rotary axis, modulo axis and spindle with absolute value encoder on motor

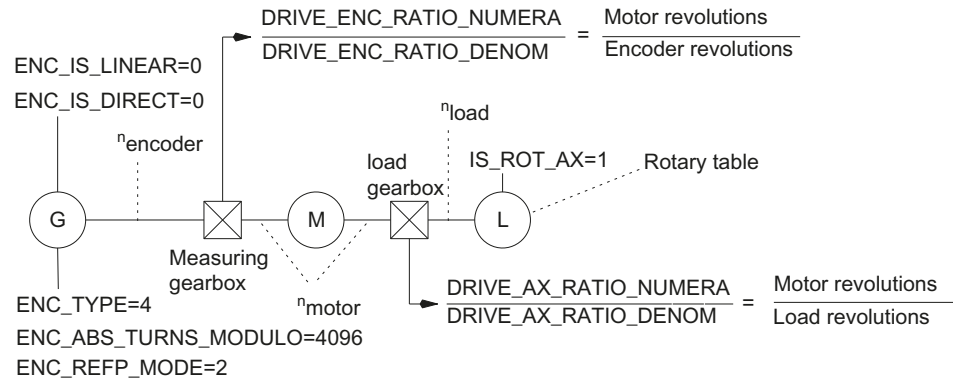


Figure 7-7 Rotary axis, modulo axis and spindle with absolute value encoder on motor

Machine data for absolute measuring systems

MD	Identifier	Comment
30240	\$MA_ENC_TYPE[n]	Actual-value acquisition modes
30242	\$MA_ENC_IS_INDEPENDENT[n]	Encoder is independent
30260	\$MA_ABS_INC_RATION[n]	Encoder fine resolution (absolute value encoder)
30300	\$MA_IS_ROT_AX[n]	Rotary axis

MD	Identifier	Comment
31000	\$MA_ENC_IS_LINEAR[n]	Direct measuring system (linear scale)
31030	\$MA_LEADSCREW_PITCH[n]	Leadscrew pitch
31040	\$MA_ENC_IS_DIRECT[n]	Encoder is connected directly to the machine
31050	\$MA_DRIVE_AX_RATIO_DENOM[n]	Denominator load gearbox
31060	\$MA_DRIVE_AX_RATIO_NUMERA[n]	Numerator load gearbox
31070	\$MA_DRIVE_ENC_RATIO_DENOM[n]	Measuring gearbox denominator
31080	\$MA_DRIVE_ENC_RATIO_NUMERA[n]	Measuring gearbox numerator
34200	\$MA_ENC_REFP_MODE[n]	Referencing mode
34210	\$MA_ENC_REFP_STATE[n]	Status of absolute value encoder
34220	\$MA_ENC_ABS_TURNS_MODULO[n]	Absolute value encoder range for rotary encoders (multi-turn resolution)

See also

For calibration of the absolute value encoder, see Chapter "Axis Homing" (Page 199).

7.3.4 Setpoint/actual value channels

Simulation axes

In order to guarantee that the controller runs up reliably, all machine axes are declared as simulation axes (without hardware).

- MD30130 \$MA_CTRLOUT_TYPE (output type of setpoint value) = 0
- MD30240 \$MA_ENC_TYPE (actual-value acquisition mode) = 0

Traversing the axes is simulated in SERVO mode without speed setpoint output, and no hardware-specific alarms are output.

The following machine data can be used to select whether the interface signals of a simulation axis are output at the NC/PLC interface (e.g. during program test, if there is no drive hardware, used in FC18 in PLC).

- MD30350 \$MA_SIMU_AX_VDI_OUTPUT (output of axis signals with simulation axes)

Assignment of the setpoint / actual value channels

For each machine axis to which a drive is assigned, the following must be parameterized:

- A setpoint channel and
- At least one actual-value channel

A second actual-value channel can be set up as an option.

Note

The motor measuring system is always used for the speed control function. Motor and motor measuring system must therefore always be connected to the same drive (SERVO).

In the following two axis-specific machine data, the logical drive number m of the drive is entered, which represents the machine axis:

- MD30110 \$MA_CTRLOUT_MODULE_NR[0] (setpoint assignment: Logical drive number)
- MD30220 \$MA_ENC_MODUL_NR[n] (actual value assignment: Logical drive number)

With the logical drive number m , that drive is addressed whose I/O address is entered under the index $n = (m - 1)$ in MD13050 \$MN_DRIVE_LOGIC_ADDRESS[<n>] (see Chapter "Axis assignment (Page 376)").

Once the drive configuration and setpoint / actual value assignment have been parameterized, an NCK reset must be executed to initiate a warm restart of the NC. After the NC has powered up, the set configuration is effective.

Measuring system switchover

The following interface signals can be used to switch between the two position measuring systems of a machine axis from the PLC:

- DB31, ... DBX1.5 (position measuring system 1 selected)
- DB31, ... DBX1.6 (position measuring system 2 selected)

Machine data

MD	Identifier	Remark
30110	\$MA_CTRLOUT_MODULE_NR	Setpoint assignment: Logical drive number
30130	\$MA_CTRLOUT_TYPE	Output of setpoint value 0 = Simulation 1 = Output of speed setpoint
30200	\$MA_NUM_ENCS	Number of measuring channels 1 = One position measuring system present 2 = Two position measuring systems present
30220	\$MA_ENC_MODULE_NR[0]	Actual value assignment: Logical drive number for position measuring system 1
30220	\$MA_ENC_MODULE_NR[1]	Actual value assignment: Logical drive number for position measuring system 2
30230	\$MA_ENC_INPUT_NR[0]	Actual value assignment: Position measuring system 1 1 = G1_XIST encoder 1 position actual value 1 2 = G2_XIST encoder 1 position actual value 2

MD	Identifier	Remark
30230	\$MA_ENC_INPUT_NR[1]	Actual value assignment: Position measuring system 2 1 = G1_XIST encoder 2 position actual value 1 2 = G2_XIST encoder 2 position actual value 2
30240	\$MA_ENC_TYPE[0]	Type of actual value recording 0 = Simulation 1 = Incremental encoder 4 = Absolute encoder with EnDat interface

References

Basic Functions Function Manual; Various Interface Signals (A2)

7.3.5 Dynamic Servo Control (DSC)

Overview

The DSC function eliminates the deadtime that necessarily exists at the speed-setpoint interface normally used between the NCK and drive due to relocation of the position controller into the drive.

This results in the following advantages for an axis operated with DSC:

- Considerably improved fault response/stability of the position control loop
- Improved command behavior (contour precision) if the loop gain (Kv factor) that can be set higher in conjunction with DSC is used.
- A reduction of the cyclic communication load on the PROFIBUS, if the position controller cycle/PROFIBUS cycle is reduced by adjusting the above parameters, even if the control loop performance is the same.

Note

The speed feedforward control can be used in conjunction with DSC.

Speed setpoint filter

If you use DSC, a speed setpoint filter for rounding the speed setpoint steps is no longer necessary. The speed setpoint filter is then only of any use with differential connection to support the position controller, for example, to suppress resonance.

Preconditions

Before you can activate DSC mode, the following preconditions must be fulfilled:

- DSC-capable drive
- A DSC-capable telegram type has been parameterized in the S7 project for the drive.

Switch ON/OFF

The DSC function is switched ON via the following axis-specific machine data:

- MD32640 \$MA_STIFFNESS_CONTROL_ENABLE (dynamic stiffness control)

If the DSC operation is switched ON or OFF, it might be necessary to adjust the following machine data:

- MD32200 \$MA_POSCTRL_GAIN (K_v factor)
- MD32610 \$MA_VELO_FFW_WEIGHT (Feedforward control factor)
- MD32810 \$MA_EQUIV_SPEEDCTRL_TIME (Equivalent time constant of the closed speed control loop)

NOTICE
Stability of the position control loop
Before you can switch off DSC operation you might have to adapt (reduce) the K _v factor of the axis. Otherwise, instability of the position control loop might result.

Actual value inversion during DSC operation

Note

Actual value inversion during DSC operation (MD32640=1) is undertaken as follows:

- Set the p0410 parameter (encoder inversion actual value) in the drive.
- In the NC in the machine data, set MD32110 \$MA_ENC_FEEDBACK_POL = 0 or 1 (no inversion!).

Actual value inversion via MD32110=-1 is not possible while DSC operation is active.

If MD32110=-1 is to be set, the "26017 axis%1 machine data 32110 value not permitted" alarm is output when DSC operation is activated.

Machine data

MD	Identifier	Name
32640	\$MA_STIFFNESS_CONTROL_ENABLE	Dyn. stiffness control
32200	\$MA_POSCTRL_GAIN	K _V factor
32642	\$MA_STIFFNESS_CONTROL_CONFIG	The dynamic stiffness control is configured: 0: DSC in the drive operates with an indirect measuring system (default setting) 1: DSC in drive operating with direct measuring system

7.3.6 Rotary axes

Rotary axes

A machine axis is parameterized as a rotary axis in

- MD30300 \$MA_IS_ROT_AX (rotary axis) = 1

The machine data is a scaling machine data. A change results in a conversion of all machine data of the machine axis with length-related units.

For the recommended procedure with respect to scaling machine data, please refer to Section "Modifying Scaling Machine Data".

Modulo display

The display of the rotary axis position modulo 360 degrees is displayed via the following machine data:

- MD30320 \$MA_DISPLAY_IS_MODULO (modulo 360 degrees display for rotary axes)

Endlessly rotating rotary axis / modulo axis

The traversing of the rotary axis modulo 360 degrees is displayed via the following machine data:

- MD30310 \$MA_ROT_IS_MODULO (modulo conversion for rotary axis)

The limit switches are not monitored during this process. The rotary axis can thus rotate endlessly.

The limit switch monitoring can be activated by the PLC interface.

Machine data

MD	Identifier	Name
10210	\$MN_INT_INCR_PER_DEG	Computational resolution for angular positions
30300	\$MA_IS_ROT_AX	Axis is rotary axis
30310	\$MA_ROT_IS_MODULO	Modulo conversion for rotary axis

MD	Identifier	Name
30320	\$MA_DISPLAY_IS_MODULO	Actual value display modulo
36100	\$MA_POS_LIMIT_MINUS	Minus software limit switch
36110	\$MA_POS_LIMIT_PLUS	Plus software limit switch

Literature

Function Manual, Extended Functions; Rotary Axes (R2)

7.3.7 Positioning axes

Positioning axes

Positioning axes are channel axes traversing parallel to the path axes without interpolating with them. Positioning axes can be traversed either from the part program or from the PLC.

A channel axis is defined as neutral with the following machine data. As a result no REORG takes place if the axis/spindle is traversed by the PLC (FC18) or by synchronous actions.

- MD30450 \$MA_IS_CONCURRENT_POS_AX (neutral axis / channel axis) = 1

Positioning axis feedrate

If a positioning axis is programmed in the part program without specifying an axis-specific feedrate, the feedrate entered in the following machine data is automatically applicable to this axis:

- MD32060 \$MA_POS_AX_VELO (initial setting for positioning axis velocity)

This feedrate applies until an axis-specific feedrate is programmed in the part program for this axis.

Machine data

MD	Identifier	Name
22240	\$MC_AUXFU_F_SYNC_TYPE	Output timing of F functions
30450	\$MA_IS_CONCURRENT_POS_AX	Neutral axis or channel axis
32060	\$MA_POS_AX_VELO	Initial setting for positioning-axis velocity

Literature

Function Manual, Extended Functions; Positioning Axes (P2)

7.3.8 Indexed axes/"Hirth" axes

Indexing axis

Indexing axes are rotary or linear axes, which can be traversed to indexing positions by part program instructions. These indexing positions are approached in JOG mode. In "normal" positioning, every position can be approached.

Note

Traversing to indexing positions using the part program or manually is only effective if the corresponding machine axis has been successfully referenced.

Hirth axes are indexing axes with Hirth tooth system. These axes are rotary or linear axes, which may only be traversed to defined positions, the indexing positions, within the traversing range (MD30505 \$MA_HIRTH_IS_ACTIVE). The indexing positions are stored in tables.

The following machine data assigns the machine axis the relevant table of indexing positions and also defines the machine axis as an indexing axis:

- MD30500 \$MA_INDEX_AX_ASSIGN_POS_TAB[n] (axis is an indexing axis)

Indexing position tables

The indexing positions are stored in one of the two tables.

- MD10900 \$MN_INDEX_AX_LENGTH_POS_TAB_1 (number of positions of indexing axis table 1)
- MD10910 \$MN_INDEX_AX_POS_TAB_1 [n] (indexing position table 1)
- MD10920 \$MN_INDEX_AX_LENGTH_POS_TAB_2 (number of positions of indexing axis table 2)
- MD10930 \$MN_INDEX_AX_POS_TAB_2 [n] (indexing position table 2)

Machine data

MD	Identifier	Comment
10260	\$MN_CONVERT_SCALING_SYSTEM	Basic system switchover active
10270	\$MN_POS_TAB_SCALING_SYSTEM	Measuring system of position tables
10900	\$MN_INDEX_AX_LENGTH_POS_TAB_1	Number of indexing positions used in table 1
10910	\$MN_INDEX_AX_POS_TAB_1[n]	Indexing position table 1
10920	\$MN_INDEX_AX_LENGTH_POS_TAB_2	Number of indexing positions used in table 2
10930	\$MN_INDEX_AX_POS_TAB_2[n]	Indexing position table 2
30300	\$MA_IS_ROT_AX	Rotary axis

MD	Identifier	Comment
30310	\$MA_ROT_IS_MODULO	Modulo conversion for rotary axis
30320	\$MA_DISPLAY_IS_MODULO	Position display is modulo 360 degrees
30500	\$MA_INDEX_AX_ASSIGN_POS_TAB	Axis is indexing axis
30501	\$MA_INDEX_AX_NUMERATOR	Numerator for indexing axes with equidistant positions
30505	\$MA_HIRTH_IS_ACTIVE	Axis is an indexing axis with Hirth toothing

Literature

Function Manual Expanded Functions; Indexing Axes (T1)

7.3.9 Position controller

Control loops

The closed-loop control of a machine axis consists of the cascaded closed-loop control circuits of current controller, speed controller and position controller.

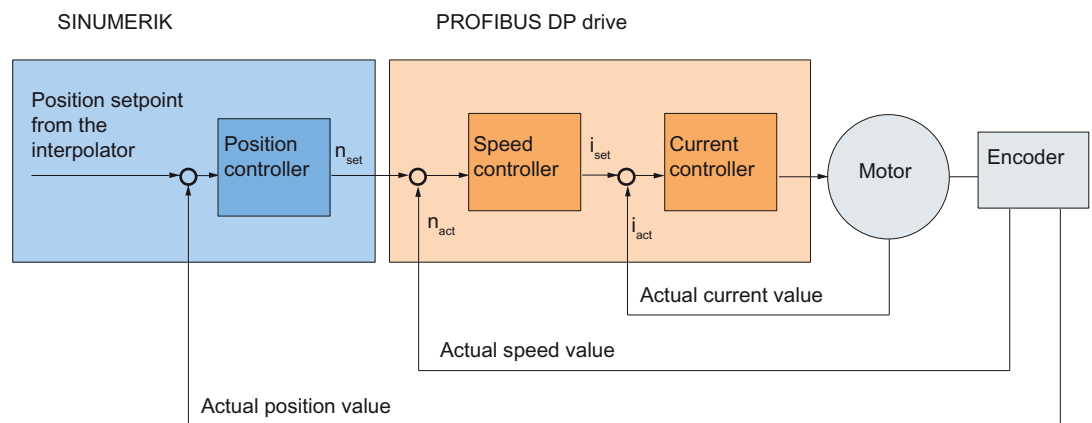


Figure 7-8 Control loops

Travel direction

If the axis does not traverse into the desired direction, the appropriate adaptation is made in the following machine data:

- MD32100 \$MA_AX_MOTION_DIR (travel direction)

The value "-1" reverses the direction of motion.

Control direction

If the control direction of the position measuring system is incorrect, it can be adjusted with the following machine data:

- MD32110 \$MA_ENC_FEEDBACK_POL (sign of actual value)

Note

When DSC is activated on the incorrect position measuring system, the control direction must also be adjusted in SINAMICS parameter p410.

Servo gain

To obtain high contour accuracy, a high loop gain (K_V factor) of the position controller is required. However, an excessively high K_V factor causes overshoot, instability and impermissibly high machine loads.

The maximum permissible K_V factor is dependent on the dynamic response and the use of the feedforward control or DSC, of the drive and the mechanical system of the machine.

Note

The initial commissioning is performed without feedforward control.

A K_V factor of "0" leads to the position controller being cut.

Definition of K_V factor

The K_V factor is defined as the ratio of velocity in m/min and the resulting following error in mm

$$K_V = \frac{\text{Velocity}}{\text{Following error}} \quad \left[\frac{\text{[m/min]}}{\text{[mm]}} \right]$$

This means for a K_V factor of 1 that at a velocity of 1m/min, a following error of 1mm results.

The K_V factor of the machine axis is entered via the following machine data:

- MD32200 \$MA_POSCTRL_GAIN (servo_{gain} factor)

Note

To adapt the input/output unit of the K_V factor selected by default to the internal unit [1/s], the following machine data is pre-assigned:

- MD10230 \$MN_SCALING_FACTORS_USER_DEF[9] = 16.666667
 - MD10220 \$MN_SCALING_USER_DEF_MASK = 'H200'; (bit 9 as hex value)
-

When entering the K_V factor it is important to note that the gain factor of the whole position control loop is still dependent on other parameters of the controlled system (speed setpoint alignment).

These factors include, among others:

- MD32260 \$MA_RATED_VELO
- MD32250 \$MA_RATED_OUTVAL
- Automatic interface alignment (SINAMICS parameter "Reference speed" p2000)

For drive optimization, see also: Adjusting speed and brake behavior (Page 153)

Note

Interpolation of axes

Machine axes that interpolate one with another must have the same dynamic response at the same velocities.

This can be achieved by setting the same K_V factor or dynamic response adaptation in the following machine data:

- MD32900 \$MA_DYN_MATCH_ENABLE
- MD32910 \$MA_DYN_MATCH_TIME

The real K_V factor can be checked with the following error in the service display.

"Diagnostics" operating area → Menu forward key → "Axis diagnostics" → "Service axis".

Checking the loop gain

If a K_V factor is already known for a machine type in question, this can be set and checked. To ensure that the drive does not reach its current limit during acceleration and deceleration, the acceleration is reduced for checking via the following machine data:

- MD32300 \$MA_MAX_AX_ACCEL (axis acceleration)

The K_V factor must also be checked for high speeds of the rotary axis and spindle (e.g. for spindle positioning, tapping).

The approach behavior at various speeds can be checked by means of the HMI-Advanced servo trace software. The speed setpoint is recorded for this purpose.

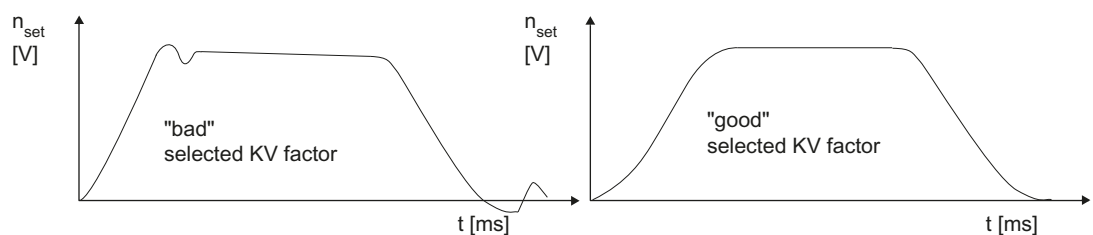


Figure 7-9 Speed setpoint characteristic

No overshoots may occur while the drive is approaching the static states; this applies to all speed ranges.

Overshoot in the position control loop

The reasons for an overshoot in the control loop can be:

- Acceleration too high (current limit is reached)
- Rise time too long (re-optimization necessary)
- Mechanical backlash
- Mechanical components canted

For safety reasons, set the Kv factor for each axis to a little less than the maximum possible value.

- MD32900 \$MA_DYN_MATCH_ENABLE[n]
- MD32910 \$MA_DYN_MATCH_TIME[n]

For axes interpolating with each other, the same Kv-factor should be set. Normally it is the Kv factor of the weakest interpolating axis.

Contour monitoring must be set subsequently (MD36400 \$MA_CONTROL_TOL).

Acceleration

In the following machine data, machine axes are accelerated and decelerated with the values entered.

- MD32300 \$MA_MAX_AX_ACCEL (axis acceleration)

This value should allow the axes to be accelerated and positioned fast and accurately, while ensuring that the machine is not loaded unduly.

Checking the acceleration

The sign of a properly adjusted acceleration of a machine axis is acceleration and positioning free from overshoot at rapid traverse rate and maximum load (max. external moment of inertia).

After the acceleration has been entered, the axis is traversed rapidly and the actual current values and current setpoint are recorded.

This recording shows whether the drive reaches the current limit. Here, the current limit can be reached for a short time.

The current must be well below the current limit, however, before the rapid traverse velocity or the final position is reached.

Load changes during the machining should not result in the current limit being reached, as they may result in contour errors. For this reason, the acceleration value should be a little less than the maximum acceleration value.

Machine axes can have different acceleration values, even if they interpolate with each other.

Axial jerk

The following should be noted for the axis jerk:

- For part program instructions (SOFT), the following machine data must be set for the axial jerk:
 - MD32431 \$MA_MAX_AX_JERK (Maximum jerk)
 - MD32402 \$MA_AX_JERK_MODE (Filter type)
 - MD32890 \$MA_DESVAL_DELAY_ENABLE (Axial phase filter setpoint)
 - MD32895 \$MA_DESVAL_DELAY_TIME
- For JOG and positioning axes the following machine data should be supplemented:
 - MD32420 \$MA_JOG_AND_POS_JERK_ENABLE
 - MD32430 \$MA_JOG_AND_POS_MAX_JERK (Axial jerk)

Example

MD32890 \$MA_DESVAL_DELAY_ENABLE = TRUE

MD32895 \$MA_DESVAL_DELAY_TIME = 0.002 s

Position control cycle setting: 2 ms

The phase filter is active and the input values are delayed by one position control cycle.

Machine data for the closed-loop position control

MD	Name	Meaning
32100	\$MA_AX_MOTION_DIR[n]	Travel direction
32110	\$MA_ENC_FEEDBACK_POL[n]	Actual value sign
32200	\$MA_POSCTRL_GAIN[n]	Servo gain factor
32300	\$MA_MAX_AX_ACCEL[n]	Axis acceleration
32890	\$MA_DESVAL_DELAY_ENABLE	Axial phase filter setpoint
32895	\$MA_DESVAL_DELAY_TIME	Time constant for the axial phase filter setpoint
32402	MD32402 \$MA_AX_JERK_MODE	Filter type for axial jerk limitation
32420	\$MA_JOG_AND_POS_JERK_ENABLE	Enabling jerk limitation
32430	\$MA_JOG_AND_POS_MAX_JERK	Axial jerk
32431	\$MA_MAX_AX_JERK	Maximum axial jerk when traversing along the path
32900	\$MA_DYN_MATCH_ENABLE[n]	Dynamic response adaptation
32910	\$MA_DYN_MATCH_TIME[n]	Time constant for dynamic matching
36400	\$MA_CONTROL_TOL	Contour monitoring

References

- Function Manual, Basic Functions; Velocities, Setpoint / Actual Value Systems, Closed-Loop Control (G2)
- Function Manual, Basic Functions; Acceleration (B2)
- Extended Functions Function Manual; Compensation (K3)

7.3.10 Speed setpoint matching

Overview

In the case of speed setpoint comparison, the NC is informed which speed setpoint corresponds to which motor speed in the drive, for parameterizing the axial control and monitoring. Speed setpoint matching can be performed automatically or manually.

Automatic adjustment

It is possible to perform automatic speed setpoint adjustment if the drive supports acyclic services on the PROFIBUS DP (default for SINAMICS).

Acyclic services on the PROFIBUS DP are supported if the value "0" is entered in the following machine data:

- MD32250 \$MA_RATED_OUTVAL (rated output voltage) [%]

During start-up of the NCK, speed setpoint matching between the NCK and the drive is then performed automatically.

 WARNING
--

No axis release

The "Reference speed" p2000 parameter may not be changed during operation of the controller with the drive.

If automatic speed setpoint matching fails for one axis, the following message is output on a traverse request for this axis: "Wait, axis enable missing". This axis and any axes that interpolate with it are not traversed.

Manual comparison

The speed setpoint alignment (interface normalization) is specified in the following machine data:

- MD32250 \$MA_RATED_OUTVAL (rated output voltage) [%]
- MD32260 \$MA_RATED_VELO (rated motor speed)

If a value not equal to 0 is entered in the following machine data, a manual speed setpoint matching is performed:

- MD32250 \$MA_RATED_OUTVAL (rated output voltage) [%]

Note

The maximum upper limit for the speed setpoint is predefined in the following machine data:

- MD36210 \$MA_CTRLOUT_LIMIT (maximum speed setpoint) [%]
-

Calculation of the motor speed

If the motor speed required for speed setpoint matching is not known directly, it can be calculated as follows with reference to the required axis velocity (linear axis) or load speed (rotary axis/spindle):

- Motor speed for linear axis:

$$n_{\text{motor}} = \frac{v_{\text{axis}} * \frac{\text{MD31060 } \$\text{MA_DRIVE_RATIO_NUMERA}}{\text{MD31050 } \$\text{MA_DRIVE_RATIO_DENOM}}}{\text{MD31030 } \$\text{MA_LEADSCREW_PITCH}}$$

- Motor speed for rotary axis/spindle:

$$n_{\text{motor}} = n_{\text{load}} * \frac{\text{MD31060 } \$\text{MA_DRIVE_RATIO_NUMERA}}{\text{MD31050 } \$\text{MA_DRIVE_RATIO_DENOM}}$$

v_{Axis} [mm/min]

n_{Motor} [rpm]

n_{Load} [rpm]

MD31060 \$MA_DRIVE_RATIO_NUMERA

MD31050 \$MA_DRIVE_RATIO_DENOM

MD31030 \$MA_LEADSCREW_PITCH

Motor speed

Load speed

Numerator load gearbox

Denominator load gearbox

Pitch of the ball screw [mm/rev]

Checking the trim

Incorrect speed setpoint matching has a negative impact on the real loop gain of the axis. To check speed setpoint matching it is necessary for a defined traverse velocity to compare the actual following error with the desired following error that should be set if speed setpoint matching is correct.

$$\text{Desired following error} = \frac{\text{Traverse rate}}{\text{MD32200 \$MA_POSCTRL_GAIN}}$$

[mm]	Desired following error
[m/min]	Traverse rate
MD32200 \$MA_POSCTRL_GAIN	K _v factor in [(m/min)/mm]

The actual following error is displayed in the "Diagnosis" operating area → Menu forward key → "Axis diagnostics" → "Service axis".

Machine data

MD	Identifier	Remark
32250	\$MA_RATED_OUTVAL	Rated output voltage [%]
32260	\$MA_RATED_VELO	Rated motor speed

References

Function Manual, Basic Functions; Velocities, Setpoint-Actual Value Systems, Closed-Loop Control (G2)

7.3.11 Velocity matching (axis)

Maximum axis velocity

The value entered in the following machine data is the limit velocity up to which a machine axis can accelerate (rapid traverse limiting). It depends on the machine and drive dynamics and the limit frequency of actual-value acquisition.

- MD32000 \$MA_MAX_AX_VELO[n] (max. axis velocity)

The max. axis velocity is used for traversing in the part program when rapid traverse (G00) is programmed. The maximum linear or rotary axis velocity should be entered in the machine data in accordance with MD30300 \$MA_IS_ROT_AX[n].

Rapid traverse in jog mode

The value entered in the following machine data is the velocity at which the machine axis traverses in JOG mode with the rapid traverse override key actuated and with an axial feed override of 100%.

- MD32010 \$MA_JOG_VELO_RAPID[n] (rapid traverse in JOG mode) or
- MD32040 \$MA_JOG_REV_VELO_RAPID[n] (revolutional feedrate in JOG mode with rapid traverse override)

The entered value may not exceed the max. permissible axis velocity.

This machine data will not be used for the programmed rapid traverse G00.

JOG axis velocity

The value entered in this machine data is the velocity at which the machine axis traverses in JOG mode with an axial feed override of 100%:

- MD32020 \$MA_JOG_VELO[n] (axis velocity in JOG mode) or
- MD32050 \$MA_JOG_REV_VELO[n] (revolutional feedrate in JOG mode)

The velocity from MD32020 JOG_VELO[n] or MD32050 JOG_REV_VELO[n] is used only in the following cases:

- For linear axes: SD41110 \$SN_JOG_SET_VELO = 0
- For rotary axes: SD41130 \$SN_JOG_ROT_AX_SET_VELO = 0
- For reverse feed: SD41120 \$SN_JOG_REV_SET_VELO = 0

If the above-mentioned setting data is not equal 0, this produces the following JOG velocity:

1. SD41100 \$SN_JOG_REV_IS_ACTIVE (revolutional feedrate in JOG mode) = 0
=> Linear feedrate (G94)
– Linear axes:
JOG velocity = SD41110 \$SN_JOG_SET_VELO (JOG velocity for G94)
– Rotary axes:
JOG velocity = SD41130 \$SN_JOG_ROT_AX_SET_VELO (JOG velocity for rotary axes)
2. SD41100 \$SN_JOG_REV_IS_ACTIVE (revolutional feedrate in JOG mode) = 1
– JOG velocity = SD41120 \$SN_JOG_REV_SET_VELO (JOG velocity for G95)

The entered values may not exceed the maximum permissible axis velocity.

Note

Depending on MD30300 \$MA_IS_ROT_AX[n] , the speeds must be entered in mm/min, inch/min or rpm.

If the velocities are changed, MD36200 \$MA_AX_VELO_LIMIT[n] (threshold value for velocity monitoring) must be adapted accordingly.

Machine data

MD	Identifier	Comment
30300	\$MA_IS_ROT_AX[n]	Rotary axis
32000	\$MA_MAX_AX_VELO[n]	Maximum axis velocity
32010	\$MA_JOG_VELO_RAPID[n]	Rapid traverse in jog mode
32020	\$MA_JOG_VELO[n]	JOG axis velocity
32040	\$MA_JOG_REV_VELO_RAPID[n]	Revolutional feedrate in JOG mode with rapid traverse override
32050	\$MA_JOG_REV_VELO[n]	Revolutional feedrate in JOG mode

MD	Identifier	Comment
32060	\$MA_POS_AX_VELO[n]	Initial setting for positioning-axis velocity
32250	\$MA_RATED_OUTVAL	Rated output voltage
32260	\$MA_RATED_VELO[n]	Rated motor speed

Literature

- Function Manual, Basic Functions; Velocities, Setpoint-Actual Value Systems, Closed-Loop Control (G2)
- Extended Functions Function Manual; Manual and Handwheel Travel (H1)

7.3.12 Axis monitoring functions (static)

Static monitoring functions

The static monitoring functions with reference to a machine axis are:

Exact stop coarse

Window around the setpoint position within which exact stop coarse is detected.

- MD36000 \$MA_STOP_LIMIT_COARSE (exact stop coarse)
- IS: DB31,... DBX60.6 (position reached with exact stop coarse)

Exact stop fine

Window around the setpoint position within which exact stop fine is detected.

- MD36010 \$MA_STOP_LIMIT_FINE (exact stop fine)
- IS: DB31,... DBX60.7 (position reached with exact stop coarse)

Delay time exact stop fine

Delay time after which the actual value must have reached the tolerance window "Exact stop fine" when the setpoint position is reached.

- MD36020 \$MA_POSITIONING_TIME (delay time exact stop fine)
- Alarm: "25080 Positioning monitoring" and follow-up mode

Zero speed tolerance

Position tolerance which a standing machine axis may not leave.

- MD36030 \$MA_STANDSTILL_POS_TOL (standstill tolerance)
- Alarm: "25040 Zero speed control" and follow-up mode

Delay time zero speed monitoring

Delay time after which the actual value must have reached the tolerance window "zero speed tolerance" when the setpoint position is reached.

- MD36040 \$MA_STANDSTILL_DELAY_TIME (Zero-speed monitoring delay time)
- Alarm: "25040 Zero speed control" and follow-up mode

Clamping tolerance

Tolerance window for a standing machine axis while the signal "Clamping active" is present at the PLC interface.

- MD36050 \$MA_CLAMP_POS_TOL (clamping tolerance)
- IS: DB31,... DBX2.3 (clamping active)
- Alarm: "26000 Clamping monitoring"

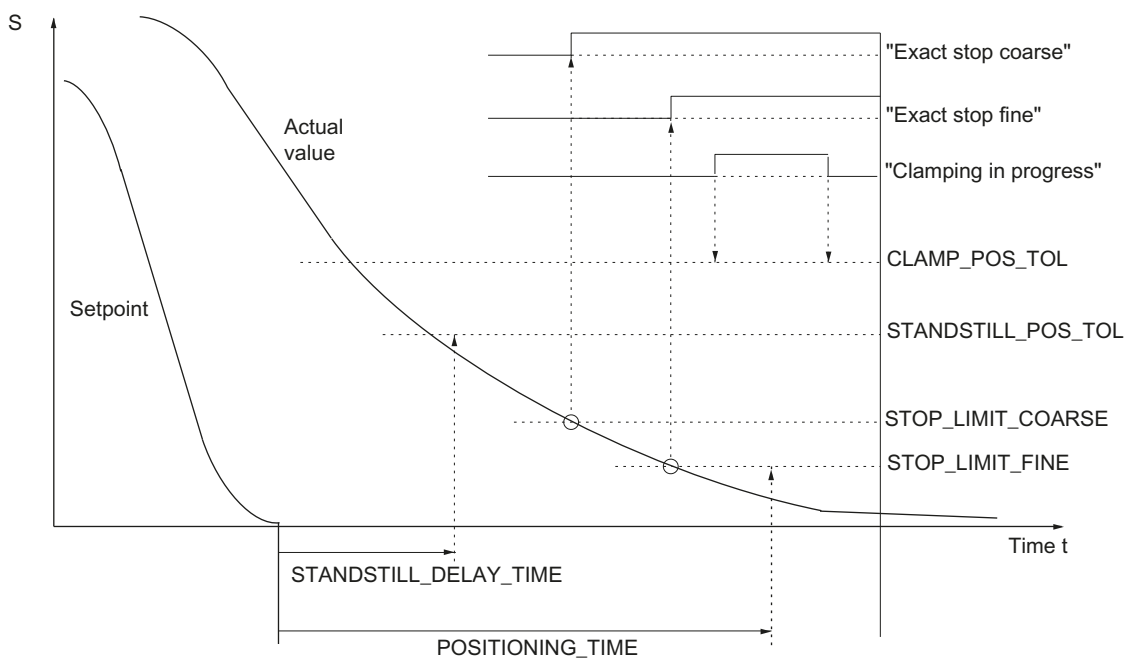


Figure 7-10 Static monitoring functions

Working area limitation

The permissible working area of the machine axes can be adapted to the particular machining situation using the "dynamic" working area limitation.

- SD43400 \$SA_WORKAREA_PLUS_ENABLE (working area limitation active in the positive direction)
- SD43410 \$SA_WORKAREA_MINUS_ENABLE (working area limitation active in the negative direction)
- SD43420 \$SA_WORKAREA_LIMIT_PLUS (working area limitation plus)
- SD43430 \$SA_WORKAREA_LIMIT_MINUS (working area limitation minus)

- Alarm: "10630 Axis reaching operating range limit +/-"
- Alarm: "10631 Axis is at operating range limit +/- (JOG)"
- Alarm: "10730 Progr. end point is behind working area limitation +/-"

Software limit switch

Two software limit switch pairs are provided per machine axis. The active software limit switch pair is selected in the PLC.

- MD36100 \$MA_POS_LIMIT_MINUS (1st software limit switch minus)
- MD36110 \$MA_POS_LIMIT_PLUS (1st software limit switch plus)
- MD36120 \$MA_POS_LIMIT_MINUS2 (2nd software limit switch minus)
- MD36130 \$MA_POS_LIMIT_PLUS2 (2nd software limit switch plus)
- IS: DB31,... DBX12.2 (2nd software limit switch minus)
- IS: DB31,... DBX12.3 (2nd software limit switch plus)
- Alarm: "10620 Axis reaching software limit switch +/-"
- Alarm: "10621 Axis is at software limit switch +/- (JOG)"
- Alarm: "10720 Progr. end point is behind software limit switch +/-"

Note

All position monitoring functions are only active with valid reference point of the corresponding reference point of the machine axis.

Hardware limit switch

If the PLC signals that a hardware limit switch has been reached, the machine axis is stopped with the parameterized brake response.

- IS: DB31, ... DBX12.1 (hardware limit switch plus)
- IS: DB31, ... DBX12.0 (hardware limit switch minus)

- MD36600 \$MA_BRAKE_MODE_CHOICE (braking behavior on hardware limit switch)
0 = Brake characteristic is complied with
1 = Rapid deceleration with setpoint "0"
- Alarm: "21614 Hardware limit switch [+/-]"

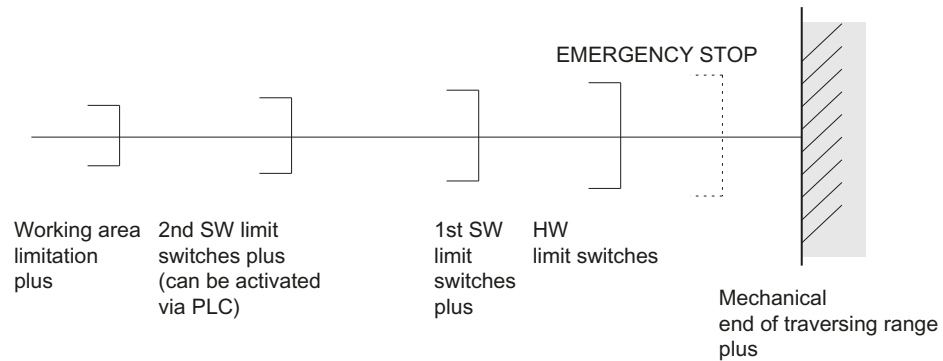


Figure 7-11 Overview of end limitations

Literature

Function Manual Basic Functions; Axis monitoring: Protection zones (A3)

7.3.13 Axis monitoring functions (dynamic)

Dynamic monitoring functions

The dynamic monitoring functions with reference to a machine axis are:

Speed setpoint monitoring

The speed-setpoint monitoring prevents that the max. admissible motor speed is exceeded. It must be set such that the max. velocity (rapid traverse) can be reached and, in addition, a certain control margin remains.

- MD36210 \$MA_CTRL_OUT_LIMIT[n] (maximum speed setpoint as %)

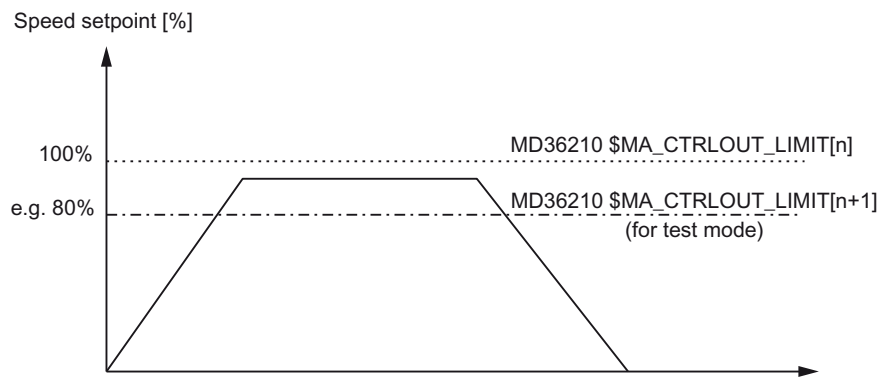


Figure 7-12 Speed setpoint limitation

The following machine data is used to define how long the speed setpoint may remain within the limits before the speed-setpoint monitoring responds.

- MD36220 \$MA_CTRLOUT_LIMIT_TIME[n] (delay time for speed-setpoint monitoring)

Error response

- Alarm: "25060 Speed-setpoint limiting"

and stopping the machine axis using a speed-setpoint ramp whose characteristic is set in

- MD36610 \$MA_AX_EMERGENCY_STOP_TIME (braking ramp time when errors occur)

Cause of errors / error handling

- A measuring circuit error or drive error is present.
- Setpoints are too high (accelerations, velocities, reducing factors).
- Obstacle in the machining space (e.g. tool hits working table) => remove obstacle.

The speed setpoint consists of the speed setpoint of the position controller and the feedforward control parameter (if feedforward control is active).

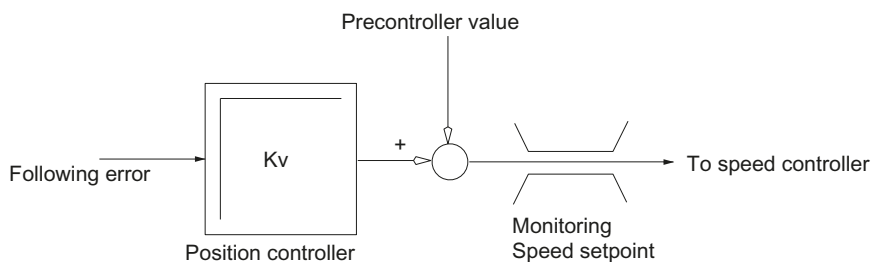


Figure 7-13 Speed setpoint calculation

Note

The limitation of the speed setpoint will turn the control loop into a non-linear control loop.
Generally, this will result in deviations from the contour and longer dwelling of the machine axis within the speed-setpoint limitation.

Actual velocity monitoring

Monitoring due to the actual velocity of the machine axis determined based on the encoder values

- MD36020 \$MA_AX_VELO_LIMIT (velocity-monitoring threshold)

Error response

- Alarm: "25030 Alarm limit of actual velocity"

and stopping the machine axis using a speed-setpoint ramp whose characteristic is set in

- MD36610 \$MA_AX_EMERGENCY_STOP_TIME (braking ramp time when errors occur)

Error correction

- Check actual values
- Check position control direction (control sense)
- Threshold value for velocity monitoring is possibly too low.

Contour monitoring

Monitoring of the difference between the following error measured and the following error calculated from the position setpoint.

- MD36400 CONTOUR_TOL (contour monitoring tolerance range)

Error response

- Alarm: "25050 Contour monitoring"

and stopping the machine axis using a speed-setpoint ramp whose characteristic is set in

- MD36610 \$MA_AX_EMERGENCY_STOP_TIME (braking ramp time when errors occur)

Error correction

Contour errors are caused by signal distortions in the position control loop.

- Increase the tolerance band
- Check the K_v factor:

The real K_v factor must correspond to the desired K_v factor, set via MD32200 \$MA_POSCTRL_GAIN[n] (K_v factor).

"Diagnostics" operating area → Menu forward key → "Axis diagnostics" → "Service axis"

- Check optimization of the speed controller
- Check smooth running of the axes
- Check machine data for traversing motions
(feed override, acceleration, max. velocities, ...)
- For operation with feedforward control:
MD32810 \$MA_EQUIV_SPEEDCTRL_TIME (equivalent time constant of speed control loop for feedforward control) or if the machine data is imprecisely set, the MD36400 \$MA_CONTOUR_TOL must be enlarged.

Encoder limit frequency monitoring

Monitoring of the limit frequency of the encoder of a machine axis.

- MD36300 \$MA_ENC_FREQ_LIMIT (encoder limit frequency)

Error response

- Alarm: "21610 Encoder frequency exceeded"
- IS: DB31, ... DBX60.2 "Encoder limit frequency exceeded 1"
- IS: DB31, ... DBX60.3 "Encoder limit frequency exceeded 2"

and stopping the machine axis using a speed-setpoint ramp whose characteristic is set in

- MD36610 \$MA_AX_EMERGENCY_STOP_TIME (braking ramp time when errors occur)

Error correction

After the axes have come to a stop, the position control is resumed after the alarm (RESET at the machine control panel) is acknowledged.

Note

The relevant axis must be re-referenced.

Encoder zero-mark monitoring

The zero-mark monitoring of the encoder of a machine axis checks whether pulses were lost between two zero mark passes.

- MD36310 \$MA_ENC_ZERO_MONITORING (zero-mark monitoring)

is used to enter the number of detected zero-mark errors at which the monitoring is to respond.

Special feature: A value of 100 will additionally disable the hardware monitoring of the encoder.

Error response

- Alarm: "25020 Zero-mark monitoring"

and stopping the machine axes using a speed setpoint ramp whose characteristic is set in

- MD36610 \$MA_AX_EMERGENCY_STOP_TIME (braking ramp time when errors occur) is set

Error causes

- MD36300 \$MA_ENC_FREQ_LIMIT [n] (encoder limit frequency) set too high
- Encoder cable damaged
- Encoder or encoder electronics defective

Position tolerance when switching over the encoder

It is possible to switch between the two encoders or position measuring systems of a machine axis at any time. The permissible position difference between the two position measuring systems when switching over is monitored.

- MD36500 \$MA_ENC_CHANGE_TOL (max. tolerance on actual position value switchover)

Error response

- Alarm: "25100 Measuring system cannot be switched over"

The requested switchover to another encoder is not carried out.

Error causes

- The specified permissible tolerance is too small.
- The position measuring system to which you want to switch over to is not referenced.

Cyclical monitoring of the encoder position tolerance

The position difference between the two encoders or position measuring systems of a machine axis is monitored with:

- MD36510 \$MA_ENC_DIFF_TOL (measuring system synchronism tolerance)

Error response

- Alarm: "25105 Measuring systems are not synchronous"

and stopping the machine axes using a speed setpoint ramp whose characteristic is set in the following machine data:

- MD36610 \$MA_AX_EMERGENCY_STOP_TIME (braking ramp time when errors occur)

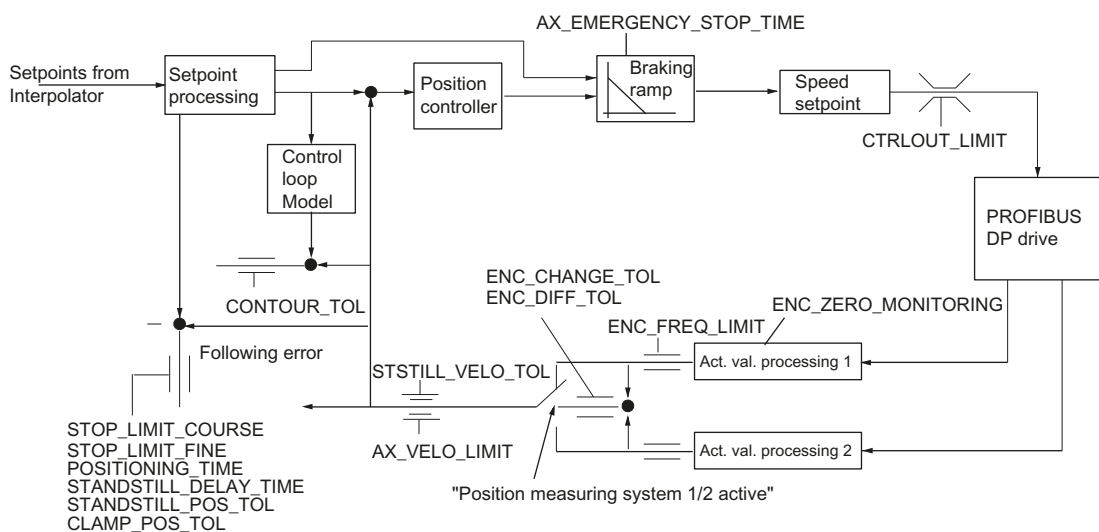


Figure 7-14 Monitoring for SINUMERIK 840D sl:

Note

Braking ramp

MD36620 \$MA_SERVO_DISABLE_DELAY_TIME (switch-off delay controller enable) must always be selected greater than MD36610 \$MA_AX_EMERGENCY_STOP_TIME (duration of the braking ramp for error states).

If this is not the case, the braking ramp cannot be kept.

References

Function Manual Basic Functions; Axis monitoring: Protection zones (A3)

7.4 Axis homing

Referencing

When referencing a machine axis, the actual position value system of the machine axis is synchronized with the machine geometry. Depending on the encoder type used, the machine axis is referenced with or without traversing movements.

Reference point approach

For all machine axes which are not equipped with an encoder providing an absolute actual position value, referencing is carried out by traversing the machine axis to a reference point; this is called the reference point approach.

The reference point approach can be carried out either manually in JOG mode, submode REF, or using a parts program.

With the operating mode JOG and submode REF, reference point approach is started using traverse direction keys PLUS or MINUS (depending on the parameterized reference point approach direction).

7.4.1 Incremental measuring system

Incremental measuring systems

With incremental measuring systems, referencing is carried out using a reference point approach divided into three phases:

1. Traversing to the reference cam
2. Synchronizing to the encoder zero mark
3. Approach reference point

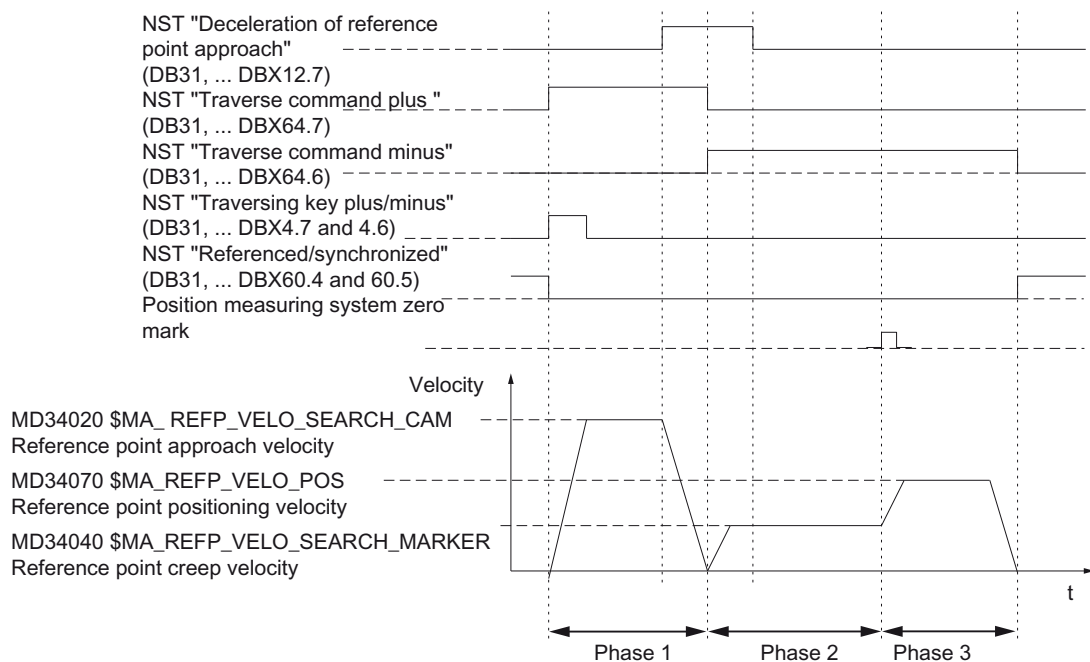


Figure 7-15 Signal chart: Referencing with an incremental measuring system (principle)

Phase-independent data

The following **machine data** and **interface signals** are relevant in each of the individual phases of the reference point approach:

- MD11300 \$MN_JOG_INC_MODE_LEVELTRIGGRD (INC/REF in jog mode)
- MD34000 \$MA_REFP_CAM_IS_ACTIVE (axis with reference cam)
- MD34110 \$MA_REFP_CYCLE_NR (axis sequence for channel-specific reference point approach)
- MD30240 \$MA_ENC_TYPE (encoder type)
- MD34200 \$MA_ENC_REFP_MODE (referencing mode)
- IS: DB21, ... DBX1.0 ("Activate referencing")
- IS: DB21, ... DBX33.0 ("Referencing active")

Phase 1: Traversing to the reference cam

The following **machine data** and **interface signals** are relevant:

- MD34010 \$MA_REFP_CAM_DIR_IS_MINUS (approach reference cam in minus direction)
- MD34020 \$MA_REFP_VELO_SEARCH_CAM (reference cam approach velocity)
- MD34030 \$MA_REFP_MAX_CAM_DIST (maximum distance to the reference cam)
- MD34092 \$MA_REFP_CAM_SHIFT (electr. cam offset, incremental measuring systems with equidistant zero marks)

- IS: DB21, ... DBX36.2 ("All axes with obligatory reference point are referenced")
- IS: DB31, ... DBX4.7/DBX4.6 ("Traversing keys plus/minus")
- IS: DB31, ... DBX12.7 ("Reference point approach delay")
- IS: DB31, ... DBX60.4, DBX60.5 ("Referenced/synchronized 1, 2")

Properties of phase 1:

- The feed override (feedrate switch) is active.
- The feed stop (channel-specific and axis-specific) is active.
- The machine axis can be stopped and restarted with NC-stop/NC-start.
- The machine axis traverses a distance specified in the following machine data from the starting position in the direction of the reference cam, without reaching the reference cam.
 - MD34030 \$MA_REFP_MAX_CAM_DIST (max. distance to reference cam)
- The following interface signal is set to "0". The axis stops, and alarm 20000 "Reference cam not reached" is output.
 - IS: DB31, ... DBX12.7 ("Reference point approach delay") = 0



WARNING

Setting the reference cam

If the reference cam is not calibrated exactly, it is possible that a wrong zero mark is evaluated after the reference cam has been left. As a result, the control system will take a wrong machine zero.

Software limit switches, protection areas and work area limits will thus also be active for the wrong positions. The difference is equivalent to one measuring system revolution in each case.

Danger for man and machine exists.

Phase 2: Synchronizing to the encoder zero mark

The following **machine data** and **interface signals** are relevant:

- MD34040 \$MA_REFP_VELO_SEARCH_MARKER (creep velocity)
- MD34050 \$MA_REFP_SEARCH_MARKER_REVERSE (direction reversal on reference cam)
- MD34060 \$MA_REFP_MAX_MARKER_DIST (maximum distance from cam to reference mark)

Properties of phase 2:

- Feed override (the feed override switch) is not active.
If a feed override of 0% is selected via the feed override switch, the traverse motion is stopped.
- Feed stop (channel-specific and axis-specific) is active.
On a feed stop, the traverse motion is stopped and the alarm displayed: 20005 "Reference point approach canceled"
- NC-Stop/NC-Start is inactive.
- With IS: DB31, ... DBX12.7 ("Reference point approach delay") = 0, the machine axis traverses a distance parameterized in the following machine data after leaving the reference cam:
MD34060 \$MA_REFP_MAX_MARKER_DIST (max. distance to the reference mark)
Without the zero mark being detected, the machine axis stops and the following alarm is displayed: 20002 "Zero mark missing"

Phase 3: Approach reference point

The following **machine data** and **interface signals** are relevant:

- MD34070 \$MA_REFP_VELO_POS (reference point positioning velocity)
- MD34080 \$MA_REFP_MOVE_DIST (reference point distance to zero mark)
- MD34090 \$MA_REFP_MOVE_DIST_CORR (reference point offset, additive)
- MD34100 \$MA_REFP_SET_POS (reference point value)
- IS: DB31, ... DBX2.4, 2.5, 2.6, 2.7 ("Reference point value 1...4")
- IS: DB31, ... DBX60.4, DBX60.5 ("Referenced/synchronized 1, 2")

Properties of phase 3:

- Feed override (the feed override switch) is active.
- Feed stop (channel-specific and axis-specific) is active.
- NC-Stop/NC-Start is active.

References

Basic Functions Function Manual; Reference Point Travel (R1)

7.4.2 Distancecoded reference marks

Distancecoded reference marks

When distance-coded reference marks are used, referencing is divided into two phases:

1. Synchronize by overriding two reference marks
2. Traverse to target point

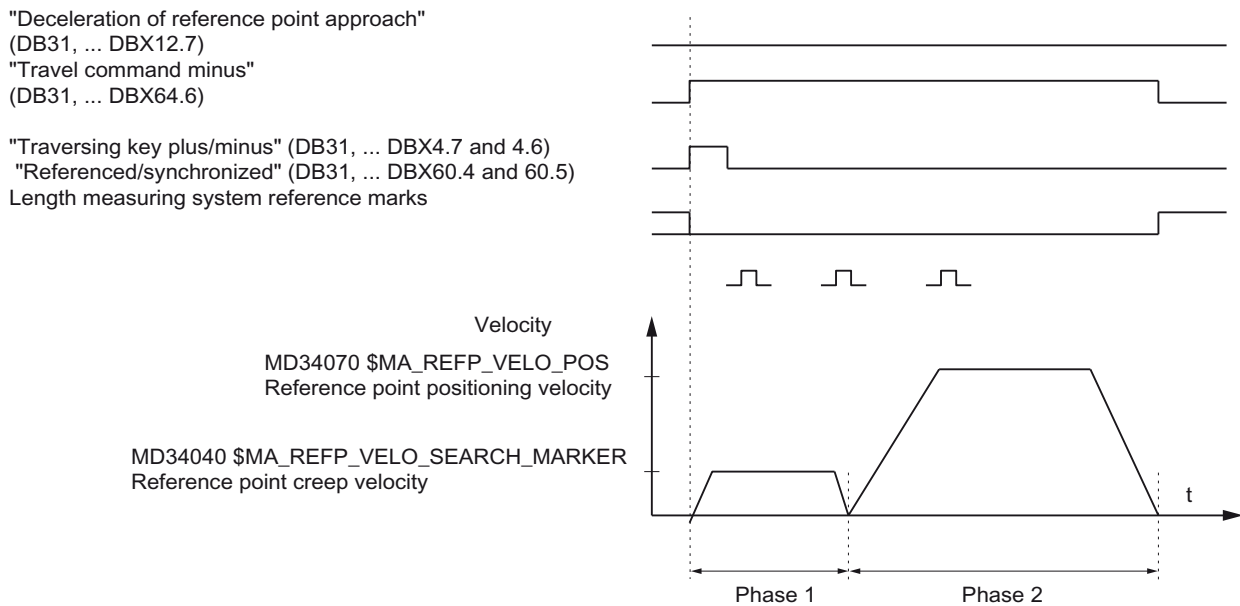


Figure 7-16 Signal chart: Distance-coded reference marks (principle)

Phase-independent data

The following **machine data** and **interface signals** are independent with respect to the individual phases of reference point approach:

- MD11300 \$MN_JOG_INC_MODE_LEVELTRIGGRD (INC/REF in jog mode)
- MD34000 \$MA_REFP_CAM_IS_ACTIVE (axis with reference cam)
- MD34110 \$MA_REFP_CYCLE_NR (axis sequence for channel-specific reference point approach)
- MD30240 \$MA_ENC_TYPE (encoder type)
- MD34200 \$MA_ENC_REFP_MODE (referencing mode)
- MD34310 \$MA_ENC_MARKER_INC (interval between two reference marks)
- MD34320 \$MA_ENC_INVERS (inverse measuring system)
- IS: DB21, ... DBX1.0 ("Activate referencing")
- IS: DB21, ... DBX33.0 ("Referencing active")

Phase 1: Synchronize by overriding two reference marks

The following **machine data** and **interface signals** are relevant:

- MD34010 \$MA REFP_CAM_DIR_IS_MINUS (approach reference cam in negative direction)
- MD34040 \$MA REFP_VELO_SEARCH_MARKER (referencing velocity)
- MD34060 \$MA REFP_MAX_MARKER_DIST (maximum distance between two reference marks)
- MD34300 \$MA ENC_REFP_MARKER_DIST (reference mark distance)
- IS: DB21 .. 30, DBX36.2 ("All axes to be referenced are referenced")
- IS: DB31, ... DBX4.7/DBX4.6 ("Traversing keys plus/minus")
- IS: DB31, ... DBX12.7 ("Reference point approach delay")
- IS: DB31, ... DBX60.4, DBX60.5 ("Referenced/synchronized 1, 2")

Properties of phase 1:

- If the machine axis travels from the initial position a distance defined in MD34300 \$MA REFP_MARKER_DIST (max. distance to the reference mark) without two reference marks being overridden, then the machine axis stops and the system issues alarm 20004 "Reference mark missing".

Phase 2: Traversing to the target point

The following **machine data** and **interface signals** are relevant:

- MD34070 \$MA REFP_VELO_POS (target point positioning velocity)
- MD34090 \$MA REFP_MOVE_DIST_CORR (absolute offset)
- MD34100 \$MA REFP_SET_POS (target point)
- MD34330 \$MA REFP_STOP_AT_ABS_MARKER (with/without target point)
- IS: DB31, ... DBX60.4, DBX60.5 ("Referenced/synchronized 1, 2")

Properties of phase 2:

- The feed override (feedrate switch) is active.
- The feed stop (channel-specific and axis-specific) is active.
- The machine axis can be stopped and restarted with NC-stop/NC-start.

Determining the absolute offset

To determine the absolute offset between the measuring system zero point and the machine zero, the following procedure is recommended:

1. Determine the actual position of the measuring system

After two reference marks following one after the other (synchronized) have been overtraveled, the actual position of the length measuring system can be read on the user interface at "Actual position".

The absolute offset must be zero at this time:

- MD34090 \$MA REFP_MOVE_DIST_CORR = 0

1. Determine the absolute machine actual position

Determining the absolute machine actual position, e.g. can be performed by traversing the machine axis to a known position (fixed stop). Alternatively, it can be measured at any position (laser interferometer).

2. Calculate the absolute offset

Linear measurement system non-inverse to machine system:

Absolute offset = actual machine position + actual position of the measuring system

Linear measuring system inverse to machine system:

Absolute offset = actual machine position - actual position of the measuring system

- MD34090 \$MA REFP_MOVE_DIST_CORR (reference point / absolute offset)

 WARNING
--

Machine measurement

The position measuring system must be re-referenced after the absolute offset has been determined and entered in the following machine data:
--

- | |
|--|
| <ul style="list-style-type: none"> • MD34090 \$MA REFP_MOVE_DIST_CORR (absolute offset) |
|--|

References

Basic Functions Function Manual; Reference Point Travel (R1)

7.4.3 Absolute encoder homing**Machine axes with absolute encoders**

The advantage of machine axes with absolute encoders is that after a one-time adjustment process, the reference point approach necessary for incremental measuring systems (e.g. run-up of control, de-selection of "parking" of machine axes etc.) can be skipped and the actual value system of the machine axis can be immediately synchronized with the determined absolute position.

Adjustment of absolute encoders

To adjust an absolute encoder, the actual value of the encoder is harmonized with the machine zero point once and then enabled.

The current status of an absolute encoder is displayed in the following axis-specific machine data of the machine axis to which it is connected:

MD34210 \$MA_ENC_REFP_STATE (status of absolute encoder)

Value	Meaning
0	Encoder not adjusted
1	Encoder adjustment released
2	Encoder is adjusted

Adjustment types

The following adjustment types are supported:

- Adjustment by entering the reference point offset
- Adjustment by entering the reference point value
- Automatic adjustment by means of a probe
- Adjustment with BERO

Readjustment

Readjustment of the absolute encoder is required after:

- Gear change between load and absolute encoder
- Removal/installation of the absolute encoder
- Removal/installation of the motor with the absolute encoder
- Data loss in the static NC memory
- Battery failure
- Setting actual value (`PRESETON`)

It is only during the following events that the controller can detect that a readjustment of the absolute encoder is required:

- Gear change with change of transformation ratio
- Response of the zero mark monitoring
- New encoder serial number after change of the absolute encoder

The controller then sets the status of the absolute encoder to "0":

- MD34210 \$MA_ENC_REFP_STATE = 0 (encoder not adjusted)

The following alarm is displayed:

Alarm 25022 "Axis <axis identifier> encoder <number> warning 0"

When the zero mark monitoring responds, the following alarm is also displayed:

Alarm 25020 "Axis <axis identifier> zero mark monitoring of the active encoders"

NOTICE

Adjustment mandatory

In all other cases (e.g. `PRESETON`), it is the sole responsibility of the user to carry out a readjustment by **manually** setting MD34210 to the value "0".

WARNING

Data backup

During the backup of machine data of a machine A, the encoder status (MD34210) of the machine axes is also backed up. When this data record is loaded into a machine B of the same type, e.g. in the context of series-start-up or after a service case, the relevant machine axes will be automatically regarded as adjusted/referenced by the NCK.

The machine manufacturer/user is specifically responsible for undertaking a readjustment in such cases.

See also: MD30250 \$MA_ACT_POS_ABS (Absolute encoder position at the time of switch-off)

References

Basic Functions Function Manual; Reference Point Travel (R1)

7.5 Parameterization of spindle data

7.5.1 Setpoint/actual value channels of spindle

Parameterization of the setpoint/actual value channels of a spindle is identical to parameterization of the setpoint and actual value channels of an axis. For this, see Section "Setpoint / actual value channels" (Page 174).

7.5.2 Gear stages

Enable

The gear stage change is generally carried out in the following machine data:

- MD35010 \$MA_GEAR_STEP_CHANGE_ENABLE (gear stage change possible, spindle has several gear stages)

If this machine data is not set, the system assumes that the spindle has no gear stages.

Multiple gearbox steps

If more than one gearbox step exists, the number of gearbox steps is entered into MD35090 \$MA_NUM_GEAR_STEPS.

Parameter sets

In **spindle mode** of a spindle, the NC will select the parameter set that suits the current gear stage best.

Gear stage $x \Rightarrow$ parameter set $(x+1) \Rightarrow$ index $[x]$

In **axis mode** of a spindle, the NC always selects the 1st parameter set (index $[0]$), independent of the current gear stage

The machine data listed in the following are gear stage-dependent machine data of a spindle:

- MD35110 \$MA_GEAR_STEP_MAX_VELO[n] (n_{\max} for gear stage change)
- MD35120 \$MA_GEAR_STEP_MIN_VELO[n] (n_{\min} for gear stage change)
- MD35130 \$MA_GEAR_STEP_MAX_VELO_LIMIT[n] (n_{\max} for gear stage)
- MD35135 \$MA_GEAR_STEP_PC_MAX_VELO_LIMIT (n_{\max} for gearbox step with position-control)
- MD35140 \$MA_GEAR_STEP_MIN_VELO_LIMIT[n] (n_{\min} for gear stage)

- MD35200 \$MA_GEAR_STEP_SPEEDCTRL_ACCEL[n] (acceleration in speed-control mode)
- MD35210 \$MA_GEAR_STEP_POSCTRL_ACCEL[n] (acceleration in position control mode)

For further information on parameter sets, see Section "Axis/spindle parameter sets" (Page 167).

Literature

Function Manual Basic Functions; Spindles: Gear stage change (S1)

7.5.3 Spindle measuring systems

Encoder matching

When parameterizing the measuring systems of spindles, the same conditions apply as for parameterization of the measuring systems of rotary axes. This multiple is 2048.

For incremental measuring systems see Section "Parameterization of incremental measuring systems" (Page 171).

For absolute measuring systems see Section "Parameterization of absolute measuring systems" (Page 172).

Note

If the motor encoder is used for actual-value sensing, the encoder matching must be entered in the machine data for each individual gear stage if there are several gear stages.

Pulse multiplication

The maximum multiplication of the appropriate drive is always used as the multiplication of the increments.

Examples of encoder adaptation

Example A: encoder on the spindle

Suppose the following conditions are provided:

- The incremental encoder is mounted on the spindle.
- Encoder pulses = 500 [pulses/rev.]
- Pulse multiplication = 128
- Internal precision = 1000 [increment/degree]

- Sensor ratio = 1:1
- Load ratio = 1:1

The machine data are set acc. to the values above:

- MD10210 \$MN_INT_INC_PER_DEG (computational resolution) = 1,000 [incr./degree]
- MD31020 \$MA_ENC_RESOL (encoder resolution) = 500 [pulses/revolution]
- MD31050 \$MA_DRIVE_AX_RATIO_DENOM (load rev. denominator) = 1
- MD31060 \$MA_DRIVE_AX_RATIO_NUMERA (load rev. numerator) = 1
- MD31070 \$MA_DRIVE_ENC_RATIO_DENOM (sensor speed denominator) = 1
- MD31080 \$MA_DRIVE_ENC_RATIO_NUMERA (sensor speed numerator) = 1

$$\text{Internal Resolution} = \frac{360 \text{ degree}}{\text{MD31020} * \text{pulse rev.}} * \frac{\text{MD31080}}{\text{MD31070}} * \frac{\text{MD31050}}{\text{MD31060}} * \text{MD10210}$$

$$\text{Internal Resolution} = \frac{360}{500 * 128} * \frac{1}{1} * \frac{1}{1} * 1000 = 5,625 \frac{\text{int. increments}}{\text{encoder pulse}}$$

One encoder increment corresponds to 5.625 internal increments.

One encoder increment corresponds to 0.005625 degrees (highest possible positioning resolution).

Example B: encoder at motor

Suppose the following conditions are provided:

- The incremental encoder is mounted on the motor.
- Encoder pulses = 2048 [pulses/rev.]
- Pulse multiplication = 128
- Internal precision = 1000 [increment/degree]
- Sensor ratio = 1:1
- Load ratio 1= 2.5:1 [motor speed/spindle speed]
- Load ratio 2= 1:1 [motor speed/spindle speed]

Gear stage 1

$$\text{Internal Resolution} = \frac{360 \text{ degree}}{\text{MD31020} * \text{pulse rev.}} * \frac{\text{MD31080}}{\text{MD31070}} * \frac{\text{MD31050}}{\text{MD31060}} * \text{MD10210}$$

$$\text{Internal Resolution} = \frac{360}{2048 * 128} * \frac{1}{1} * \frac{1}{2,5} * 1000 = 0,54932 \frac{\text{int. increments}}{\text{encoder pulse}}$$

One encoder increment corresponds to 0.54932 internal increments.

One encoder increment corresponds to 0.00054932 degrees (highest possible positioning resolution).

Gear stage 2

$$\text{Internal Resolution} = \frac{360}{2048 * 128} * \frac{1}{1} * \frac{1}{1} * 1000 = 1,3733 \frac{\text{int. increments}}{\text{encoder pulse}}$$

One encoder increment corresponds to 1.3733 internal increments.

One encoder increment corresponds to 0.0013733 degrees (highest possible positioning resolution).

7.5.4 Speeds and setpoint adjustment for spindle

Speeds, gear stages

Data for five gear stages is implemented for SINUMERIK 840D sl. These stages are defined by a minimum and maximum speed for the stage itself and by a minimum and maximum speed for the automatic gear stage change.

A new set gear stage is output only if the new programmed speed cannot be traversed in the current gear stage. For the sake of simplification, the oscillation times for gear stage changes can be specified directly in the NC; the oscillation function must otherwise be implemented in the PLC. The oscillation function is initiated via the PLC.

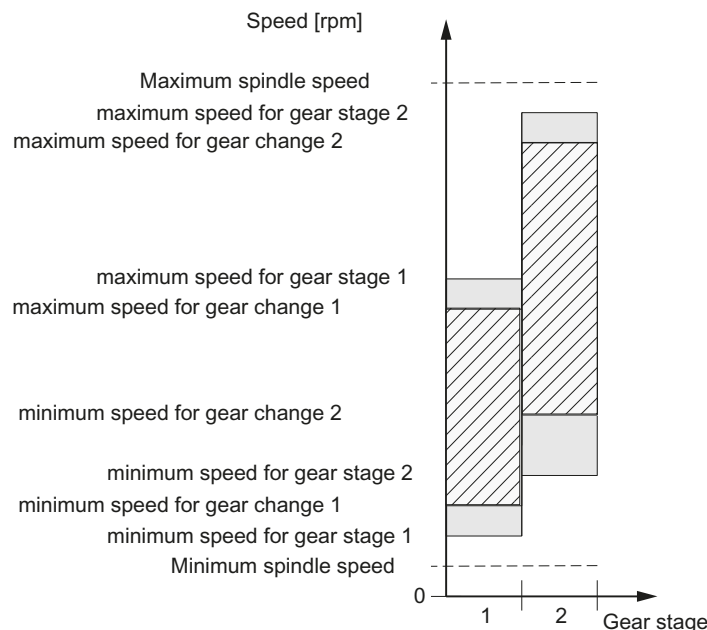


Figure 7-17 Example for speed ranges for automatic gear stage selection (M40)

Speeds for conventional operation

The speeds of the spindle for conventional mode are entered in the following machine data:

- MD32010 \$MA_JOG_VELO_RAPID (rapid traverse in jog mode)
- MD32020 \$MA_JOG_VELO (axis velocity in JOG mode)

The direction of rotation is specified via the appropriate directional keys for the spindle on the machine control panel.

Direction of rotation

The direction of rotation of a spindle corresponds to the traversing direction of an axis.

Setpoint matching

The speeds must be transferred with standardized values for the drive controller. The values are scaled in the NC using the selected load gear and the appropriate drive parameter.

Machine data

MD	Identifier	Meaning
31050	\$MA_DRIVE_AX_RATIO_DENOM	Denominator load gearbox
31060	\$MA_DRIVE_AX_RATIO_NUMERA	Numerator load gearbox
32010	\$MA_JOG_VELO_RAPID	Rapid traverse in jog mode
32020	\$MA_JOG_VELO	JOG axis velocity
35010	\$MA_GEAR_STEP_CHANGE_ENABLE	Gear stage change possible
35020	\$MA_SPIND_DEFAULT_MODE	Basic spindle setting
35030	\$MA_SPIND_DEFAULT_ACT_MASK	Activate initial spindle setting
35040	\$MA_SPIND_ACTIVE_AFTER_RESET	Spindle active after reset
35200	\$MA_GEAR_STEP_SPEEDCTRL_ACCEL[n]	Acceleration in speed control mode
35220	\$MA_ACCEL_REDUCTION_SPEED_POINT	Speed limit for reduced acceleration
35230	\$MA_ACCEL_REDUCTION_FACTOR	Reduced acceleration
35400	\$MA_SPIND_OSCILL_DES_VELO	Oscillation speed
35410	\$MA_SPIND_OSCILL_ACCEL	Oscillation acceleration
35430	\$MA_SPIND_OSCILL_START_DIR	Oscillation start direction
35440	\$MA_SPIND_OSCILL_TIME_CW	Oscillation time for M3 direction
35450	\$MA_SPIND_OSCILL_TIME_CCW	Oscillation time for M4 direction

7.5.5 Position spindle

Functionality

The NC provides an oriented spindle stop function with which the spindle can be moved into a certain position and held there (e.g. for tool changing purposes). Several programming commands are available for this function which define the approach and program processing.

- To absolute position (0-360 degrees)
- Incremental position (+/- 999999.99 degrees)
- Positioning without influence of block change (SPOSA)
- Block change when block end position is reached (calculated by interpolation)

The controller brakes the spindle down to position-control speed at the acceleration rate for speed operation.

If the position-control speed has been reached, the controller branches into position-control mode and the acceleration rate for position-control mode and the K_v factor become active.

The interface signal "Exact stop fine" is output to indicate that the programmed position has been reached (block change when position reached).

Acceleration rate for position-control mode must be set such that the current limit is not reached. Acceleration rate must be entered separately for each gear step.

If the spindle is positioned from zero speed, it is accelerated up to a maximum speed corresponding to position-control speed; the direction is defined via machine data. If no reference is present, the direction of motion is specified as in MD35350 \$MA_SPIND_POSITIONING_DIR. The contour monitoring function is activated as soon as the control mode switches to position control.

Machine data

MD	Identifier	Meaning
35300	\$MA_SPIND_POSCTRL_VELO	Position-control activation speed
35350	\$MA_SPIND_POSITIONING_DIR	Direction of rotation when positioning from standstill
35210	\$MA_GEAR_STEP_POSCTRL_ACCEL	Acceleration in position-control mode
36000	\$MA_STOP_LIMIT_COARSE	Exact stop coarse
36010	\$MA_STOP_LIMIT_FINE	Exact stop fine
32200	\$MA_POSCTRL_GAIN	K_v factor
36400	\$MA_CONTOUR_TOL	Contour monitoring

Literature

Function Manual, Basic Functions; Spindles (S1)

7.5.6 Synchronizing spindle

Overview

To allow the spindle to be positioned from the NCK, its position has to be adjusted using the measuring system. This operation is called "synchronization". As a rule, synchronizing is done to the zero mark of the connected encoder or to a reference cam as zero mark substitute.

The following machine data defines the actual position of the spindle at the zero-mark position:

- MD34100 \$MA_REFP_SET_POS (reference point value)

The zero-mark offset is entered in the following machine data:

- MD34090 \$MA_REFP_MOVE_DIST_CORR (reference point offset)

The following machine data specifies which signal is used for synchronization:

- MD34200 \$MA_ENC_REFP_MODE (referencing mode)
 - 1 = Encoder zero mark
 - 2 = Bero

When is synchronization necessary?

The spindle will be synchronized:

- After the NC has powered up when the spindle is moved using a programming command
- After a request for resynchronization by the PLC
 - NST DB31,... DBX16.4 (resynchronize spindle 1)
 - NST DB31,... DBX16.5 (resynchronize spindle 2)
- After each gear stage change for an indirect measuring system
 - MD31040 \$MA_ENC_IS_DIRECT (direct measuring system) = 0
- When the encoder limit frequency falls below the programmed value after a speed has been programmed which is above the encoder limit frequency.

NOTICE
Synchronization via BERO signal <p>If the spindle encoder is not mounted directly on the spindle and there are gear ratios between the encoder and spindle (e.g. encoder mounted on motor), then a BERO signal connected to the drive (SERVO) must be used for synchronization. The control system then automatically resynchronizes the spindle after each gear stage change. The user does not have to contribute anything here.</p> <p>In general, backlash, gearbox elasticity and the BERO hysteresis reduce the accuracy achievable during synchronization.</p>

Machine data

MD	Identifier	Meaning
34100	\$MA_REFP_SET_POS	Reference point value
34090	\$MA_REFP_MOVE_DIST_CORR	Reference point offset
34200	\$MA_REFP_MODE	Referencing mode

7.5.7 Spindle monitoring

Spindle stationary

The maximum permissible spindle speed up to which spindle standstill is detected, is set using machine data:

- MD36060 \$MA_STANDSTILL_VELO_TOL (max. speed "Spindle stationary")

If the actual speed falls below this speed limit, the NC/PLC interface signal is set:

- DB31,... DBX61.4 = 1 (spindle stationary)

Enabling path feed

Precondition:

- The spindle is in the open-loop control mode
- MD35510 \$MA_SPIND_STOPPED_AT_IPO_START == TRUE (feed enable for "Spindle stationary")

The path feed is enabled when both conditions are fulfilled:

- (actual speed of the spindle) < (MD36060 \$MA_STANDSTILL_VELO_TOL)
- DB31,... DBX61.4 == 1 (spindle stationary)

Spindle in setpoint range

If the spindle reaches the tolerance range specified in the following machine data, then the interface signal IS DB31,... DBX83.5 (spindle in setpoint range) is set:

- MD35150 \$MA_SPIND_DES_VELO_TOL (spindle speed tolerance)

The path feedrate is then released in the following set machine data:

- MD35510 \$MA_SPIND_STOPPED_AT_IPO_START (feed enable for "Spindle stopped")

Maximum spindle speed

The maximum spindle speed can be set using the following system data:

- Machine-dependent maximum speed via machine data
MD35100 \$MA_SPIND_VELO_LIMIT (max. spindle speed)
- Process-dependent maximum speed via immediately effective setting data
SD43235 \$SA_SPIND_USER_VELO_LIMIT (max. spindle speed)

The NC limits the spindle speed to the lower of the two values.

Error response:

If the speed is nevertheless exceeded by the speed tolerance (drive error), the following signal is output:

- DB31,... DBX83.0 = 1 (speed limit exceeded)
- Alarm "22150 Maximum number of chucks exceeded"

The following machine data also limits the speed of the spindle:

- MD36200 \$MA_AX_VELO_LIMIT (velocity-monitoring threshold)

When the speed is exceeded, an alarm is generated.

In position-control mode (e.g. SPCON), the NC limits the specified maximum speed specified in the machine or setting data to 90% of the maximum value (control reserve).

Gear stage speed min./max.

The default of a max./min. gear stage speed is entered in the following machine data:

- MD35130 \$MA_GEAR_STEP_MAX_VELO_LIMIT (maximum speed for gear stage)
- MD35140 \$MA_GEAR_STEP_MIN_VELO_LIMIT (minimum speed for gear stage)

The speed cannot leave this range when the appropriate gear stage is engaged.

Programmed spindle speed limitations

The following functions can be used to specify a spindle speed limitation in an indexing program:

- G25 S... (min. spindle speed)
- G26 S... (max. spindle speed)

The limitation is active in all operating modes.

The function LIMS=... can be used to specify a spindle speed limit for G96 (constant cutting rate):

- LIMS=... (speed limitation (G96))

This limitation is only effective when G96 is active.

Encoder frequency limit

If the encoder frequency limit in the following machine data is exceeded, synchronization of the spindle is lost and spindle functionality is reduced (thread, G95, G96):

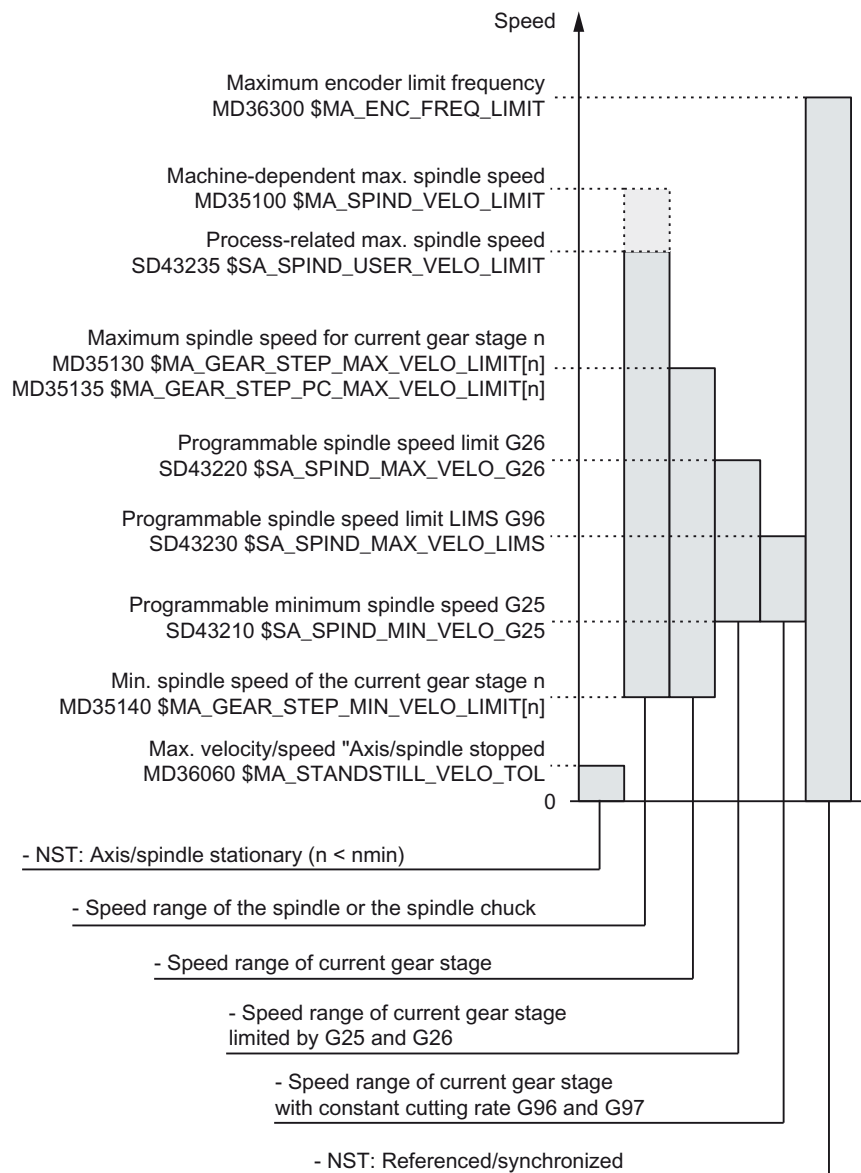
- MD36300 \$MA_ENC_FREQ_LIMIT (encoder frequency limit)

The spindle will be re-synchronized automatically once the encoder frequency falls below the value defined in the following machine data:

- MD36302 \$MA_ENC_FREQ_LIMIT_LOW (encoder frequency limit at which the encoder is turned on again)

The encoder frequency limit value must be such that the mechanical encoder speed limit is not exceeded or else the synchronization from high speeds will be incorrect.

Overview of the speed limit values



Literature

Function Manual Basic Functions; Spindles: Spindle monitoring (S1)

7.6 System data

7.6.1 Resolutions

Overview

The following types of resolution, e.g. resolution of linear and angular positions, velocities, accelerations and jerk, must be differentiated as follows:

- The **input resolution**, i.e. the input of data from the user interface or using the part programs.
- The **display resolution**, i.e. the display of data on the user interface.
- The **computational resolution**, i.e. the internal representation of the data input through the user interface or the part program.

Input and display resolution

The input and display resolution is specified via the control panel, whereby the display resolution of position values can be changed with MD9004 \$MM_DISPLAY_RESOLUTION (display resolution).

MD9011 \$MM_DISPLAY_RESOLUTION_INCH (INCH measuring system display resolution) can be used to configure the display resolution for position values with inch setting. This allows you to display up to six decimal places with the inch setting.

For the programming of part programs, the input resolutions listed in the Programming Guide apply.

Computational resolution

The computational resolution defines the maximum number of effective decimal places for all data the physical unit of which is referred to a length or an angle, e.g. position values, velocities, tool offsets, zero offsets, etc.

The desired computational resolution is defined using the machine data

- MD10200 \$MN_INT_INCR_PER_MM (computational resolution for linear positions)
- MD10210 \$MA_INT_INCR_PER_DEG (computational resolution for angular positions).

The default assignment is:

- 1000 increments/mm
- 1000 increments/degrees

The computational resolution thus also determines the maximum achievable precision for positions and selected offsets. However, it is essential that the measuring system is adapted to this degree of precision.

Note

Although the computational resolution is generally independent of the input/display resolution, it should have at least the same resolution.

Rounding

The precision of angle and linear positions is limited to the computational resolution by rounding the product of the programmed value with the computational resolution to an integer number.

Example of rounding:

Computational resolution: 1000 increments/mm
Programmed path: 97.3786 mm
Effective value = 97.379 mm

Note

To keep rounding easily understandable, it is better to use powers of 10 for the computational resolution (100, 1000, 10,000).

Display resolution

In MD9004 \$MM_DISPLAY_RESOLUTION (display resolution), you can set the number of decimal places after the decimal point for the position values on the operator panel.

Input and display limit values

Limitation of the input values depends on the display features and on the input options on the operator panel. The limit is ten digits plus comma and sign.

Example of programming in the $1/10$ - μm range:

All the linear axes of a machine are to be programmed and traversed within the range of values 0.1 to 1000 mm.

In order to position accurately to 0.1 μm , the computational resolution must be set to $\geq 10^4$ incr./mm.

MD10200 \$MN_INT_INCR_PER_MM = 10000 [incr./mm]:

Example of related part program:

```
N20 G0 X 1.0000 Y 1.0000
;Axes move to position X=1.0000 mm, Y=1.0000 mm

N25 G0 X 5.0002 Y 2.0003
;Axes move to position X=5.0002 mm, Y=2.0003 mm
```

Machine data

MD	Identifier	Comment
9004	\$MM_DISPLAY_RESOLUTION	Display resolution
9011	\$MM_DISPLAY_RESOLUTION_INCH	Display resolution for INCH system of measurement
10200	\$MN_INT_INCR_PER_MM	Computational resolution for linear positions
10210	\$MN_INT_INCR_PER_DEG	Computational resolution for angular positions

Literature

Function Manual, Basic Functions; Velocities, Setpoint-Actual Value Systems, Closed-Loop Control (G2)

7.6.2 Normalization of phys. units of machine data and setting data

Scaling of physical quantities

Machine and setting data that have a physical unit are interpreted in the input/output units listed in the table "Scaling physical units of machine and setting data" by default, depending on the scaling system (metric/inch).

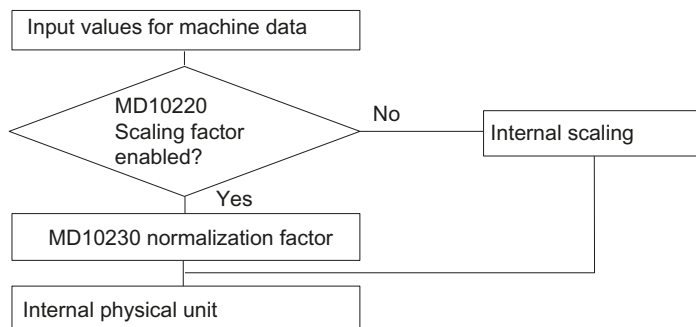
The internally used units which the NC uses are independent and fixed.

Physical unit	Input/output units for the basic system		Internally used unit
	Metric	Inch	
Linear position	1 mm	1 inch	1 mm
Angular position	1 degree	1 degree	1 degree
Linear velocity	1 mm/min	1 inch/min	1 mm/s
Angular velocity	1 rpm	1 rpm	1 deg./s
Linear acceleration	1 m/s ²	1 inch/s ²	1 mm/s ²
Angular acceleration	1 rev/s ²	1 rev/s ²	1 degree/s ²
Linear jerk	1 m/s ³	1 inch/s ³	1 mm/s ³
Angular jerk	1 rev/s ³	1 rev/s ³	1 degree/s ³
Time	1 sec	1 sec	1 sec
Position controller servo gain	1 s ⁻¹	1 s ⁻¹	1 s ⁻¹
Rev. feedrate	1 mm/rev	1 inch/rev	1 mm/degree
Compensation value linear position	1 mm	1 inch	1 mm
Compensation value angular position	1 degree	1 degree	1 degree

User-defined

The user can define different input/output units for machine and setting data. This also requires an adjustment between the newly selected input/output units and the internal units via the following machine data:

- MD10220 \$MN_SCALING_USER_DEF_MASK (Activation of the scaling factors) and
- MD10230 \$MN_SCALING_FACTORS_USER_DEF[n] (Scaling factors of the physical quantities)



The following applies:

Input/output unit selected=

$\text{MD10230 } \$MN_SCALING_FACTORS_USER_DEF[n] * \text{internal unit}$

The selected input/output unit, expressed in the internal units 1 mm, 1 degree and 1 s must therefore be entered in MD10230 \$MN_SCALING_FACTORS_USER_DEF[n].

Table 7- 1 Bit number and index for user definition

Physical unit	MD10220 Bit number	MD10230 Index n
Linear position	0	0
Angular position	1	1
Linear velocity	2	2
Angular velocity	3	3
Linear acceleration	4	4
Angular acceleration	5	5
Linear jerk	6	6
Angular jerk	7	7
Time	8	8
K _v factor	9	9
Rev. feedrate	10	10
Compensation value linear position	11	11
Compensation value angular position	12	12

Example 1:

The data input/output of the linear velocities should be in m/min rather than mm/min (initial state). The internal unit is mm/s.

MD10220 \$MN_SCALING_USER_DEF_MASK Bit2 = 1 is used to enter the scaling factor for linear velocities as a user-defined value. The scaling factor is calculated using the following formula:

$$\text{MD10230 \$MN_SCALING_FACTORS_USER_DEF}[n] = \frac{\text{Selected input/output unit}}{\text{Internal unit}}$$

$$\text{MD10230 \$MN_SCALING_FACTORS_USER_DEF}[n] = \frac{1 \frac{\text{m}}{\text{min}}}{1 \frac{\text{mm}}{\text{s}}} = \frac{\frac{1000 \text{ mm}}{60 \text{ s}}}{1 \frac{\text{mm}}{\text{s}}} = \frac{1000}{60} = 16.667$$

→ MD10230 \$MN_SCALING_FACTORS_USER_DEF[2] = 16.667

Index 2 specifies the "linear velocity".

Example 2:

In addition to the change in example 1, the machine data input/output of linear accelerations is to be performed in ft/s², instead of m/s² (initial state) (the internal unit is mm/s²).

MD10220 \$MN_SCALING_USER_DEF_MASK = ,H14'; (bit no. 4 and bit no. 2) of Example 1 as hex value

$$\text{MD10230 \$MN_SCALING_FACTORS_USER_DEF}[n] = \frac{1 \frac{\text{ft}}{\text{s}^2}}{1 \frac{\text{mm}}{\text{s}^2}} = \frac{12 \cdot 25.4 \frac{\text{mm}}{\text{s}^2}}{1 \frac{\text{mm}}{\text{s}^2}} = \frac{1000}{60} = 304.8$$

→ MD10230 \$MN_SCALING_FACTORS_USER_DEF[4] = 304.8

Index 4 specifies the "linear acceleration".

Machine data

MD	Identifier	Comment
10220	\$MN_SCALING_USER_DEF_MASK	Activation of scaling factors
10230	\$MN_SCALING_FACTORS_USER_DEF[n]	Scaling factors of physical quantities
10240	\$MN_SCALING_SYSTEM_IS_METRIC	Basic system metric
10250	\$MN_SCALING_VALUE_INCH	Conversion factor for switchover to inch system
10260	\$MN_CONVERT_SCALING_SYSTEM	Basic system switchover active
10270	\$MN_POS_TAB_SCALING_SYSTEM	Measuring system of position tables
10290	\$MN_CC_TDA_PARAM_UNIT	Physical units of the tool data for CC
10292	\$MN_CC_TOA_PARAM_UNIT	Physical units of the tool edge data for CC

7.6.3 Modifying scaling machine data

The scaling of machine data having physical units is defined by the following machine data:

- MD10220 \$MN_SCALING_USER_DEF_MASK (activation of standardizing factors)
- MD10230 \$MN_SCALING_FACTORS_USER_DEF (standardizing factors of the physical quantities)
- MD10240 \$MN_SCALING_SYSTEM_IS_METRIC (basic system metric)
- MD10250 \$MN_SCALING_VALUE_INCH (conversion factor for switchover to INCH system)
- MD30300 \$MA_IS_ROT_AX (rotary axis)

When scaling machine data are modified, all machine data affected by this modification due to their physical unit are converted with the next NCK reset.

Example: Redefining an A1 axis from linear to rotary axis.

The control has been started up with default values. Axis A1 is declared as a linear axis.

- MD30300 \$MA_IS_ROT_AX[A1] = 0 (no rotary axis)
- MD32000 \$MA_MAX_AX_VELO [A1] = 1000 [mm/min] (max. axis velocity).

Axis A1 is now declared as a rotary axis containing the following machine data:

- MD30300 \$MA_IS_ROT_AX[A1] = 1 (rotary axis)
- MD32000 \$MA_MAX_AX_VELO [A1] = 1000 [mm/min] (max. axis velocity).

With the next NCK reset, the control system recognizes that axis A1 is defined as a rotary axis and standardizes MD32000 \$MA_MAX_AX_VELO to [rev./min] with reference to a rotary axis.

- MD30300 \$MA_IS_ROT_AX[A1] = 1 (rotary axis)
- MD32000 \$MA_MAX_AX_VELO [A1] = 2.778 [rev./min]

Note

If a scaling machine data item is altered, then the control outputs alarm "4070 Scaling data changed".

Modifying manually

The following procedure is recommended when modifying scaling machine data manually:

1. Set all scaling machine data
2. Carry out NCK reset
3. Set all dependent machine data after the NC has powered up.

7.6.4 Loading default machine data

Loading standard machine data

Using the input values listed below in MD11200 \$MN_INIT_MD (loading the standard machine data during the "next" NC boot), you can load various data storage areas with default values on the next NC boot. After setting the machine data, an NCK reset must be carried out:

1. NCK RESET: The machine data is activated.
2. NCK RESET: Depending on the input value, the corresponding machine data is set to its default values and the MD11200 \$MN_INIT_MD is reset to "0".

Input values:

- MD11200 \$MN_INIT_MD = 1

On the next NC boot, all machine data (with the exception of the memory-configuring data) is overwritten with default values.

- MD11200 \$MN_INIT_MD = 2

On the next NC boot, all memory-configuring machine data is overwritten with default values.

7.6.5 Switching over the measuring system

Switching over the measuring system

The measuring system of the complete machine is switched in "Machine" operating area → "Settings" → "Switch to inch" ↔ "Switch to metric". The actual switchover of the system of measurement is performed internally by writing all the necessary machine data and subsequently activating them with a Reset (po).

MD10240 \$MN_SCALING_SYSTEM_IS_METRIC and the corresponding G70/G71/G700/G710 settings in MD20150 \$MC_GCODE_RESET_VALUES are switched over automatically and consistently for all configured channels. The value of machine data: MD20150 \$MC_GCODE_RESET_VALUES[12] varies between G700 and G710. This process takes place independently of the protection level currently set.

Supplementary conditions

The switchover occurs only under the following supplementary conditions:

- MD10260 \$MN_CONVERT_SCALING_SYSTEM=1.
- Bit 0 of MD20110 \$MC_RESET_MODE_MASK is set in every channel.
- All channels are in the Reset state.
- Axes are not traversing with JOG, DRF or PLC control.
- Constant grinding wheel peripheral speed (GWPS) is not active.

Actions such as part program start or mode change are disabled for the duration of the switchover.

If the switchover cannot be performed, this is indicated by a message in the user interface. These measures ensure that a consistent set of data is always used for a running program with reference to the system of measurement.

System data

When switching over the measuring system, from the view of the user, all length-related specifications are converted to the new measuring system automatically. This includes:

- Positions
- Feedrates
- Acceleration rates
- Jerk
- Tool offsets
- Programmable, settable and work offsets external and DRF offsets
- Compensation values
- Protection zones
- Machine data
- JOG and handwheel factors

After the switchover, all data is available in physical quantities. Data, for which no unique physical units are defined, is not converted automatically.

- R parameters
- GUDs (**G**lobal **U**ser **D**ata)
- LUDs (**L**ocal **U**ser **D**ata)
- PUDs (**P**rogram global **U**ser **D**ata)
- Analog inputs/outputs
- Data exchange via FC21

The user is prompted to take the current valid measuring system MD10240 \$MN_SCALING_SYSTEM_IS_METRIC into consideration.

The current system of measurement setting can be read at the PLC interface via the "inch system" signal DB10.DBX107.7. DB10.DBB71 can be used to read out the "system of measurement change counter".

Machine data

Number	Identifier	Comment
10240	\$MN_SCALING_SYSTEM_IS_METRIC	Basic system metric
10250	\$MN_SCALING_VALUE_INCH	Conversion factor for switchover to inch system
10260	\$MN_CONVERT_SCALING_SYSTEM	Basic system switchover active
32711	\$MA_CEC_SCALING_SYSTEM_METRIC	System of measurement of sag compensation

Literature

Function Manual, Basic Functions; Velocities, Setpoint-Actual Value Systems, Closed-Loop Control (G2)

7.6.6 Traversing ranges

Computational resolution and traversing ranges

The range of values of the traversing range depends directly on the selected computational resolution.

The pre-setting of the machine data for the computational resolution is set as follows:

- 1000 inc./mm
- 1000 inc./deg.

The following traversing ranges result:

	Traversing range in the metric system	Traversing range in the inch system
Linear axes	± 999,999.999 [mm; deg.]	± 399,999.999 [inch; deg.]
Rotary axes	± 999,999.999 [mm; deg.]	± 999,999.999 [inch; deg.]
Interpolation parameters I, J, K	± 999,999.999 [mm; deg.]	± 399,999.999 [inch; deg.]

See also

Resolutions (Page 219)

7.6.7 Positioning accuracy of the control system

Computational resolution and traversing ranges

The positioning accuracy depends on:

- The computational accuracy (internal increments/(mm or degrees))
- The actual-value resolution (encoder increments/(mm or degrees)).

The less-precise resolution of both determines the positioning accuracy of the NC.

The input resolution, the position-control and interpolation clock do not affect the accuracy.

Machine data

Number	Identifier	Name / remarks
10200	\$MN_INT_INCR_PER_MM	Computational resolution for linear positions
10210	\$MN_INT_INCR_PER_DEG	Computational resolution for angular positions
31020	\$MA_ENC_RESOL[n]	Encoder pulses per revolution

7.6.8 Cycle times

Cycle times

For SINUMERIK 840D sl, the system clock cycle, the position-control cycle and the interpolation cycle of the NC are based on the DP cycle time that is configured in the STEP 7 hardware configuration.

Note

Check operating modes

If you change the cycle times, check the behavior of the control in all operating modes before you finish commissioning.

Boundary conditions:

- For axes with Safety Integrated, the following applies: Max. sampling time 12 ms
- Maximum number of SERVO axes = 6 per CU (integrated) or NX

The lower the chosen cycle times (PROFIBUS DP cycle), the higher the control quality for the drive and better the surface quality on the workpiece.

Basic system clock cycle

The system clock cycle is set fixed to the ratio of 1:1 with regard to the DP cycle time. The active value is displayed in the machine data MD10050 \$MN_SYSCLOCK_CYCLE_TIME (system clock cycle). It cannot be changed.

Adapt the DP cycle time in the STEP 7 hardware configuration to the **basic system clock cycle**.

Position-control cycle

The position-control cycle (MD10061 \$MN_POSCTRL_CYCLE_TIME) is set to the fixed ratio 1:1 with regard to the system clock cycle. It cannot be changed.

Position-control cycle offset

The position-control cycle offset T_M is automatically determined in the default setting (MD10062 \$MN_POSCTRL_CYCLE_DELAY=0).

The effective position-control offset is displayed in the MD10063[1]. The following values can be read out via the MD10063 \$MN_POSCTRL_CYCLE_DIAGNOSIS:

- MD10063[0] = T_{DX}
- MD10063[1] = T_M
- MD10063[2] = $T_M + T_{pos\ max}$

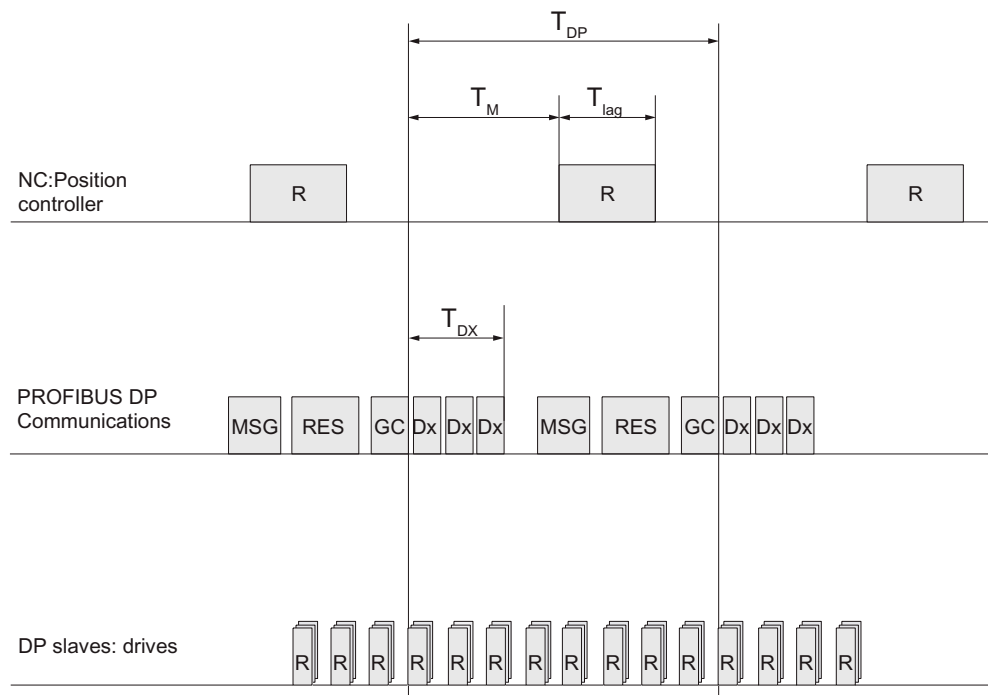
The following conditions must be met for explicit specification of the position-control cycle offset (MD10062 \$MN_POSCTRL_CYCLE_DELAY!=0):

- Cyclic communication with the DP slaves (drives) must be completed before the position controller is started.

Condition: $T_M > T_{DX}$

- The position controller must be completed before the DP cycle / system clock cycle is completed.

Condition: $T_M + T_{\text{Position control max}} < T_{DP}$



GC Global control: Broadcast message for cyclic convergence of the equidistance between DP master and DP slaves

Dx Useful data exchange between the DP master and DP slaves

MSG Non-cyclic services such as DP/V1, token passing

R CPU time

Res. Reserve: "Active pause" until the isochronous (equidistant) cycle has expired

Tpos Computing time requirements for the position controller

TDP DP cycle time: DP cycle time

T_{DX} Data exchange time: Total transfer time for all DP slaves

T_M Master time: Offset of the start time for NCK position control

Figure 7-18 Position-control cycle offset compared to PROFIBUS DP cycle

Error response

- Alarm: "380005 PROFIBUS DP: Bus access conflict, type t, counter z"

Cause of errors / error handling

- $t = 1$

The position-control cycle offset selected is too small. The cyclic PROFIBUS communication with the drives was not yet completed with the start of the position controller.

- Remedy: Increase the position-control cycle offset.

- $t = 2$

The position-control cycle offset selected is too large. The cyclic PROFIBUS communication with the drives started before the position controller had finished. The position controller requires more CPU time than available within the DP cycle.

- Remedy: Decrease the position-control cycle offset or increase the DP cycle time.

Interpolation cycle

The interpolation cycle may be chosen freely as a whole multiple of the position-control cycle.

- MD10070 \$MN_IPO_SYSCLOCK_TIME_RATIO (factor for the interpolation cycle)

Error response:

- Alarm 4240: "CPU time overflow at the IPO or position controller level"

Cause of errors / error handling

The DP cycle time / position-control cycle, the interpolation cycle, or the NC CPU time share is set in such a way that not enough CPU time is available for one of the two cyclic levels of the NCK (position controller or interpolator).

Remedy: Calculate the maximum values for $T_{\text{pos max}}$ and $T_{\text{IPO max}}$ (see above) and adapt the following machine data:

MD	Identifier	Remark
10050	\$MN_SYSCLOCK_CYCLE_TIME	The system clock cycle is always equal to the equidistant PROFIBUS DP cycle.
10060	\$MN_POSCTRL_SYSCLOCK_TIME_RATIO	Factor for the position-control cycle is permanently fixed to the factor 1.
10061	\$MN_POSCTRL_CYCLE_TIME	Position-control cycle
10062	\$MN_POSCTRL_CYCLE_DELAY	Position-control cycle offset
10063	\$MN_POSCTRL_CYCLE_DIAGNOSIS	[0] = DP cycle time [1] = Position-control cycle offset [2] = Position-control cycle offset + max. computation time needed by the position controller
10070	\$MN_IPO_SYSCLOCK_TIME_RATIO	Factor for the interpolation cycle can be freely selected in integer multiples.
10185	\$MN_NCK_PCOS_TIME_RATIO	Computation time ratio NCK

References

Special Functions, Function Manual; Cycle Times (G3)

7.6.9 System utilization

System utilization

The system utilization is displayed channel-specific in the "Diagnostics" → Menu forward key → "System utilization" operating area:

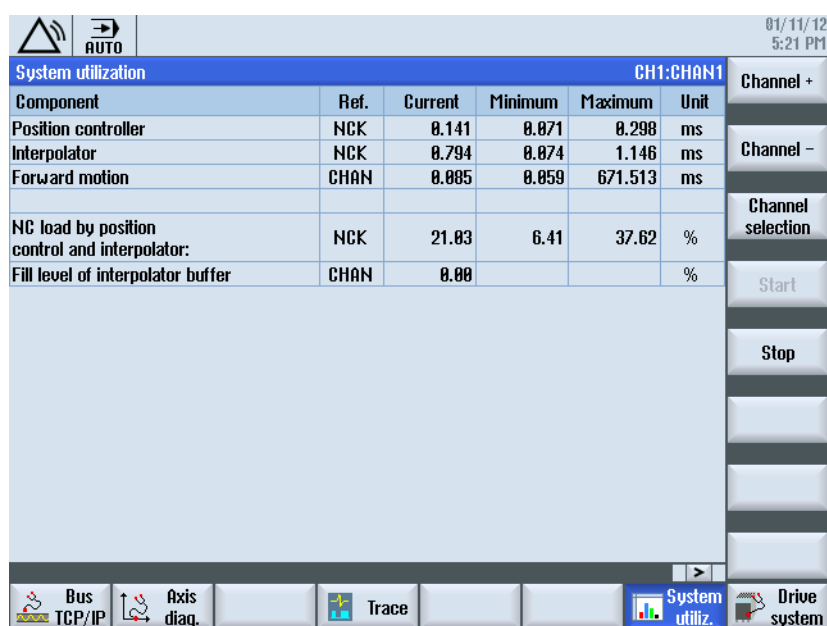


Figure 7-19 System utilization

The displayed values have the following significance:

Component	Display
Position controller	Total utilization of the system: Current, minimum and maximum utilization of the NCK in milliseconds. <ul style="list-style-type: none"> MD10050 \$MN_SYSCLOCK_CYCLE_TIME (system clock cycle) MD10061 \$MN_POSTCTRL_CYCLE_TIME (position-control cycle) MD10070 \$MN_IPO_SYSCLOCK_TIME_RATIO (factor for the interpolation cycle) MD10071 \$MN_IPO_CYCLE_TIME (interpolation cycle) MD11510 \$MN_IPO_MAX_LOAD (time required for synchronized actions)
Interpolator	
Preprocessing	

Component	Display
Position controller and interpolator NC load	In order to have sufficient reserves for the program processing, the maximum load in typical operations should not exceed 75%. The current load on the average should not exceed 50%. MD10185 \$MN_NCK_PCOS_TIME_RATIO = 90 (default setting)
Interpolator buffer level	This display indicates whether batch preparation for batch processing can commence. Jerky processing in continuous-path mode, if for instance a number of short traversing blocks have been programmed in succession, is a typical indicator of the IPO buffer idling. Capacity indication is channel-specific. MD28060 \$MC_MM_NUM_IPO_BUFFER_SIZE is displayed as a percentage.

See also

Section Cycle times (Page 228)

7.6.10 Velocities**Max. axis velocity and spindle speed**

The maximum possible axis velocities and spindle speeds depend on the machine design, drive dynamics and the encoder frequency limit of the individual drives.

Max. programmable tool path velocity

The maximum programmable tool path velocity results from the maximum axis velocities of the axes involved in the path programmed.

Max. tool path velocity

The maximum tool path velocity at which traversing is possible within a part program block results as follows:

$$v_{\text{max.}} = \frac{\text{Progr. path length in part program block [mm or degrees]}}{\text{Interpolation cycle [s]}}$$

Upper limit

To guarantee that part program blocks are executed continuously (control margin), the NC limits the tool path velocity within a part program block to 90% of the max. possible tool path velocity as follows:

$$V_{\max.} \leq \frac{\text{Progr. path length in part program block [mm or degrees]}}{\text{Interpolation cycle [s]}} * 0.9$$

For example, in the case of part programs generated by means of a CAD system which contain extremely short blocks, this limiting of the path velocity can result in a strong reduction of the path velocity over several part program blocks.

A compressor function can be used to avoid such velocity drops.

Lower limit

The minimum tool path or axis velocity at which traversing is possible results from:

$$V_{\min} \geq \frac{10^{-9}}{\text{comput. resolution [mm or degrees]} * \text{IPO cycle [s]}}$$

If V_{\min} is not reached, no traversing motion is carried out.

Literature

You can find further details in:

- Programming Manual Work Preparation: Special motion commands (COMPON, COMPCURVE)
- Function Manual, Basic Functions; Velocities, Setpoint-Actual Value Systems, Closed-Loop Control (G2)

7.7 Memory configuration

Memory division

On the SINUMERIK 840D sl, the persistent data is divided into various independent areas: Siemens, manufacturer, user.

The memory available in the NCK is displayed on the user interface in the: "Commissioning" → "NC" → "NC memory" operating area.

The figure below shows how NCK persistent data is divided:

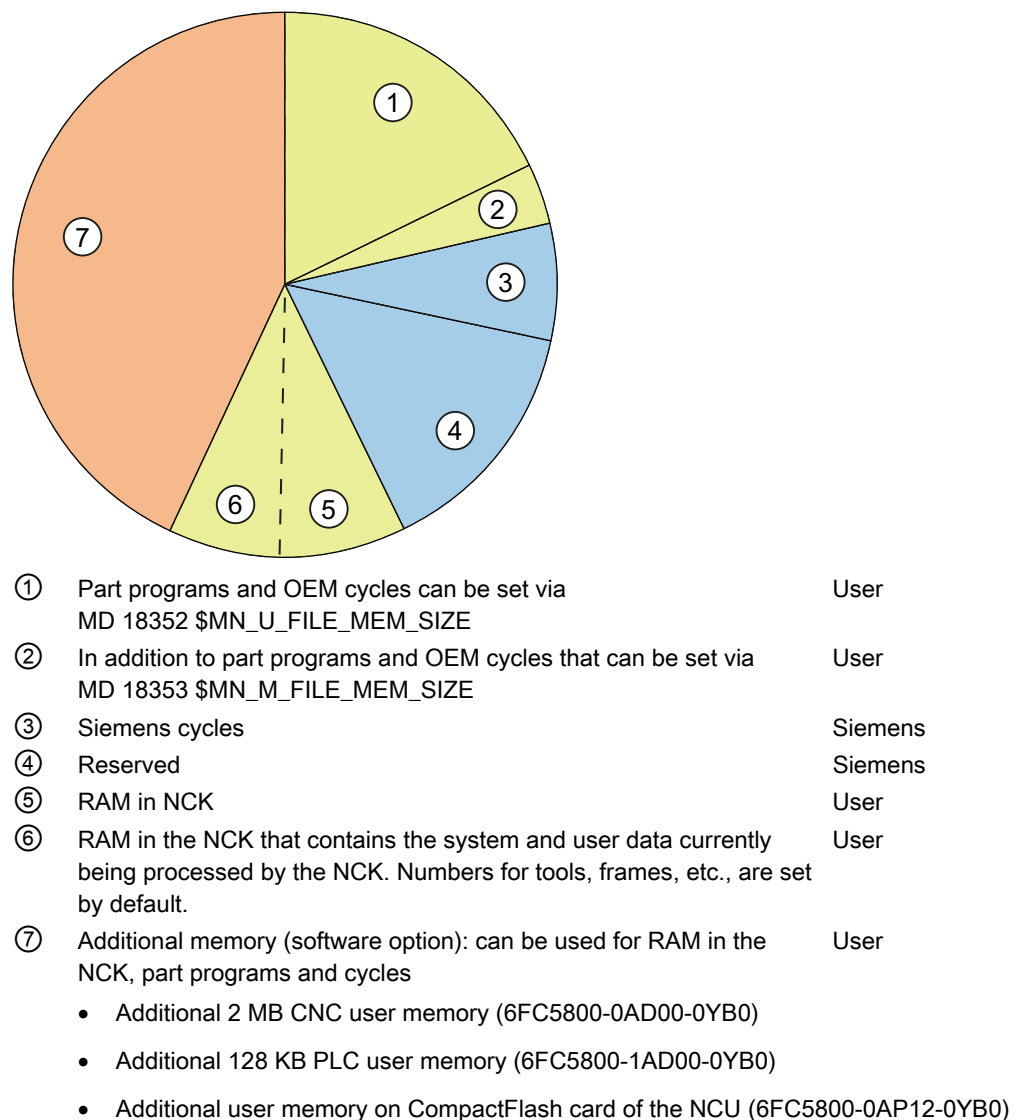


Figure 7-20 Memory division

7.8 Application example

Advanced Surface (option)

Advanced Surface is a function for machining milled surfaces in the tool and mold making area.



Software option

You require the following software option in order to use this function: "Advanced Surface" (MLFB: 6FC5800-0AS07-0YB0).

The machine and setting data influenced by this functionality as well as their contents are listed below. The values are recommended settings.

7.8.1 Preconditions, G code

Introduction

Dynamic G groups are used for the Advanced Surface (AS) option.

Preconditions

- The machine axes have been optimized.
- The dynamic G groups have been set-up and parameterized for the following machining sections:
 - Roughing (DYNROUGH)
 - Semi-finishing (DYNSEMIFIN)
 - Finishing (DYNFINISH)

Recommendations

- Dynamic G groups

The following classification of dynamic G groups is recommended (G code group 59):

DYNNORM	→ 2.5D machining without AS
DYNPOS	→ Positioning mode (e.g. tool change, thread cutting) without AS
DYNROUGH	→ Milling with AS
DYNSEMIFIN	→ Milling with AS
DYNFINISH	→ Milling with AS

Note

DYNNORM is the initial setting of the G group (default).

For Advanced Surface, the precondition is that jerk-limited velocity control is active. Jerk-limited velocity control is selected using the G code SOFT.

- **COMPCAD**

Using COMPCAD, it is possible to combine part programs with short linear blocks, with the associated tolerance, using polynomials.

This path compression technique has been developed so that the surface character, which the milling paths form, is retained.

- **G645**

G645 (G code group 10) switches to the continuous path mode (Look Ahead).

G645 has the ability to insert smoothing elements in existing contour elements so that acceleration steps (jumps) do not occur.

- **FIFOCTRL**

FIFOCTRL (G code group 4) switches to the automatic pre-processing memory control.

The feed is adapted so that the pre-processing memory does not become empty.

- **FFWON**

FFWON (G code group 24) switches to the parameterized pre-control (speed or acceleration pre-control). FFWON can only be used if pre-control is parameterized. This must be ensured by the machine suppliers.

Commands for 5-axis machining

The following commands are important for 5-axis machining:

- **TRAORI** enables the defined transformation and must be programmed alone in the block.
- **UPATH** (G code group 45) switches to the path parameter that was developed for 5-axis interpolation.
- **ORIXES** (G code group 51) linearly interpolates the orientation axes in the block up to the end of block.
- **ORIWKS** (G code group 25) defines the workpiece coordinate system for orientation interpolation.

CYCLE832 (High Speed Cutting)

The CYCLE832 (High Speed Cutting) cycle optimally supports Advanced Surface. This cycle has been developed for this purpose and sets the above mentioned commands and the tolerance.

Commands CTOL (Chord TOLerance) and OTOL (Orientation TOLerance)

Commands CTOL (Chord TOLerance for chord tolerance) and OTOL (Orientation TOLerance) can be used if the tolerance is programmed without support of CYCLE832.

Activating the G code

Activation can be realized either using "Programming in the part program" or when commissioning machines, by re-configuring the RESET response (see \$MC_GCODE_RESET_VALUES).

Programmable program sequence without CYCLE832

This produces the following program sequence for customers who do not use CYCLE832 or if the G commands do not correspond to the machine initial setting:

```
SOFT
FFWON
FIFOCTRL
G645
COMPCAD
DYNROUGH or DYNSEMIFIN or DYNFINISH {depending on the machining
phase}
TRAORI(<Transformation number>) {for 5-axis programs and
transformation}
ORIAxes
ORIMKS
```

7.8.2 Setting machine data

Machine data preassignment for 3-axis and 5-axis machining

MD	Name	Description	Rec. value	Comment
10200	\$MN_INT_INCR_PER_MM	Internal calculation resolution, linear axis	100000	10000 for export version
10210	\$MN_INT_INCR_PER_DEG	Internal calculation resolution, rotary axis	=MD10200	10000 for export version
18360	\$MN_MM_EXT_PROG_BUFFER_SIZE	Maximum reload memory when executing from external	500	Against jamming
18362	\$MN_MM_EXT_PROG_NUM	Number of external programs that can be simultaneously processed	2	
20150	\$MC_GCODE_RESET_VALUES[3]	Initial setting of G group 4	3	FIFOCTRL
20150	\$MC_GCODE_RESET_VALUES[19]	Initial setting of G group 20	2	SOFT

MD	Name	Description	Rec. value	Comment
20150	\$MC_GCODE_RESET_VALUES[44]	Initial setting of G group 45	2	UPATH (for 5-axis machining)
20150	\$MC_GCODE_RESET_VALUES[50]	Initial setting of G group 50	2	ORIAXES (for 5-axis machining)
20170	\$MC_COMPRESS_BLOCK_PATH_LIMIT	Maximum length of POLY generated by the compressor	20	
20172	\$MC_COMPRESS_VELO_TOL	Maximum deviation of the path feed for COMCAD	1000	Default setting
20443	\$MC_LOOKAH_FFORM[0-1]	Activates the extended Look Ahead in the associated technology group (DYNNORM, DYNPOS)	0	Default setting
20443	\$MC_LOOKAH_FFORM[2-4]	Activates the extended Look Ahead in the associated technology group (DYNROUGH, DYNSEMIFIN, DYNFINISH)	1	
20482	\$MC_COMPRESSOR_MODE	Behavior of the compressor tolerance	300	
20490	\$MC_IGNORE_OVL_FACTOR_FOR_ADIS	Control of G642	1	
20560	\$MC_G0_TOLERANCE_FACTOR	Factor for tolerance for COMPCAD, G645, OST, ORISON	3	
20600	\$MC_MAX_PATH_JERK [0-4]	Path jerk	10000	Should not be effective
20602	\$MC_CURV_EFFECT_ON_PATH_ACCEL[0-1]	Ratio of translatory acceleration to the centripetal acceleration	0	Should not be effective
20602	\$MC_CURV_EFFECT_ON_PATH_ACCEL[2]	Ratio of translatory acceleration to centripetal acceleration with DYNROUGH	0.65	Must be effective so that the jerk is minimized during active curvature smoothing.
20602	\$MC_CURV_EFFECT_ON_PATH_ACCEL[3]	Ratio of translatory acceleration to centripetal acceleration with DYNSEMIFIN	0.6	Must be effective so that the jerk is reduced during active curvature smoothing.

MD	Name	Description	Rec. value	Comment
20602	\$MC_CURV_EFFECT_ON_PATH_ACCEL[4]	Ratio of translatory acceleration to centripetal acceleration with DYNFINISH	0.5 (determine using the circularity test)	Limit rotational acceleration, especially for "large" machines.
20606	\$MC_PREPDYN_SMOOTHING_ON[0-1]	Activates curvature smoothing	0	Default setting
20606	\$MC_PREPDYN_SMOOTHING_ON[2-4]	Activates curvature smoothing	1	
21104	\$MC_ORI_IPO_WITH_G_CODE	G code for orientation interpolation	1	
28060	\$MC_MM_IPO_BUFFER_SIZE	Memory, interpolator for number of G1 blocks	150	
28070	\$MC_MM_NUM_BLOCKS_IN_PREP	Memory, preparation (pre-processing)	80	
28520	\$MC_MM_MAX_AXISPOLY_PER_BLOCK	Maximum number of axis polynomials per block	5	
28530	\$MC_MM_PATH_VELO_SEGMENTS	Number of memory elements for limiting the path velocity	5	
28533	\$MC_MM_LOOKAH_FFORM_UNITS	Memory for extended Look Ahead	18	
28540	\$MC_MM_ARCLENGTH_SEGMENTS	Number of memory elements to display the arc length function	10	
28610	\$MC_MM_PREPDYN_BLOCKS	Memory, curvature smoothing	10	
29000	\$OC_LOOKAH_NUM_CHECKED_BLOCKS	Number of Look Ahead blocks (this must be the same as N28060)	150	
42470	\$SC_CRIT_SPLINE_ANGLE	COMP criteria for target point analysis (should be >30°)	36	Default setting
42471	\$SC_MIN_CURV_RADIUS	Factor for compressor tolerance (should be 0.3 - 3)	1	
42500	\$SC_IS_MAX_PATH_ACCEL	Limits the path acceleration via SD	10000	
42502	\$SC_IS_SD_MAX_PATH_ACCEL	Activates the path acceleration via SD	0	
42510	\$SC_SD_MAX_PATH_JERK	Limits the path jerk via SD	10000	
42512	\$SC_IS_SD_MAX_PATH_JERK	Activates path jerk via SD	0	

Optimize the drive

8.1 Optimization overview

Overview of drive optimization

Once the drives and axes have been commissioned, it is time to start optimizing the particular machine or a machine type.

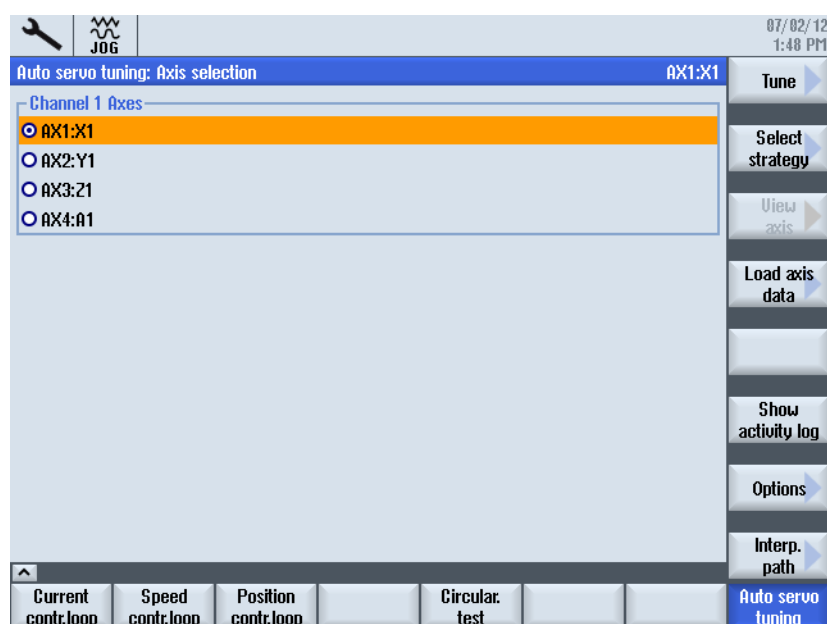


Figure 8-1 Selection of "Automatic servo optimization"

The following functions are available for this:

- In the "Commissioning" → "Optimization/Test" operating area
 - Automatic servo optimization
 - Measuring functions (current control loop, speed control loop, position control loop)
 - Circularity test
- In the "Diagnostics" operating area → Menu forward key → "Trace"

With the "Trace" function, you can select the NC, PLC, or drive variables whose signal chart is to be visualized.

During drive optimization, the following variables are of particular interest:

– **Trace for NC/PLC variables**

Recording and graphical representation of the temporal characteristics of SERVO signal values, such as actual position value, following error, etc.

– **Trace for drive variables**

Recording and graphical representation of the temporal characteristics of signal values from the drive system, such as actual speed value, actual current value, etc. It must be possible to interconnect the signals to be recorded via a BICO source.

Description of the procedure

The following procedures are described in this chapter:

- Optimization by using all automatic defaults (especially efficient procedure)
- Optimization with manual settings for position controllers, speed controllers and current controllers (procedure for experts)

References

You can find further details in the following manuals:

- Basic Software and Operating Software Commissioning Manual, SINUMERIK Operate (IM9), "Trace" chapter
- Basic Functions Function Manual; Axis Monitoring, Protection Zones (A3)
- Function Manual, Basic Functions; Velocities, Setpoint / Actual Value Systems, Closed-Loop Control (G2)
- Extended Functions Function Manual; Compensations (K3)

8.2 Automatic drive optimization

8.2.1 Automatic servo optimization

Automatic servo optimization

The following options are available for automatically optimizing an axis:

- Selection of individual axis for optimization
- Selection of a strategy from many options
- Reconfiguration of measurement conditions
- Chart display and activity log for optimization process
- Display of current measurement and at the same time the average of previous measurements
- Checking and processing of optimization results for speed and position controller
- Accept or reject results

The "Automatic servo optimization" function is started in the "Commissioning" → "Automat. Servo Opt." operating area and can be used for all SERVO and direct drives.

Note

The master-slave axes for automatic optimization are not supported by SINUMERIK Operate Version 2.6 SP1.

Master-slave axes can be optimized as individual axes if they are not coupled.

Interpolation axes

For axes which make up an interpolation group, additional optimization steps should be undertaken, e.g.:

- Interpolation path (Page 264) with the automatic servo optimization
- Circularity test (Page 284)
- Adaptation of servo gains (e.g. smallest servo gain in all interpolating axes without DSC (see also: Position control loop measurement (Page 277))
- When using speed feedforward control, transfer equivalent time constants of the slowest axis (highest value) into all interpolating axes (see also: Speed control loop measurement (Page 274)).

Overview of navigation

When optimizing an axis, you navigate via various dialogs. The following figure shows the navigation for optimizing an axis:

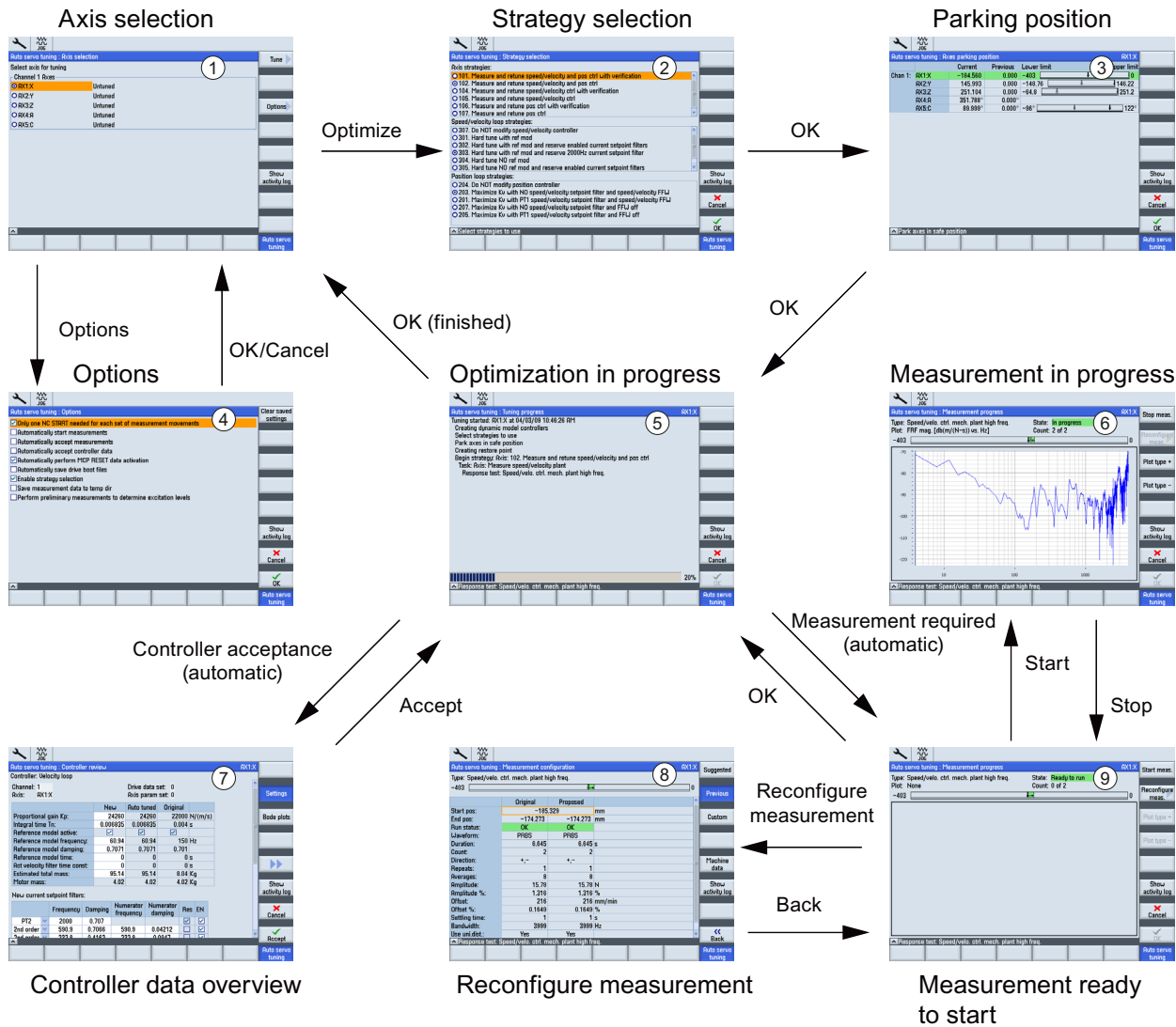


Figure 8-2 Navigation for automatic optimization of an individual axis

Note

The following chapter "General operating sequences for automatic servo optimization" uses the numbers shown in the figure above (e.g. "Strategy selection" dialog ②).

8.2.2 Setting the options for the measurement procedure

Options

In the first step, select the "Options" softkey to set the general behavior for automatic servo optimization.

The following selections are recommended for a machine without a gantry axis grouping while using all automatic sequences and settings:

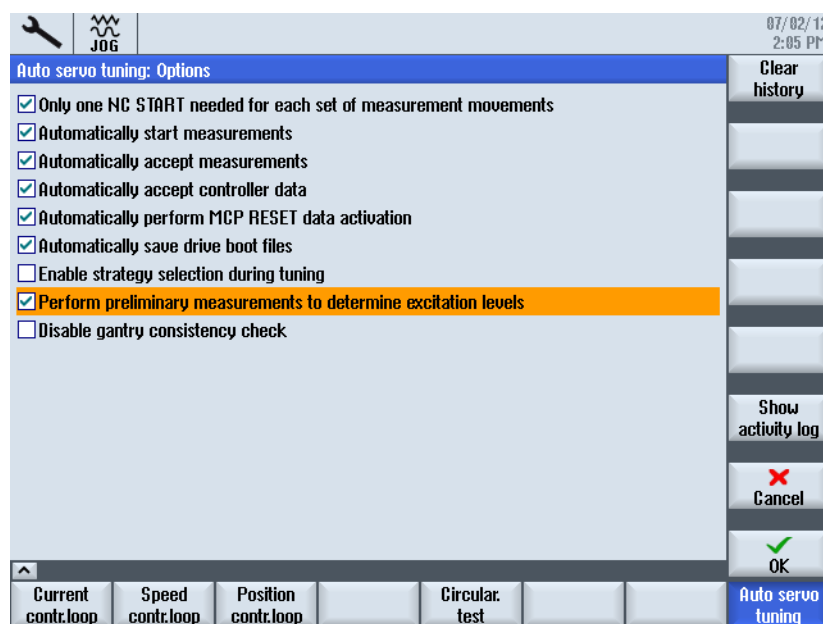


Figure 8-3 Options

Meaning of the options:

- Perform all measurements of each measurement series with the first NC start:
All repeats (e.g. motion in the positive and negative axis direction) within a measurement series are started automatically.
- Start measurements automatically:
The start screen of each measurement series is skipped and the measurement process is directly started with the default measurement parameters.
- Automatic confirmation of the measurement:
The final screen of each measurement series (is used to evaluate the measurement results -> if required, adapt measurement parameters and restart measurement series) is skipped. The algorithm changes directly to the next optimization step.
- Automatic acknowledgement of the control data:
The "control data overview" display is skipped. The control data determined by the algorithm are directly activated.

- Automatic data activation using the operator panel reset:
The "Operator panel reset" signal is generated by the algorithm. If this option is deactivated, "Operator panel reset" is requested using a dialog screen.
- Automatically backup drive boot files (ACX format):
After completing the optimization of a machine axis, the drive data is automatically saved on the CompactFlash Card in the ACX format. If this option is deactivated, a query is made.
- Allow strategy selection during optimization:
The dialog screen to select the optimization strategies for the speed and position controller is displayed. This option is not necessary for a simple automated procedure.
- Perform preliminary measurement to determine the excitation:
Activate a preceding (additional) measurement for each measurement series to more precisely determine the measurement parameters. This is especially recommended when measuring directly-driven machine axes for the first time.
- Switch off gantry consistency checking
This option is only required for checking a gantry axis grouping.

Further actions:

- "Delete history" softkey to delete any measurement data that already exists for this axis.
- "Optimization log" softkey to display the window in which the optimization log is output.
- "Cancel" and "OK" softkeys to cancel or accept the new settings, respectively.

8.2.3 General operating sequences for automatic servo optimization

Precondition

 WARNING
Avoiding unwanted axis movements Automatic servo optimization is based on the analysis of measurements. The measurements require the axis to move. Ensure that all axes are in a safe position and no collisions will occur during the traversing motion that is required.

General operating sequences

Procedure:

1. In the "Commissioning" operating area, press the "Automat. servo opt." softkey. The following dialog appears: ①

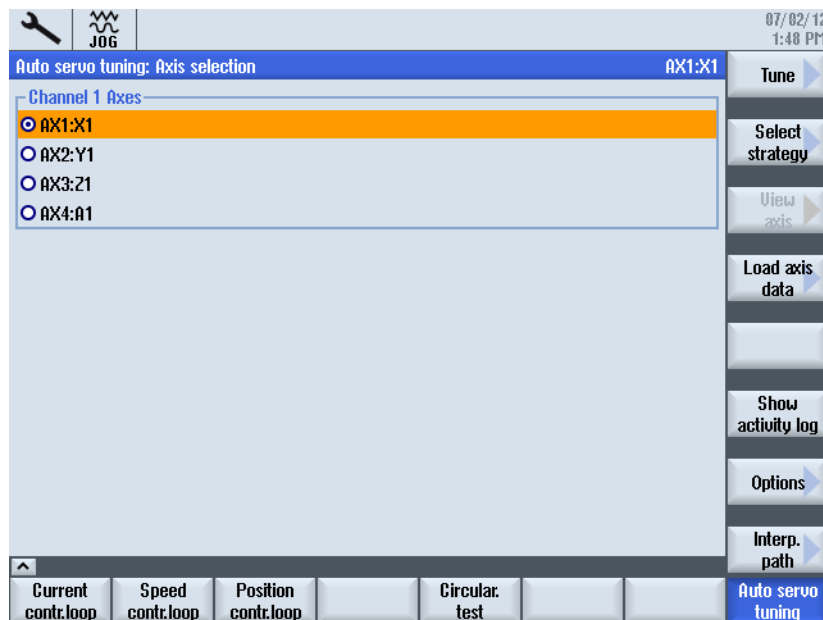


Figure 8-4 Axis selection

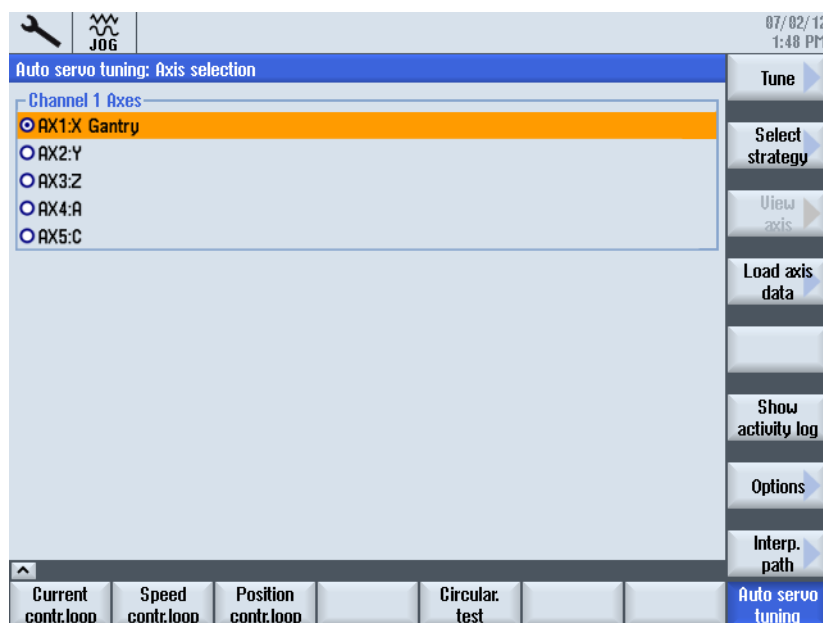


Figure 8-5 Axis selection with gantry axis grouping

2. Use the cursor keys to select an axis for optimization.

Note

For a gantry axis grouping, only the guide axis is displayed and labeled with the "Gantry" text. Synchronous axes are hidden, but are measured and optimized when the guide axis is selected.

3. In the "Axis selection" dialog ①, press the "Optimize" softkey.
4. In the "Strategy selection" dialog ②, the predefined strategy for optimization is displayed:

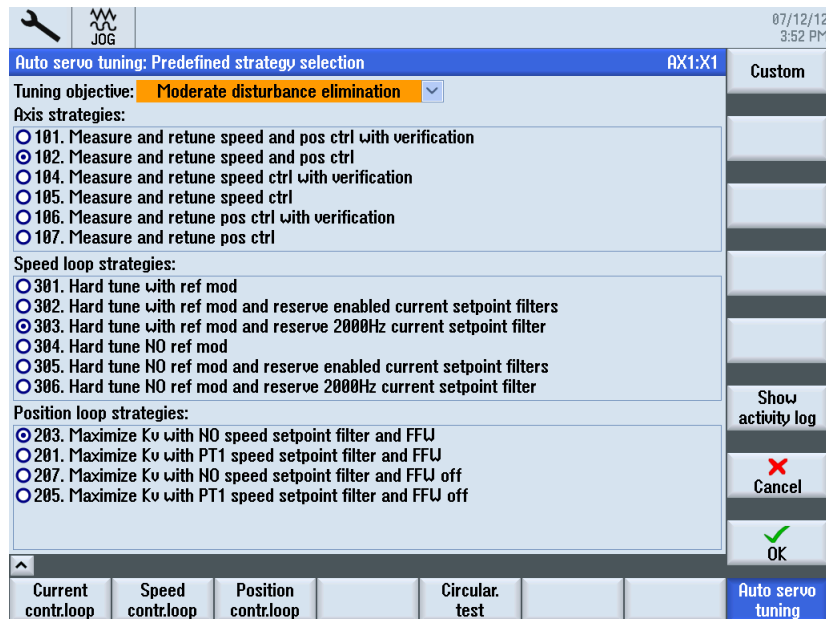


Figure 8-6 Strategy selection

In a typical strategy, for example, the mechanical controlled system of the speed control is measured and gains and filters are defined for optimized dynamic behavior.

Note

A user-defined strategy can be set using the vertical "User-defined" softkey.

5. Press "OK".

6. In the "Axis parking position" dialog ③, move the axes on the machine into a safe position for optimization.

	Current	Previous	Lower limit	Upper limit
Chan 1: AX1:X	-184.560	0.000	-403	0
AX2:Y	145.993	0.000	-148.76	146.22
AX3:Z	251.104	0.000	-64.8	251.2
AX4:A	351.788°	0.000°	0.000°	122°
AX5:C	89.999°	0.000°	-96°	122°

Auto servo tuning : Axes parking position

AX1:X

Chan 1: AX1:X

AX2:Y

AX3:Z

AX4:A

AX5:C

Park axes in safe position

Auto servo tuning

Figure 8-7 Axis parking position

7. Press "OK". Optimization is started ⑤.

Auto servo tuning : Tuning progress

AX1:X

Tuning started: AX1:X at 04/03/09 10:46:26 AM

Creating dynamic model controllers

Select strategies to use

Park axes in safe position

Creating restore point

Begin strategy: Axis: 102. Measure and retune speed/velocity and pos ctrl

Task: Axis: Measure speed/velocity plant

Response test: Speed/velo. ctrl. mech. plant high freq.

20%

Response test: Speed/velo. ctrl. mech. plant high freq.

Auto servo tuning

Figure 8-8 Optimization in progress

If measurement can only be continued after the necessary inputs have been made, then this is signaled using input prompts (screen forms). This is required because you need to initiate certain machine sequences (e.g. measurements which require an <NC START>).

You can abort the coordination process at any stage of automatic servo optimization. Once optimization has been aborted, all original machine data which was present in the control and in the drives before optimization was started is restored.

Note

After the measurement has been completed, you can perform the measurements again. In this case, the quality of the measurement data can be influenced by changing the excitation parameters using the "Measurement configuration" dialog.

Auto servo tuning : Measurement configuration AX1:X

Type: Speed/velo. ctrl. mech. plant high freq.

-403 0

	Original	Proposed	
Start pos:	-185.329	-174.273	mm
End pos:	-174.273	-174.273	mm
Run status:	OK	OK	
Waveform:	PRBS	PRBS	
Duration:	6.645	6.645	s
Count:	2	2	
Direction:	+,-	+,-	
Repeats:	1	1	
Averages:	8	8	
Amplitude:	15.78	15.78	N
Amplitude %:	1.316	1.316	%
Offset:	216	216	mm/min
Offset %:	0.1649	0.1649	%
Settling time:	1	1	s
Bandwidth:	3999	3999	Hz
Use uni.dist:	Yes	Yes	

Response test: Speed/velo. ctrl. mech. plant high freq.

Buttons: Suggested, Previous, Custom, Machine data, Show activity log, Back, Auto servo tuning

Figure 8-9 Measurement configuration

8. If the optimization process has completed certain optimizations for a control loop, the "Controller data overview" ⑦ dialog is displayed.

Auto servo tuning : Controller review AX1:X

Controller: Velocity loop

Channel: 1 Drive data set: 0

Axis: AX1:X Axis param set: 0

	New	Auto tuned	Original
Proportional gain Kp:	24260	24260	22000 N/(m/s)
Integral time Tn:	0.006835	0.006835	0.004 s
Reference model active:	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>
Reference model frequency:	60.94	60.94	150 Hz
Reference model damping:	0.7071	0.7071	0.701
Reference model time:	0	0	0 s
Act velocity filter time const:	0	0	0 s
Estimated total mass:	95.14	95.14	8.04 Kg
Motor mass:	4.02	4.02	4.02 Kg

New current setpoint filters:

	Frequency	Damping	Numerator frequency	Numerator damping	Res	EN
PT2	2000	0.707			<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>
2nd order	590.9	0.7066	590.9	0.04212	<input type="checkbox"/>	<input checked="" type="checkbox"/>
2nd order	222.8	0.4162	222.8	0.0847	<input type="checkbox"/>	<input checked="" type="checkbox"/>

Buttons: Settings, Bode plots, Show activity log, Cancel, Accept, Auto servo tuning

Figure 8-10 Controller data overview

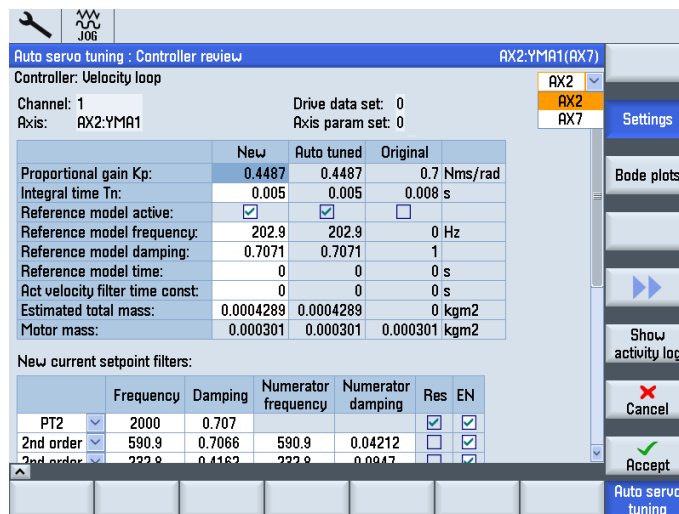


Figure 8-11 Controller data overview for gantry axis grouping

You can modify and check the results and either accept or reject the proposed control parameters.

- To confirm that you wish to accept the determined values, click the "Accept" softkey.

Example of display switchover

Procedure:

Note

Alternatively, you can display the optimized values graphically as a Bode diagram using the "Bode diagram" softkey.

1. If you accept the settings for speed control by pressing "Accept", the drive data is updated, and the strategy then runs the measurements for closed-loop position control, "Measurement in progress" dialog ⑥.

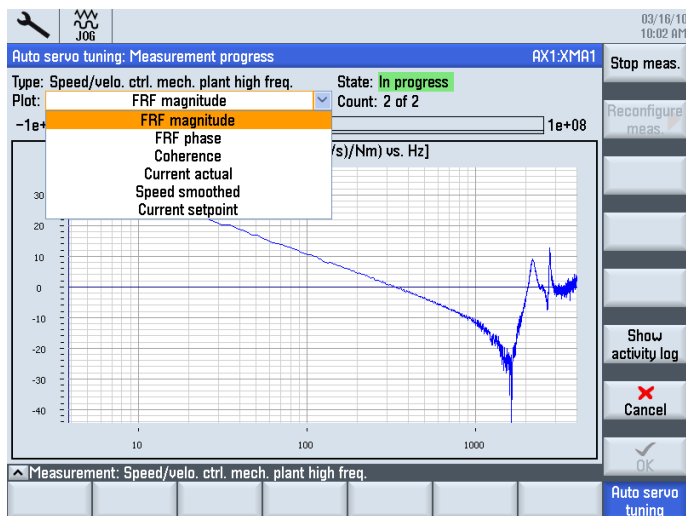


Figure 8-12 Measurement in progress

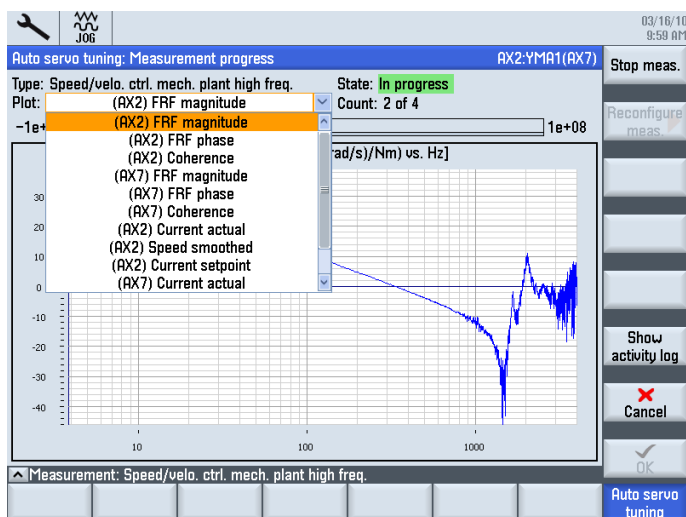


Figure 8-13 Measurement in progress, gantry axis grouping

2. Once the optimum values for closed-loop position control have been selected, the data is transferred to the NC and drives, and the strategy runs the next stage. This might, for example, consist of performing a verification measurement.

8.2.4 Setting optimization strategy

Optimization strategy

For the speed controller and position controller axis strategies, the default settings (strategies 102, 303, and 203; see figure) are recommended:

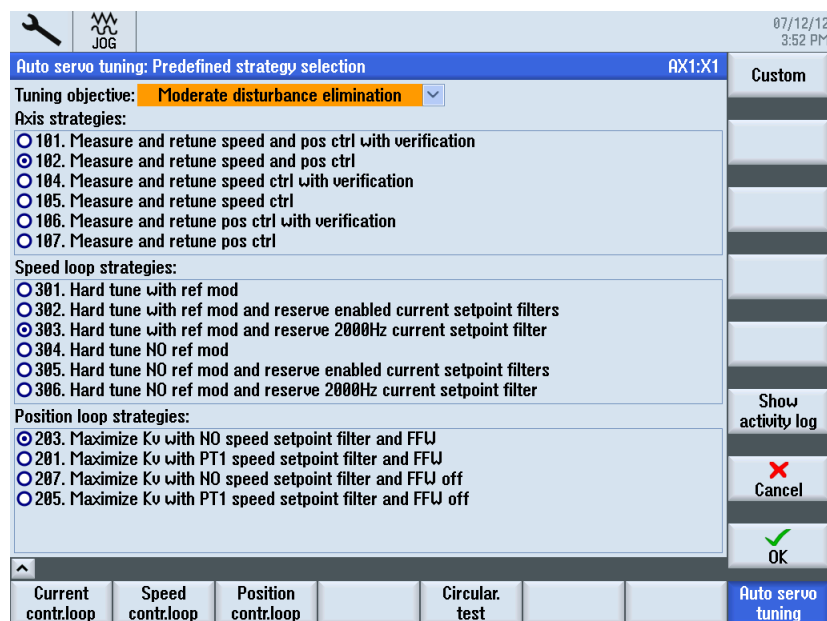


Figure 8-14 Selection of predefined strategy

The default optimization objective is "Moderate fault clearance". The option selected depends on the mechanical properties of the machine/axis. The "Maximum fault clearance" option should not be used for a "weak" axis.

Optimization objective

Description of the optimization objective:

- **Selection: "Maximum fault clearance"**

The speed and position controller gain (servo gain factor) is optimized with maximum values and minimum ruggedness.

- Application: High speed machining with maximum suppression of all disturbing forces such as friction, teeth of the drive belt, strong cutting forces, when machining titanium, for example.

Recommended for high-speed machining with linear motors.

- Precondition: The machine must have a rigid design; the dynamic masses do not change significantly.

- **Selection: "Moderate fault clearance"**

The speed and position controllers are optimized with 80% of the maximum gain and a good level of ruggedness.

- Application: There are many uses.
- Precondition: No high expectations for the machine design; recommended for general use.

- **Selection: "Optimal damping"**

The speed controller is optimized so that it achieves maximum damping to prevent vibrations and to achieve a good position control value.

- Application: Large machines with large dynamic masses.
- Precondition: A weak machine design due to large masses/inertia. The size of the motor justifies a low dynamic response. Recommended, for example, for traversing columns where the operator cabin moves with the column. Can be used if the "Optimal damping" check produces a very low position controller gain.

User-defined settings

The optimization process is re-defined using the "User-defined" softkey.

Setting the speed controller:

Auto servo tuning: Custom strategy design

Strategy: Speed loop

Tuning aggressiveness:	0.6
Target gain margin:	18 dB
Target phase margin:	42 °
Reference model active:	<input checked="" type="checkbox"/>
Min integral time Tn:	5e-3 s
Deploy act speed filter:	<input type="checkbox"/>
Act speed filter time const:	8 s
Use attenuation in curr filter:	<input type="checkbox"/>

Manual filters:

		Frequency	Damping	Numerator frequency	Numerator damping	Res	EN
CS 1	PT2	2000	0.707			<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>
CS 2	PT2	1999	0.7			<input type="checkbox"/>	<input type="checkbox"/>
CS 3	PT2	1999	0.7			<input type="checkbox"/>	<input type="checkbox"/>
CS 4	PT2	1999	0.7			<input type="checkbox"/>	<input type="checkbox"/>

CS=Current setpoint 1-4

Current contr.loop Speed contr.loop Position contr.loop Circular test

Predefined Axis Speed Position Show activity log Cancel OK Auto servo tuning

The most important settings are: Optimization aggressiveness and Min integral time Tn.

- Optimization aggressiveness:

This parameter determines the setting of Kp and Tn based on stability limits.

- Default = 0.6
- Min = 0 [maximum stability]
- Max = 1 [maximum aggressiveness]

- Minimum integral time Tn:

This parameter prevents automatic servo optimization from setting the integrator time of the speed control loop too low. Otherwise, if automatic servo optimization sets a value lower than this parameter, the actual value used will be limited to the value set by the minimum integral time Tn.

- Default setting = 5.0 ms
- Min = 0.5 ms
- Max = 100 ms

Setting the position controller:

Auto servo tuning: Custom strategy design

Strategy: Position loop

DSC active:	<input checked="" type="checkbox"/>
Kv reduction factor:	0.8
Kv upper limit:	7 1000/min
Feed forward type:	Torque
Kv max method:	Standard

Manual filters:

		Frequency	Damping	Numerator frequency	Numerator damping	Res	EN
SS 1	PT1	3999				<input type="checkbox"/>	<input type="checkbox"/>
SS 2	PT1	3999				<input type="checkbox"/>	<input type="checkbox"/>

SS=Speed setpoint 1-2

Current contr.loop Speed contr.loop Position contr.loop Circular test Auto servo tuning

The most important setting is Kv (position controller) reduction factor

- Kv reduction factor:

This parameter acts in the same way as the aggressiveness of the position controller. It causes a specific reduction of the maximum Kv calculated by automatic servo optimization.

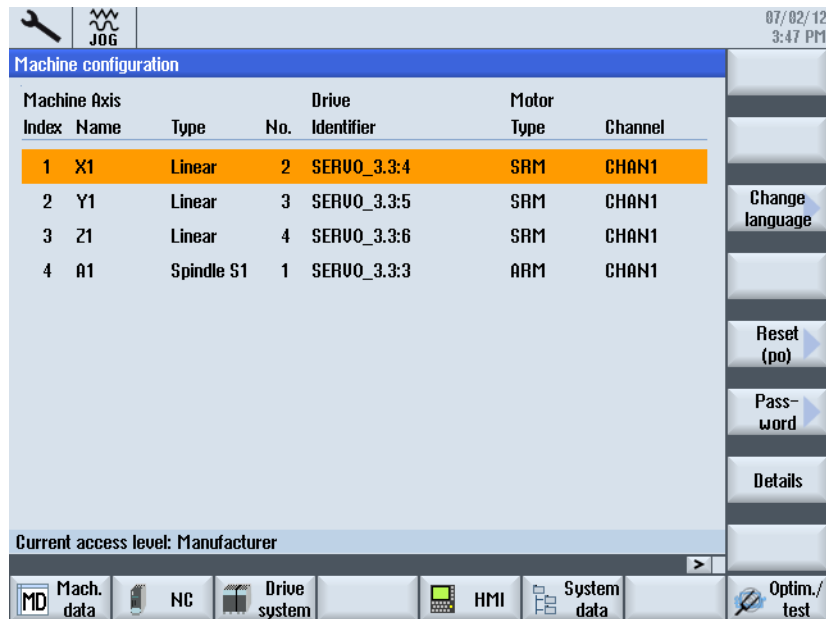
The maximum Kv is the largest Kv that would cause the zero position to be overshoot when the feedrate is deactivated.

- Default = 0.8
- Min = 0.1
- Max = 1 [no reduction]

8.2.5 Example: How to optimize the X1 axis

Precondition

This example shows how to optimize the X1 axis using the "Automatic servo optimization" function. In this case, the following machine configuration is assumed:



Machine Axis Index	Name	Type	No.	Drive Identifier	Motor Type	Channel
1	X1	Linear	2	SERVO_3.3:4	SRM	CHAN1
2	Y1	Linear	3	SERVO_3.3:5	SRM	CHAN1
3	Z1	Linear	4	SERVO_3.3:6	SRM	CHAN1
4	A1	Spindle S1	1	SERVO_3.3:3	ARM	CHAN1

Current access level: Manufacturer

WARNING

Avoiding unwanted axis movements

Automatic servo optimization is based on the analysis of measurements. These measurements require the axis to move.

Ensure that all axes are in a safe position and no collisions will occur during the traversing motion that is required.

Number of measurements

For optimization purposes, the following measurements are taken with the **speed controller**:

- Overall bandwidth: 2 preliminary measurements
- Overall bandwidth: 2 measurements
- Reduced bandwidth: 2 preliminary measurements
- Reduced bandwidth: 2 measurements

Mechanical system motor to DMS: 2 measurements

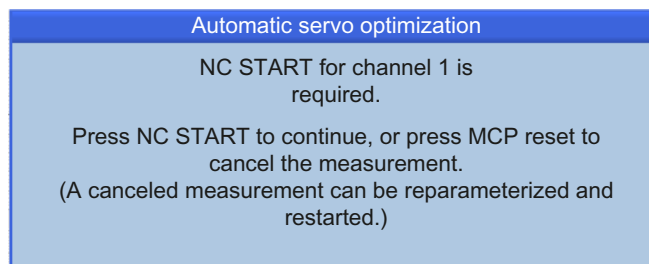
Optimizing X1 axis

Procedure:

1. Select the X1 axis in the "Axis selection" dialog.
2. Check the options set: "Options" softkey.
3. Use the preset optimization strategy: "Select strategy" softkey.
4. Check that the optimization objective "Moderate fault clearance" is selected.
5. Start the measurement with the "Optimize" softkey.



6. Confirm with "OK".
7. Follow the prompts on the screen and press NC START.



8. Two measurements are taken each time to optimize the axis.

9. Before the measurements are taken, you will be prompted to press NC START. After the successful completion of the measurements, the values of the parameters are output:

Auto servo tuning: Controller review AX1:X1

Position loop
Channel: 1
Axis: AX1:X1

Drive data set: DDS0
Axis param set: 1

	Manual	Auto tuned	Original
Kv factor:	7	7	18.68 1000/min
Feed forward type:	Torque	Torque	Torque
Equivalence time for FFW:	5.536e-4	5.536e-4	5.64e-4 s
Spd FFW Branch Delay Time:	0	0	0 s
Inertia for torque FFW:	0.002564	0.002564	0.002511 kgm²
DSC active:	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>	<input checked="" type="checkbox"/>
Estimated dead time:	1.25e-4	1.25e-4	1.25e-4 s

Manual filters:

	Frequency	Damping	Numerator frequency	Numerator damping	EN
SS 1 PT1	3999				<input type="checkbox"/>
SS 2 PT1	3999				<input type="checkbox"/>

SS=Speed setpoint 1-2
Auto tuned filters: None

Current ctrl loop Speed ctrl loop Position ctrl loop Circular test

Speed ctrl Bode plots Machine data Show activity log Cancel Accept Auto servo tuning

10. If you agree with the optimized values, confirm with the "Accept" softkey.
11. OR: Enter new values manually and repeat the measurements.
12. After accepting the measurement results, optimization is complete.

Auto servo tuning: Progress AX1:X1

Plant smoothing
Validate position controller model data
Max Kv
Select equivalence time for speed feed forward
Configure torque feed forward
Set feed forward type
End strategy
Activate the position controller data
Processing Position loop controller for review
Finalize controllers
Controller(s) accepted by user
End strategy
Saving drive object parameters
Tuning finished
Steps to setup interpolation path group:
1. Tune each axis in the interpolation path group
2. From the axis selection screen, press the "Interp. path" softkey
3. Edit and tune the interpolation path
4. Ensure that Axis MD32638 MA_FFW_ACTIVATION_MODE matches for every interpolating

100%

Current ctrl loop Speed ctrl loop Position ctrl loop Circular test

Show activity log Cancel OK Auto servo tuning

13. After completion of the measurement, you can display the complete optimization log: "Optimization log" softkey.

X1 axis result

After confirming with "OK", you get the following result:

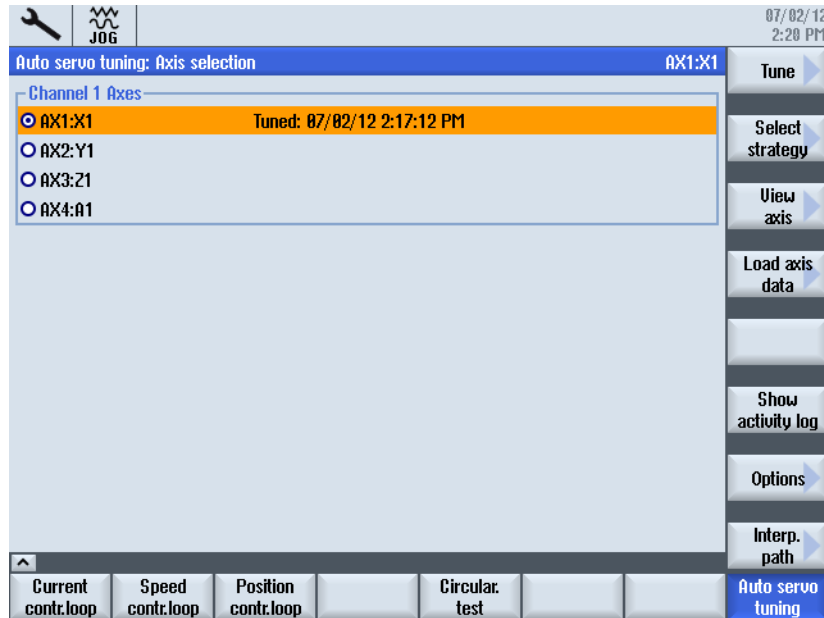


Figure 8-15 X1 axis: optimized

See also

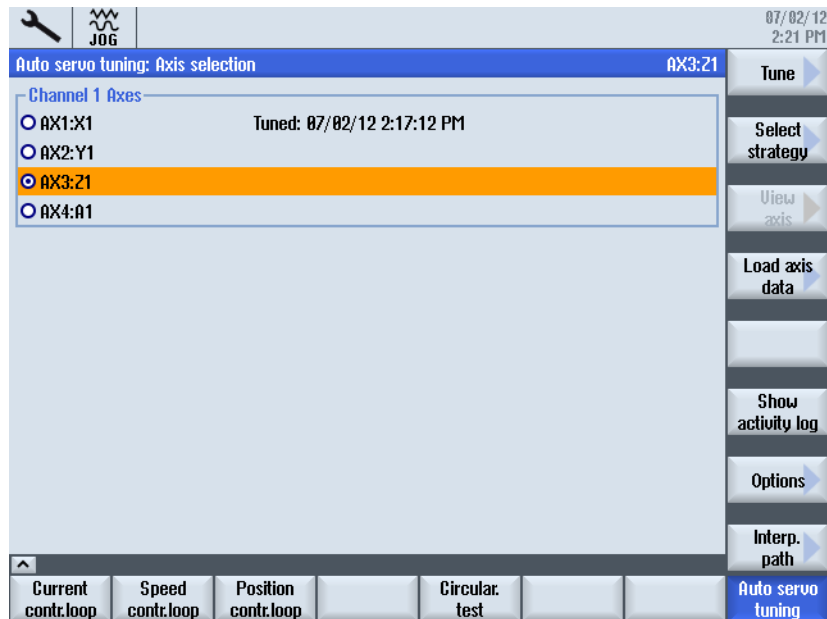
General operating sequences for automatic servo optimization (Page 246)

8.2.6 Example: How to optimize the Z1 axis

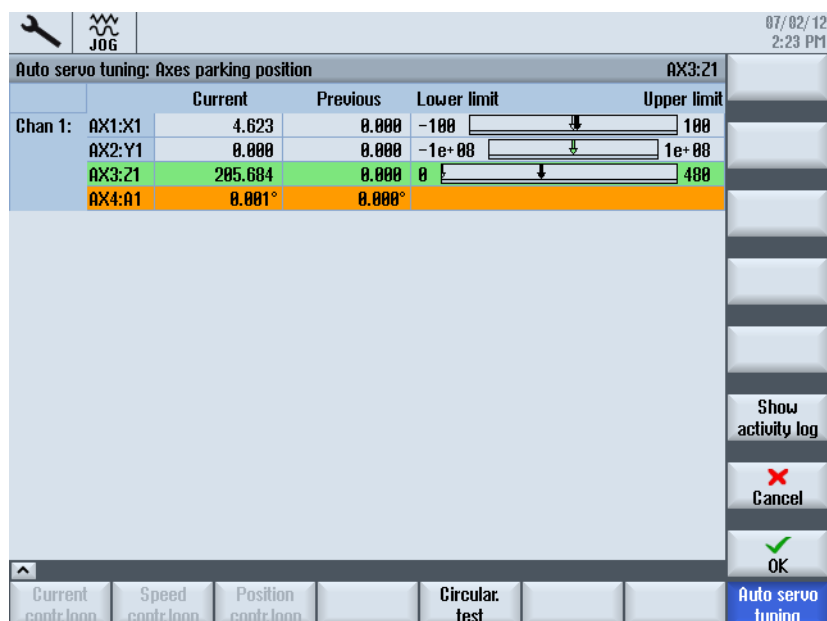
Optimizing the Z1 axis

Procedure:

1. Select the Z1 axis in the "Axis selection" dialog.

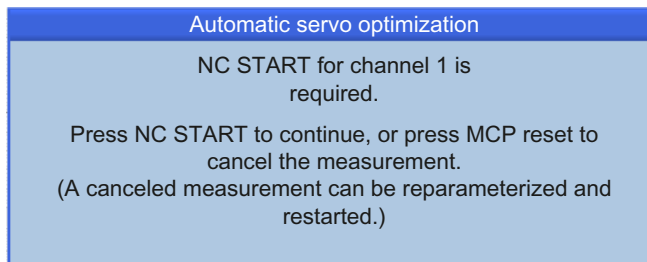


2. The options and strategy that are set continue to be valid.
3. Start the measurement with the "Optimize" softkey.

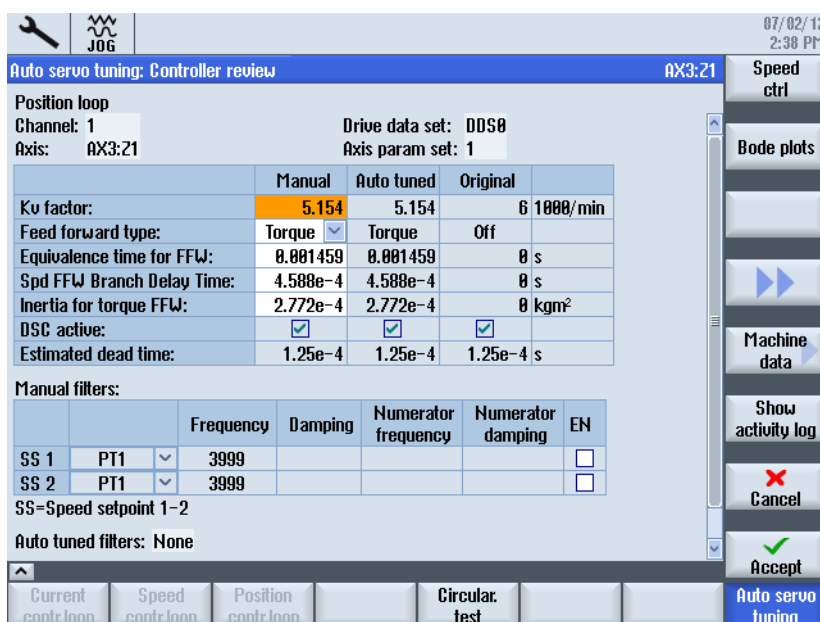


4. Confirm with "OK".

5. Follow the prompts on the screen and press NC START.

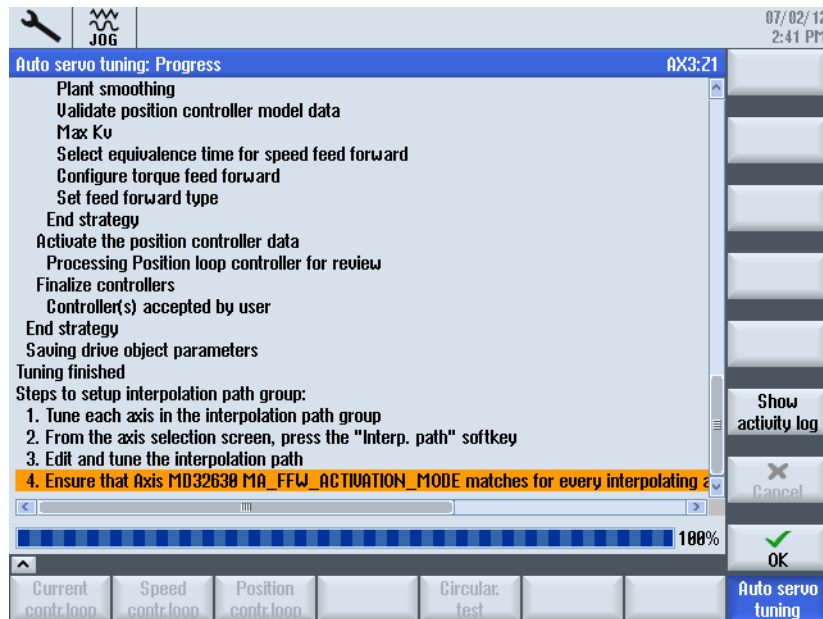


6. Two measurements are taken each time to optimize the axis.
7. Before the measurements are taken, you will be prompted to press NC START. After the successful completion of the measurements, the values of the parameters are output:



8. If you agree with the optimized values, confirm with the "Accept" softkey.
9. OR: Enter new values manually and repeat the measurements.

10. After accepting the measurement results, optimization is complete.



11. After completion of the measurement, you can display the complete optimization log: "Optimization log" softkey.

Z1 axis result

After confirming with "OK", you get the following result:

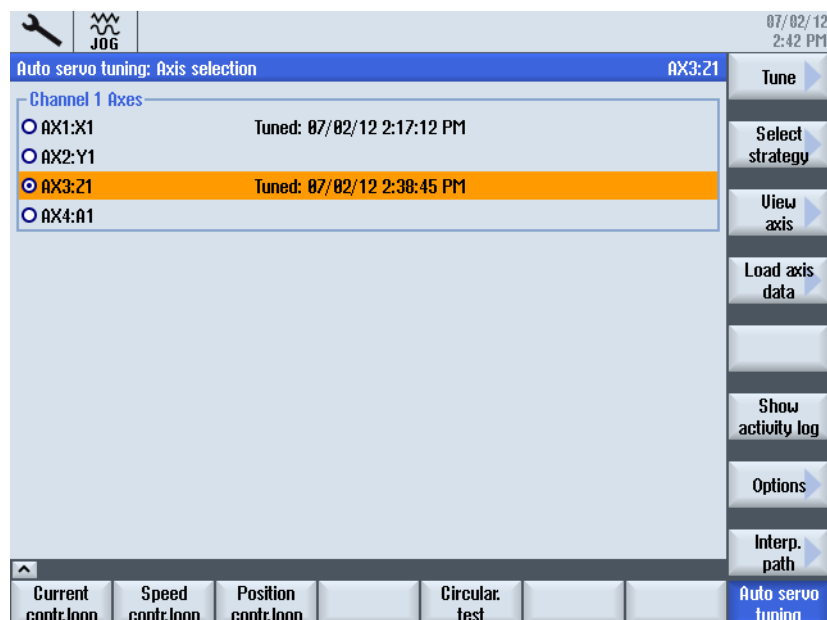


Figure 8-16 Z1 axis: optimized

See also

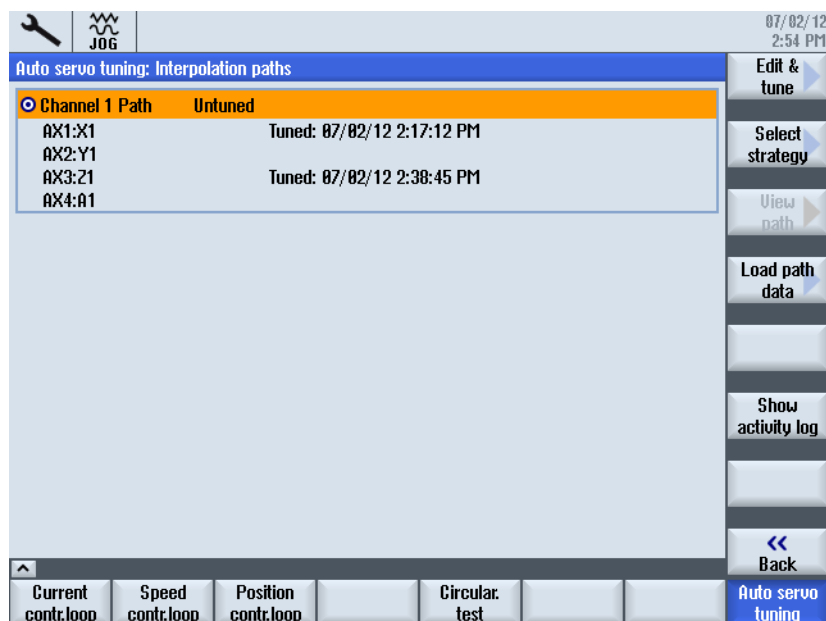
General operating sequences for automatic servo optimization (Page 246)

8.2.7 Example: How to start the interpolation

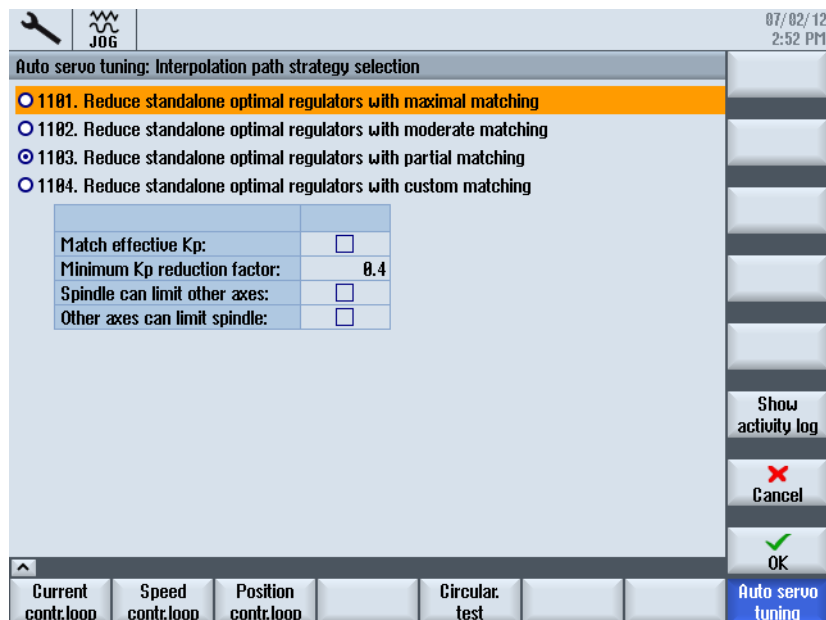
Interpolation of the axes

Procedure:

1. Select the "Interpolation path" softkey to optimize the X1 and Z1 axes.



2. Select the "Select strategy" softkey to check the default setting for the "Interpolation path strategy selection". Accepting the default setting is recommended.



3. Confirm with "OK". This starts optimization.

4. After the "Interpolation path optimization completed" message is output, confirm with "OK".

Then you can switch back and forth between the parameter view (softkey: "Parameters") and the graphical view (softkey: "Bode diagrams").

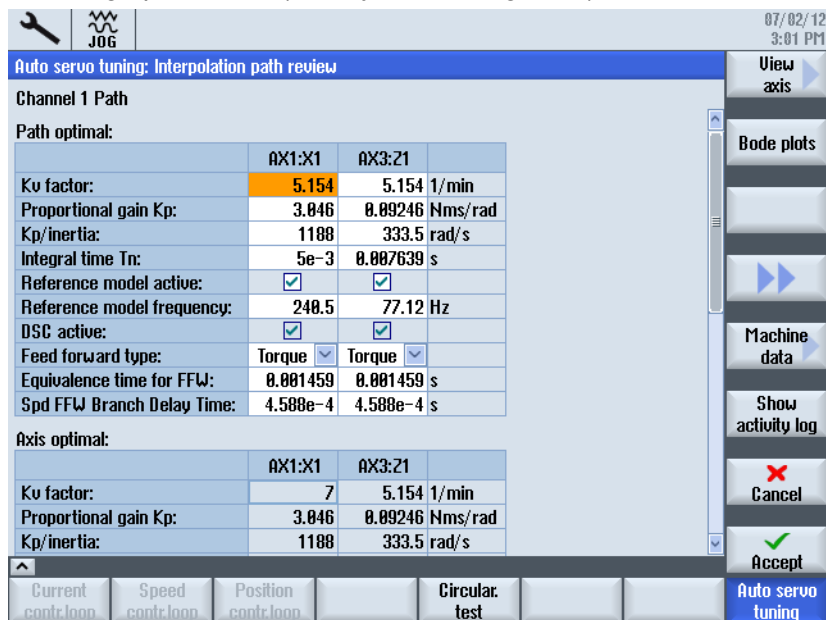


Figure 8-17 Parameter view

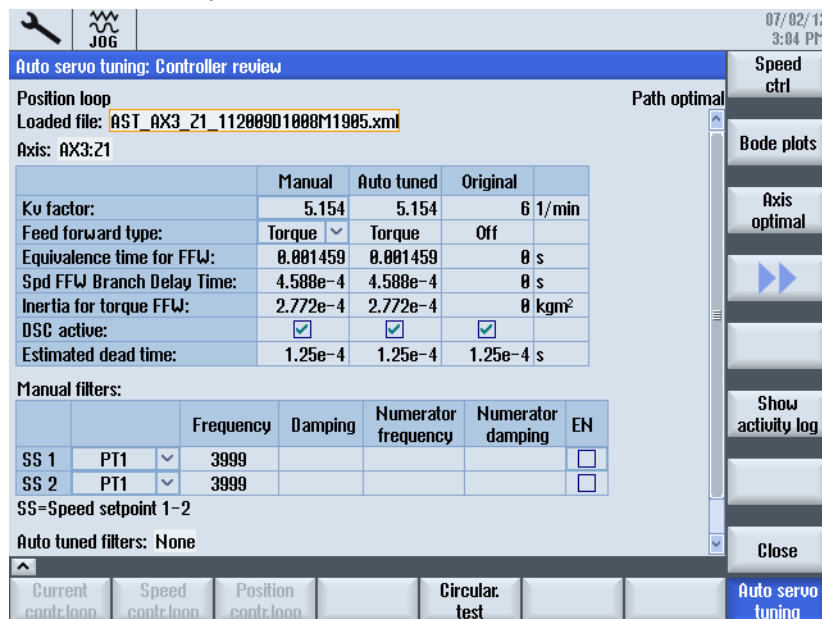


Figure 8-18 Graphic view ***pre-release***

With the ">>" softkey, you can switch the vertical softkey bar to access the following selection:

- Softkey: "Reoptimize"
- Softkey: "Back to optimized"
- Softkey: "Back to axis optimization"
- Softkey: "<<"
- Softkey: "Save to file"

To save the optimization data in a file, select "Save to file": An XML file is created.

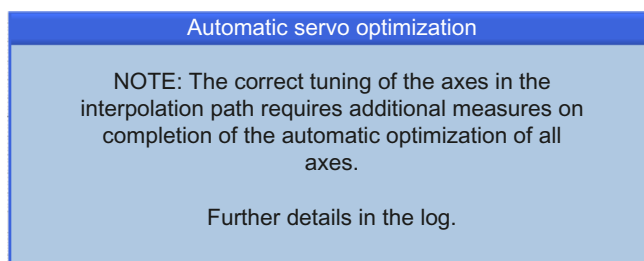


- Softkey: "Generate report"

To create a report, select "Generate report (Page 267)": A report is created in RTF format.

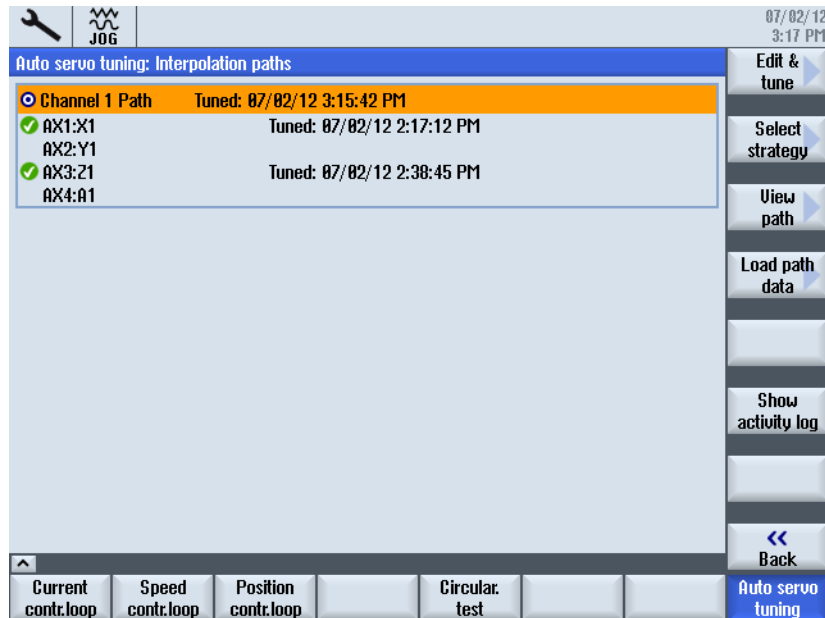
5. To exit the interpolation process, press the softkey: "Close".

This message indicates that more axes must be optimized to provide a regular interpolation result:



Result

If you want to accept the interpolation result, confirm with "Accept". "Cancel" will start the interpolation again.



To check what values the parameters have been set to for optimization purposes, select the "<< Back" softkey.

8.2.8 Example of a report

Logging the result

To document the results of optimization, i.e. parameters and diagrams, you can create the following logs:

- You can save the interpolation result as an XML file: "Save to file" softkey.
- In addition, you can create a report in RTF format: "Generate report" softkey.

Example of a report

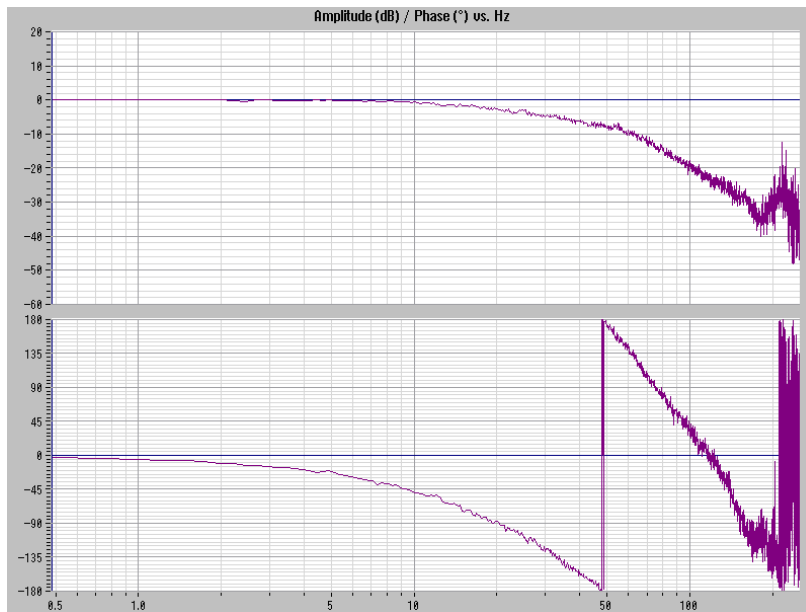
The report is output in the language set on the control system:

Machine

Date of the session	2012-07-02
Time of the session	14:58:42
Machine axis name	Z1
SAT version	4.5.1.0.2

Serial number	112009D1008M1905
Date of the report	2012-07-02
Time of the report	15:07:56
XML file	AST_AX3_Z1_112009D1008M1905.xml

Position controller: Bode diagrams



Optimal standalone:

- (purple) Calculation of closed position control loop without FFW
- (blue) Measured position control loop

Parameter	Optimal standalone	Optimal self-optimized standalone axis	Initial platform configuration	
Servo gain factor	5.154	5.154	6	1/min
Feedforward control mode	Torque	Torque	Off	
Equivalent time for FFW	0.001459	0.001459	0	s
Speed FFW tap delay time	0.0004588	0.0004588	0	s
Moment of inertia for FFW torque	0.0002772	0.0002772	0	kgm ²
DSC active	Correct	Correct	Correct	
Estimated dead time	0.000125	0.000125	0.000125	s
Update date	0.002	0.002	0.002	s

Optimal standalone:		Frequency	XX_D filter amping	Numerator frequency	Numerator damping	Res.	Act.
DS	PT1	3999					
DS	PT1	3999					

Optimal self-optimized standalone axis:		Frequency	XX_D filter amping	Numerator frequency	Numerator damping	Res.	Act.
None							

Initial platform configuration:		Frequency	XX_D filter amping	Numerator frequency	Numerator damping	Res.	Act.
None							

Speed controllers: Bode diagrams



Optimal standalone:

- (purple) Closed speed control loop calculated
- (blue) Closed speed control loop measured

Parameter	Optimal standalone	Optimal self- optimized standalone axis	Initial platform configuration	
Proportional gain Kp	0.09246	0.09246	0.2	Nms/rad
Integral time Tn	0.007639	0.007639	0.05	s
Reference model active	Correct	Correct	Incorrect	

Parameter	Optimal standalone	Optimal self-optimized standalone axis	Initial platform configuration	
Frequency reference model	77.12	77.12	0	Hz
Damping reference model	0.7071	0.7071	1	s
Dead time reference model	0	0	0	s
Actual speed value smoothing time	0	0	0	kgm ²
Motor moment of inertia	2.7e-05	2.7e-05	2.7e-05	kgm ²
Update date	0.000125	0.000125	0.000125	s

Optimal standalone:		Frequency	XX_D filter amping	Numerator frequency	Numerator damping	Res.	Act.
SW	PT2	2000	0.707			X	X
SW	Second order	540.1	0.7071	540.1	0.04158		X
SW	Second order	1213	0.4158	1213	0.172		X
SW	PT2	387	0.707				X

Optimal self-optimized standalone axis:		Frequency	XX_D filter amping	Numerator frequency	Numerator damping	Res.	Act.
SW	PT2	2000	0.707			X	X
SW	Second order	540.1	0.7071	540.1	0.04158		X
SW	Second order	1213	0.4158	1213	0.172		X
SW	PT2	387	0.707				X

Initial platform configuration:		Frequency	XX_D filter amping	Numerator frequency	Numerator damping	Res.	Act.
SW	Second order	500	2.182	550	0.1093	X	X

8.3 Measuring functions

8.3.1 Measuring functions

Explanation of the measuring functions

A range of measuring functions allows the time and frequency response of drives and controls to be displayed in graphical form on the screen. For this purpose, test signals with an adjustable interval are connected to the drives.

Measurement/signal parameters

The test setpoints are adapted to the application in question by means of measurement or signal parameters, the units of which are determined by the relevant measuring function or operating mode. The measurement or signal parameter units are subject to the following conditions:

Table 8- 1 Quantity and units for measurement or signal parameters

Size	Unit
Velocity	Metric system: Specification in mm/min or rev/min for translatory or rotary movements Inch system: Specification in inch/min or rev/min for translatory or rotary movements
Distance	Metric system: Specification in mm or degrees for translatory or rotary movements Inch system: Specification in inch or degrees for translatory or rotary movements
Time	Specified in ms
Frequency	Specified in Hz

Note

The default setting for all parameters is 0.

Preconditions for starting measuring functions

To ensure that no erroneous traversing movements due to part programs can be carried out, the measuring functions have to be started in <JOG> mode.

NOTICE
Collision avoidance
When traversing movements are carried out within the framework of measuring functions, no software limit switches and working area limitations are monitored, since these are carried out in follow-up mode.
Prior to starting traversing movements, the user must therefore ensure that the axes are positioned such that the traversing limits specified within the framework of the measuring functions are sufficient to prevent collision with the machine.

Starting measuring functions

Measuring functions initiating a traversing movement are only selected using the specific softkey. The actual start of the measuring function and thus of the traversing movement is always carried out with <NC-START> on the machine control panel.

If the main screen of the measuring function is quitted without the traversing movement being initiated, the selection of the traversing function is canceled.

Once the traversing function has been started, the main screen can be exited without any affect on the traversing movement.

Note

<JOG> mode must be selected when measuring functions are started.

Further safety notices

The user must ensure that when the measuring functions are used:

- The <EMERGENCY STOP> button is always within reach.
- No obstacles are in the traversing range.

Canceling measuring functions

The following events will cancel active measuring functions:

- Hardware limit switch reached
- Traversing range limits exceeded
- Emergency stop
- Reset (mode group, channel)
- NC STOP

- No controller enabling command
- Canceling drive enable
- Canceling traversing enable
- Selection of parking (in position-controlled operation).
- Feed override = 0%
- Spindle override = 50%
- Change in operating mode (JOG) or operating mode JOG not selected
- Actuation of traversing keys
- Actuation of handwheel
- Alarms leading to axis shutdown

8.3.2 Measurement of current control loop

Functionality

The current control loop only needs to be measured for diagnostic purposes if there is a fault or if there is no standard data for the motor / power unit combination (third-party motor).

NOTICE

Protection of the machine

The user must take special safety measures when measuring the current control loop (e.g. secure drive clamping) for hanging axes without external counterweight.

Operating path

Operating path for measuring the current control loop: Operating area switchover > "Commissioning" > "Optimization/Test" > "Current control loop"

Measuring functions

The following measuring functions are available for measuring the current control loop:

Measuring type	Measured variable
Reference frequency response (downstream of the current setpoint filter)	Torque-generating actual current value / torque-generating current setpoint
Setpoint step change (downstream of the current setpoint filter)	Measured variable 1: Torque-generating current setpoint Measured variable 2: Torque-generating actual current value

Measurement

The measurement sequence is divided into the following steps:

1. Setting the traverse range monitoring and the enable logic
2. Selecting the measurement type
3. Setting the parameters, softkey: "Measuring parameters"
4. Displaying the measurement results, softkey: "Display"



Figure 8-19 Current controller

Measuring parameters

- Amplitude
Magnitude of the test signal amplitude. Given in percent of the peak torque. Values from 1% to 5% are suitable.
- Bandwidth
The frequency range analyzed with the measurement.
The bandwidth depends on the current controller sampling time.
Example:
125 μ s current controller sampling time, set bandwidth 4000 Hz

8.3.3 Speed control loop measurement

Functionality

The response characteristics for the motor measuring system are analyzed when measuring the speed control loop. Various measurement parameter lists are available depending on the basic measurement setting which has been selected.

Operating path

Operating path for measuring the speed control loop: Operating area switchover > "Commissioning" > "Optimization/Test" > "Speed control loop"

Measuring functions

The following measurement functions are available for measuring the speed control loop:

Measuring type	Measured variable
Reference frequency response (downstream of the speed setpoint filter)	Actual speed value motor encoder/speed setpoint after filter
Reference frequency response (upstream of the speed setpoint filter)	Actual speed value motor encoder/speed setpoint after filter
Setpoint step change (downstream of the speed setpoint filter)	Measured variable 1: <ul style="list-style-type: none"> Speed setpoint downstream of the filter Actual torque value Measured variable 2: Actual speed value motor encoder
Interference frequency response (fault downstream of the current setpoint filter)	Actual speed value motor encoder / torque setpoint fct. generator
Disturbance variable step change (fault downstream of the current setpoint filter)	Measured variable 1: <ul style="list-style-type: none"> Torque setpoint fct. generator Actual torque value Measured variable 2: Actual speed value motor encoder
Speed-controlled system (excitation downstream of the current setpoint filter)	Actual speed value motor encoder/actual torque value
Frequency response of the mechanical parts ¹⁾	Actual speed value measuring system 1/actual speed value measuring system 2
1) The machine axis in question must have both a direct and an indirect measuring system to determine the frequency response of the mechanical parts.	

Measurement

The measurement sequence is divided into the following steps:

1. Setting the traverse range monitoring and the enable logic
2. Selecting the measuring type and measured variable

- 3. Setting the parameters, softkey "Measuring parameters"
- 4. Displaying the measurement results, softkey "Display"



Figure 8-20 Speed controller

In the example shown, the speed control loop has not yet been optimized.

A suitable filter parameterization is used to optimize the dynamic response. This can be called with the "Filter" softkey.

The following figure shows the standard settings for a low-pass filter at 1999 Hz (encoder mounting frequency).

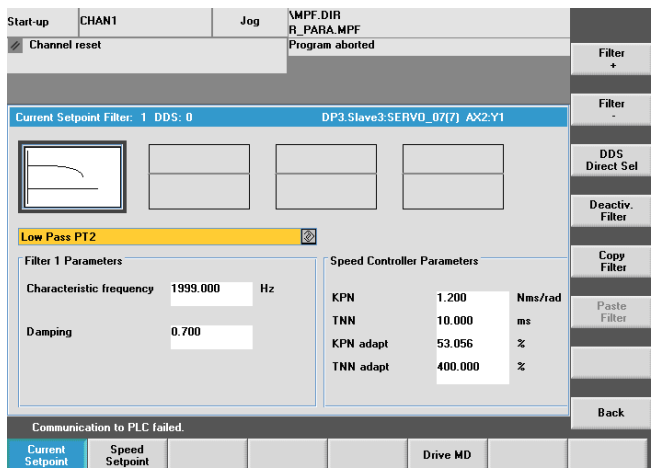


Figure 8-21 Standard settings of the speed control loop filter

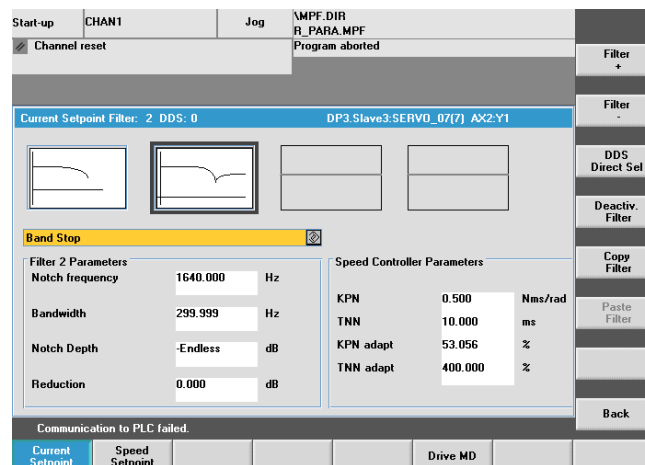


Figure 8-22 Speed control loop filter with rejection band 1190 Hz

The use of a rejection band at 1190 Hz and adaptation of the proportional gain results in the following optimized setting for the speed control loop.



Figure 8-23 Optimized speed control loop

8.3.4 Position control loop measurement

Functionality

This measuring function basically analyzes the response to the active position measuring system. If the function is activated for a spindle without a position measuring system, an alarm is displayed. Depending on the measured variable selected, various measurement parameter lists are displayed.

Operating path

Operating path for measuring the speed control loop: Operating area switchover > "Commissioning" > "Optimization/Test" > "Position control loop"

Measuring functions

The following measuring functions are available for measuring the position control loop:

Measuring type	Measured variable
Reference frequency response	Actual position/position setpoint
Setpoint step change	Measured variable 1: Position setpoint Measured variable 2: <ul style="list-style-type: none"> • Actual position value • System deviation • Following error • Actual speed value
Setpoint ramp	Measured variable 1: Position setpoint Measured variable 2: <ul style="list-style-type: none"> • Actual position value • System deviation • Following error • Actual speed value

Measurement

The measurement sequence is divided into the following steps:

1. Setting the traverse range monitoring and the enable logic
2. Selecting the measuring type and measured variable
3. Setting the parameters, softkey: "Measuring parameters"
4. Displaying the measurement results, softkey: "Display"

The following figure shows an optimized position control loop in which the K_v factor has been adapted via the machine data MD32200 \$MA_POSCTRL_GAIN.



Figure 8-24 Optimized position control loop

Reference frequency response measurement

The reference frequency response measurement determines the transmission ratio of the position controller in the frequency range (active position measuring system).

The setpoint filters, control loop gain (K_v factor) and feedforward control must be parameterized such that resonance is avoided wherever possible over the entire frequency range.

Measuring parameters

- Amplitude

This parameter determines the magnitude of the test signal amplitude. It should be set to the smallest possible value (e.g. 0.01 mm).

- Bandwidth

The bandwidth parameter is used to set the analyzed frequency range. The larger this value, the finer the frequency resolution and the longer the measurement time. The maximum value is specified by the position controller cycle ($T_{\text{position controller}}$):

$$\text{Bandwidth}_{\text{max}} [\text{Hz}] = 1 / (2 * T_{\text{position controller}} [\text{sec}])$$

Example:

Position controller cycle: 2 ms

$$\text{Bandwidth}_{\text{max}} = 1 / (2 * 2 * 10^{-3}) = 250 \text{ Hz}$$

- Averaging

The accuracy of the measurement and measurement duration increase with this value. A value of 20 is normally suitable.

- Settling time

This value represents the delay between recording of the measured data and injection of the test setpoint and offset. A value of between 0.2 and 1 s is recommended. Do not set too low a value for the settling times, or the frequency response and phase diagrams will be distorted.

- Offset

The measurement requires a slight speed offset of a few motor revolutions per minute. The offset must be set such that no speed zero crossings occur at the set amplitude.

Measurement: Setpoint step change and setpoint ramp

The transient or positioning response of the position control in the time range, and in particular the effect of setpoint filters, can be assessed with the step and ramp stimulation functions.

Possible measured variables:

- Actual position value (active position measuring system)
- Control deviation (following error)

Measuring parameters

- Amplitude

Determines the magnitude of the specified setpoint step change or ramp.

- Measurement time

This parameter determines the period of time to be recorded (maximum: 2048 position controller cycles).

- Settling time

This value represents the delay between measured data recording / test setpoint output and the injection of the offset.

- Ramp time

With default setting: The position reference value is specified with the "Setpoint ramp" according to the set ramp time. In this case, the acceleration limits which currently apply to the axis or spindle are effective.

- Offset

The step is stimulated from standstill or starting from the constant traverse speed set in this parameter.

If an offset value other than zero is input, the step change is stimulated during traversal. For the sake of clarity, the displayed actual position value does not include this speed offset.

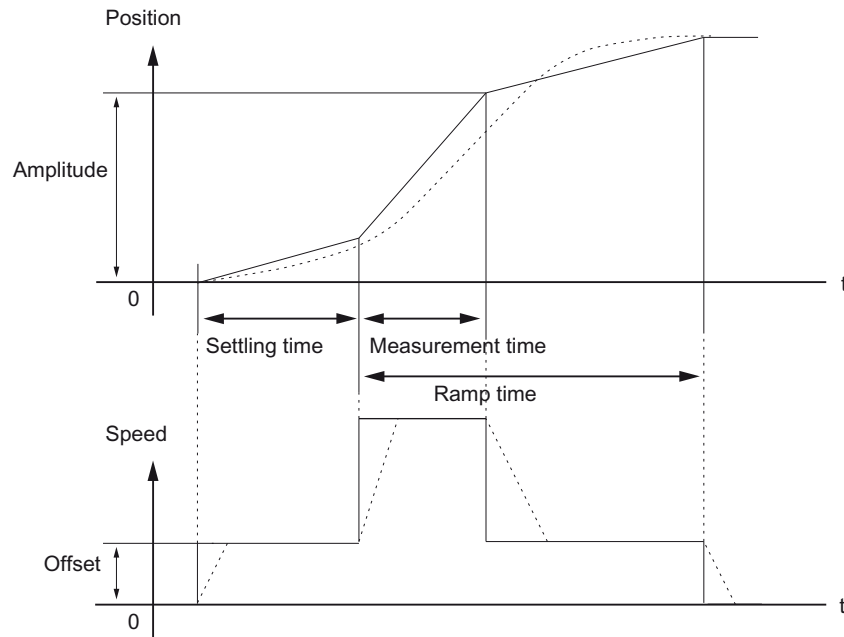


Figure 8-25 Signal chart for position setpoint/ramp measuring function

At maximum axis velocity, there is a (virtual) step change in the velocity (continuous line).

The curves represented by the dashed line correspond to a realistic, finite value. The offset component is excluded from the display graphic in order to emphasize the transient processes.

Measurement: Setpoint step change

To avoid overloading the mechanical system of the machine, the step height is limited to the value specified in the machine data during the "Setpoint step change" measurement:

- MD32000 \$MA_MAX_AX_VELO (maximum axis velocity)

This may result in failure to achieve the desired step height.

Measurement: Setpoint ramp

With measurement "Setpoint ramp", the following machine data influences the measurement result:

- MD32000 \$MA_MAX_AX_VELO (maximum axis velocity)

The maximum axis velocity limits the ramp gradient (velocity limitation). The drive does not reach the programmed end position (amplitude).

- MD32300 \$MA_MAX_AX_ACCEL (maximum axis acceleration)

The maximum axis acceleration limits the velocity change (acceleration limitation). This leads to "rounding" on the transitions at the beginning and end of the ramp.

NOTICE

Protection of the machine

In normal cases the machine data corresponds exactly with the load capacity of the machine kinematics and should not be changed (increased) as part of the measurements:

- MD32000 \$MA_MAX_AX_VELO (maximum axis velocity)
- MD32300 \$MA_MAX_AX_ACCEL (maximum axis acceleration)

8.3.5 Function generator

Function description

The function generator can be used, for example, to perform the following tasks:

- Measuring and optimizing closed-loop control circuits
- Comparing the dynamic properties of coupled drives
- Specifying a straightforward traversing profile without traversing program

The function generator can be used to generate various signal forms.

In the Servo mode, the setpoint can additionally be supplied into the control structure in accordance with the currently selected mode, for example, as a current setpoint, disturbing torque or speed setpoint. Any influence of overlaid closed-loop control circuits is suppressed automatically.

Position of the application points:

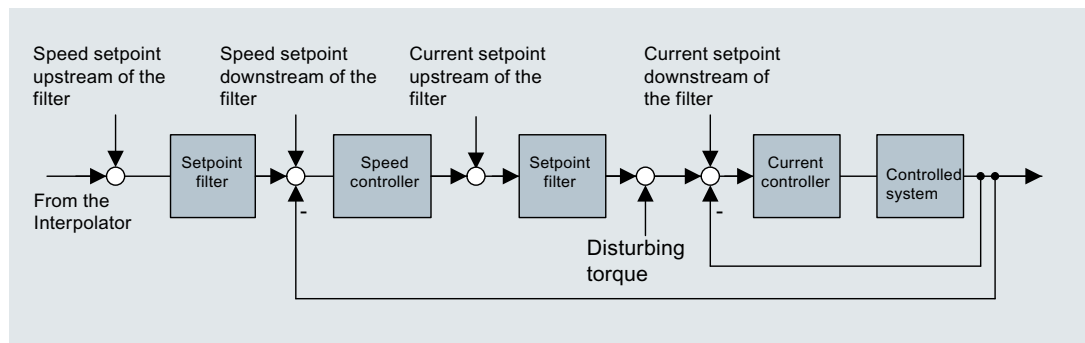


Figure 8-26 Application points

To activate the function generator, select "Commissioning" operating area → "Automatic servo optimization" → "Function generator".



CAUTION

Starting/stopping the function generator

With the corresponding function generator parameter settings (e.g. offset), the motor can "drift" and travel to its end stop. The drive movement is not monitored for activated function generator.

8.4 Circularity test

8.4.1 Circularity test: Function

The circularity test serves to set and assess the dynamic response for interpolating axes and to analyze the contour accuracy on the quadrant transitions (circular contours) achieved by means of friction compensation (conventional quadrant error compensation).

The circularity test is used to check the interpolation of the axes which work together. This function measures a circle with reference to the motor or to the direct measuring system. Alignment of the machine-mechanical equipment is not taken into account in the result. This gives the commissioning engineer the option of separating problems with the controller optimization from mechanical problems.

The following axis machine data and parameters are checked with this procedure:

- MD32200, MD32400, MD32402, MD32410, MD32490, MD32500, MD32510, MD32520, MD32540 MD32620, MD32640, MD32810, MD32900, MD32910, MD32930, MD32940
- p1421 to p1426, p1400, p1433, p1434

Note

MD32450 backlash must be adjusted via an external device, such as a circularity test or gauge.

The following position error compensations should be disabled if this procedure is carried out:

- MD32450 backlash compensation
- MD32500 friction compensation active
- MD32700 Encoder/lead error compensation
- MD32710 enable sag compensation
- MD32750 Temperature compensation type

Example

NC test program for the measurement of the X-Y axes:

```
FFWON
SOFT
G90 G01 F3000 X400 Y200 Z500
LAB:
G91 G64 G02 X0 Z0 I10
GOTOB LAB
M30
```

Position, feedrate and active plane must be adjusted to the machine!

Specification and results

The best contour results are achieved when the circular form test results are in the correct actual size, shape and minimum p/p deviation between a combined interpolation of the axes (X-Y, X-Z, Y-Z).

An NC program in the MDA operating mode and the circularity test function are used to measure and evaluate these results. The "worst case" of a circle radius and the path velocity must lead to a realistic radial acceleration of which the machine is capable.

Machine manufacturers generally have specifications for the radius and feedrate test circuit.

Circularity tests of machine manufacturers usually use a radius of 100 mm or 150 mm with feedrate speeds that are determined by the machine manufacturer. The machine manufacturer determines the specifications for an acceptable result.

High-speed processes generally have higher requirements for testing circles with high-speed milling machines and can range from circle radii of 10 - 25 mm and feedrates of 5 - 10 m/min. For high-speed milling machines, the results are generally acceptable if the P/P deviation ≤ 0.010 mm and the actual size of the circle is equal to the programmed radius, and in the worst-case scenario to the path velocity.

8.4.2 Circularity test: Performing the measurement

Setting parameters

07/09/12 4:43 PM

Circularity test measurement

Measurement

Axis:	Meas. system:	Absolute position:	Status:
X1	1 Active	15.05000 mm	Inactive
Z1	2 Active	-61.83000 mm	Inactive

Parameter

Radius:	10.0000 mm
Feedrate:	3000.0000 mm/min
Multiplier:	1.0000
Meas. time:	1257 ms

Representation:

Resolution	0.0100 mm/Skt
Represent.:	Mean radius

Axis+
Axis-
Start
Stop
Graphic
Opti-mization
Load parameters
Save parameters
Auto servo tuning

Current contr.loop Speed contr.loop Position contr.loop **Circular. test**

Figure 8-27 Circularity test - measurement: Parameters

Enter the following parameters to carry out a measurement:

- **"Measurement"**: Selection of the two axes that are meant to be measured and of the measuring system.
- **"Parameter"**: The parameter settings in the input fields "Radius" and "Feed" must correspond to the values from the part program that controls the circular motion of the axes, taking account of the feed override switch setting.
- **"Representation"**: Parameters for displaying the graphics
 - "Resolution" (scaling) of the diagram axes in [mm/scaled]
 - "Display" via the mean radius or programmed radius

Perform measurement

Procedure:

1. In the "Commissioning" operating area select the "Optimization/Test" softkey → "Circularity test" softkey.
2. Select the axes that are meant to be measured with the <SELECT> key or using the "Axis+/" "Axis -" softkeys.
3. Set the "parameters" for the measurement: "Radius" and "Feed"

The "Measuring time" display field shows the measuring time calculated from the "Radius" and "Feed" values for recording the actual position values during the circular movement:

If the measuring time is not sufficient then only parts of the circle are portrayed. The measuring time can be increased by reducing the feed value. This also applies if the circularity test is started from the stationary condition.

4. Set the parameters for displaying the graphic:

If the measuring time calculated from this exceeds the time range that can be displayed (maximum measuring time = position controller cycle frequency * 2048), a coarser sampling rate is used for recording ($n \cdot \text{position controller cycle frequency}$), so that a complete circle can be displayed.

Further actions:

- To start the measurement, press the "Start" softkey.
- To stop the measurement, press the "Stop" softkey.
- To make further adjustments for optimization, press the "Optimization" softkey.
- On a new softkey bar, you can navigate **directly** to the following areas:
 - "Service axis" in the "Diagnostics" operating area
 - "Axis machine data"
 - "Drive machine data"
 - "User Views"

- In order to save the parameters for a measurement, press the "Save parameter" softkey.
- In order, for example, to repeat a measurement with the same parameters, press the "Load parameter" softkey.

Displaying a graphic

In order to display the measurement result as a graphic, press the "Graphic" softkey.

8.4.3 Circularity test: Examples

The MD32400 \$MC_AX_JERK_ENABLE axial jerk limitation is set via a time constant and is always active.

Machine data for setpoint filter:

- MD32402 \$MC_AX_JERK_MODE = Type 2 is recommended, type 1 is preset for compatibility reasons. Parameterizing a pure band-stop filter is expressly not recommended.
- MD32402 \$MA_AX_JERK_MODE (filter type) and MD32410 \$MA_AX_JERK_TIME > 0 is effective only if MD32400 \$MA_AX_JERK_ENABLE = 1 is set.

Example 1 for optimization

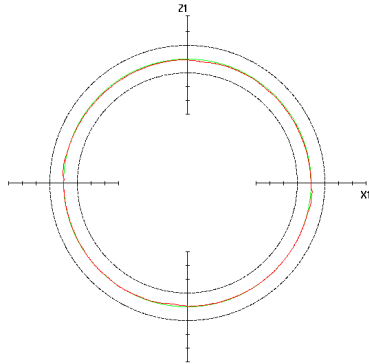
Machine data after optimization of the axes:

Parameters / machine data		X axis	Z axis
MD32200	\$MC_POSCTRL_GAIN	8.500	8.500
p1460	SPEEDCTRL_GAIN1	3.01	3.89
p1462	SPEEDCTRL_INTEGRATOR_TIME_1	6.18	6.18
p1463	SPEEDCTRL_REF_MODEL_FREQ	106.3	106.3
p1440	NUM_SPEED_FILTERS	0	0
MD32610	\$MC_VELO_FFW_WEIGHT	1.0	1.0
MD32620	\$MC_FFW_MODE	4	4
MD32810	\$MC_EQUIV_SPEEDCTRL_TIME	0.0022	0.0022
MD32400	\$MC_AX_JERK_ENABLE	0	0

The actual value of the radius is generally too large with optimized feed precontrol. This can be corrected with the MD32410 \$MC_AX_JERK_TIME time constant. Use a time constant in all axes if required.

This circle displays the results after the feed precontrol has been optimized. However, the mean radius is 0.0019 mm too large:

X1: active measuring system
Z1: active measuring system



Parameter

Radius: 10.00000 mm

Feedrate: 3000.00000 mm/min

Measurement time: 1257 ms

X1: active measuring system

Z1: active measuring system

Representation

Resolution: 0.01000 mm

Representation: mean radius

Radius: 10.00190 mm

Delta R: 4.02698 µm

Parameters / machine data		X axis	Z axis
MD32200	\$MC_POSCTRL_GAIN	8.500	8.500
p1460	SPEEDCTRL_GAIN1	3.01	3.89
p1462	SPEEDCTRL_INTEGRATOR_TIME_1	6.18	6.18
p1463	SPEEDCTRL_REF_MODEL_FREQ	106.3	106.3
p1440	NUM_SPEED_FILTERS	0	0
MD32610	\$MC_VELO_FFW_WEIGHT	1.0	1.0
MD32620	\$MC_FFW_MODE	3	3
MD32810	\$MC_EQUIV_SPEEDCTRL_TIME	0.0022	0.0022
MD32400	\$MC_AX_JERK_ENABLE	1	1
MD32402	\$MC_AX_JERK_MODE	2	2
MD32410	\$MC_AX_JERK_TIME	0.012	0.012

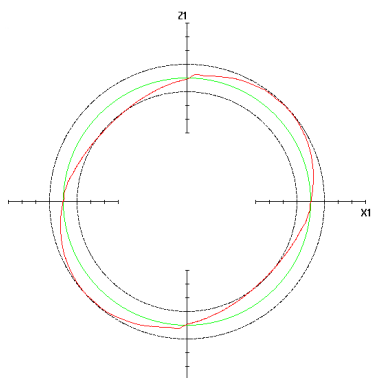
Example 2 for optimization

This circle shows the effect of a slightly different time constant for the axial jerk filter. The time constant is adapted in order to correct this type of error:

Parameters / machine data		X axis	Z axis
MD32400	\$MC_AX_JERK_ENABLE	1	1
MD32402	\$MC_AX_JERK_MODE	2	2
MD32410	\$MC_AX_JERK_TIME	0.012	0.0125

X1: active measuring system

Z1: active measuring system



Parameter

Radius: 10.00000 mm

Feedrate: 3000.00000 mm/min

Measurement time: 1257 ms

X1: active measuring system

Z1: active measuring system

Representation

Resolution: 0.01000 mm

Representation: mean radius

Radius: 10.00029 mm

Delta R: 25.47002 µm

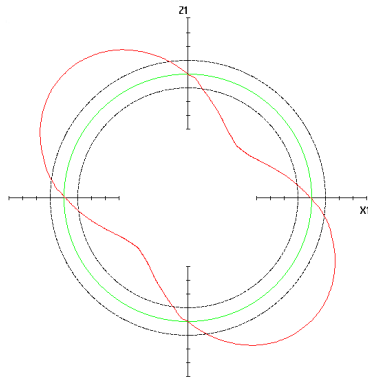
Example 3 for optimization

This circle shows the effect of a considerably different time constant for the axial jerk filter. The time constant is adapted in order to correct this type of error:

Parameters / machine data		X axis	Z axis
MD32400	\$MC_AX_JERK_ENABLE	1	1
MD32402	\$MC_AX_JERK_MODE	2	2
MD32410	\$MC_AX_JERK_TIME	0.015	0.012

X1: active measuring system

Z1: active measuring system



Parameter

Radius: 10.00000 mm

Feedrate: 3000.00000 mm/min

Measurement time: 1257 ms

X1: active measuring system

Z1: active measuring system

Representation

Resolution: 0.01000 mm

Representation: mean radius

Radius: 9.98971 mm

Delta R: 75.67665 µm

8.4.4 Circularity test: Saving data

The following data can be backed up with the circularity test:

- **Save parameters:** The parameters entered can be saved as a file.

The following path is the default path:

user/sinumerik/hmi/log/optimization/cicular/<name>.sup

- **Save graphic:** If the graphic has been saved correctly the message "Data was saved" appears, otherwise an "Error in saving the file" error message is received.

The following path is the default path:

user/sinumerik/hmi/log/optimization/cicular/<name>.sud

- **Print graphic:** The graphic is saved as a pixel graphic in PNG format. Type in a name.

The name can be freely selected. The following path is the default path:

user/sinumerik/hmi/log/optimization/cicular/<name>.png

Save parameters

The file format is structured as follows (with comments in brackets[])

```
H: CstPar [Identifier for circularity test parameters]
V: 5.0 [Version number of the file format]

@Measurement
P 1: 1 [Axis number first axis]
P 2: 2 [Axis number second axis]
P 3: 0 [Measuring system Axis 1 - 0: active; 1:first; 2: second]
P 4: 0 [Measuring system Axis 2 - 0: active; 1:first; 2: second]

@ parameters
P 10: 30 [Radius]
P 11: 3000 [Feed]
P 12: 3770 [Measuring time]
P 14: 1 [Multiplier]

@Representation
P 20: 10 [Resolution]
P 21: 8 [mean / prog. radius - 8 = mean R ; 9 = prog. Radius]
```

Save graphic

The file format is structured as follows (with comments in brackets[]):

```
H: CstPic [Identifier for circularity test graphic]
V: 5.0 [Version number of the file format]

@ parameters
P 1: 30 [Radius]
P 2: 3000 [Feed]
P 3: 3770 [Measuring time]
P 4: 0 [Measuring system Axis 1 - 0: active; 1:first; 2: second]
P 5: 0 [Measuring system Axis 2 - 0: active; 1:first; 2: second]

@Representation
P 10: 10 [Resolution]
P 11: 9 [mean / prog. radius - 8 = mean R ; 9 = prog. Radius]
P 12: X1 [Axis name 1]
P 13: Z1 [Axis name 2]

@Intermediate values
P 20: 15.6632 [max. radius measured values]
```

```
P 21: 10.9326 [min. radius measured values]
P 22: 13.6694 [mean radius measured values]
P 23: 1886 [Number of measured values]
@Additional values
P 30: 1000 [Accuracy (1/P30))
@Physical units
P 40: 5370 [Text number radius unit]
P 41: 5381 [Text number feed unit]
P 42: 6165 [Text number Resolution unit]
P 43: 5346 [Text number DeltaRadius unit]
P 44: 0 [New: Operate: Basislengthunit]
@Abscissa
Ai:   [Abscissa values i: 0..P23]
@Ordinate
Oi:   [Ordinate values i: 0..P23]
@Radius
Ri:   [Radius values i: 0..P23]
```

Commissioning of PLC-controlled drives

9.1 Introduction

Commissioning of PLC-controlled drives

The following tools support the commissioning of PLC-controlled drives of SINAMICS S120 type:

- All parameters of the drive DOs are shown in the operating area "Commissioning" → "Machine data", e.g.
 - "Control Unit Parameter" for the DO1 drive unit
 - "Infeed MD" for DRIVE-CLiQ Line Module DO2
 - "Drive MD" for drive control DO

Parameters of the integrated drives with SINUMERIK view as well as PLC-controlled drives with SINAMICS view are displayed.

- Support for the series commissioning of the PLC-controlled drives, because the parameters are contained in the commissioning archive.
- Topology views, including a list of all of the drive units of this type that have been found.
- Diagnostics with alarms from these PLC drives whose time stamp is synchronized with the system.

In this case, it is necessary that the following general machine data is pre-assigned:

- **MD13120[...] \$MN_CONTROL_UNIT_LOGIC_ADDRESS**
I/O address on a DO1 telegram of the SIEMENS telegram 390 type
- **MD13150 \$MN_SINAMICS_ALARM_MASK**
Bit 2 =1, to indicate failures of the PLC-controlled drives.
Bit 10 =1, to indicate warnings of the PLC-controlled drives.
- SINUMERIK Operate (only for PROFIBUS connection):
 - Automatic device configuration (Page 78)
 - Guided commissioning (Page 76) with the drive wizards for SERVO DOs.
 - Manual commissioning (Page 101) performed by experienced commissioning engineers.

Note

SINAMICS G1x0 type drives

Guided commissioning wizards, e.g. for vector control are not provided by SINUMERIK Operate. To do this, the STARTER commissioning software appropriate for the version can be used.

PLC axes can only be used with the "basic positioning" (EPOS) function module if commissioning takes place via STARTER.

In general, SINUMERIK Operate does not support drives of the SINAMICS G1x0 type and treats them like third-party devices.

9.2 Configuration via PROFIBUS

9.2.1 Boundary conditions for PLC drives via PROFIBUS

Permissible version combinations

For PLC-controlled drives connected via PROFIBUS DP, the following applies:

- Supply and disposal directly from the PLC user program.
- Integrated in the part program operations using an H command.

Note

In certain version combinations, the integration functions are checked for compatibility.

As of SINUMERIK CNC V4.5 software, the following versions are supported:

CU320-2 DP with SINAMICS firmware version 4.5

All other SINAMICS drives can be connected to the PLC as standard slaves in accordance with the PROFIdrive profile and are not included in the quantity structure, according to the following "Quantity structure" table.

Quantity structure

Scaling	SINUMERIK 840D sl NCU type:		
	710.3 PN	720.3 PN	730.3 PN
Drives (drive control DOs) in total ²⁾ :	15	40	50
• of which, assigned to the NC, maximum ²⁾ :	8	31	31
• resulting from this, those not assigned to the NC, minimum:	7	9	19
• not assigned to the NC, maximum:	15	40	50
Drives units (DO1) with drive control objects, in total ²⁾ :	9	13	15
• of which, at the virtual, integrated PROFIBUS, maximum ³⁾ :	4	6	6
• of which, at the virtual, integrated PROFIBUS, minimum:	1	1	1
• of which at the DP interface ¹⁾ minimum:	5	7	9
• of which at the DP interface ¹⁾ maximum:	8	12	14

¹⁾ X126: PROFIBUS DP of the integrated PLC; X136: PROFIBUS DP/MPI of the integrated PLC

²⁾ The sum is monitored using Alarm 380077

Supplementary conditions

The additional operator control options for the PLC drives produce the following general conditions:

- Because the PLC drives create an additional communication load, the number of these drive objects (DO) limits depending on the NCU \Rightarrow note the quantity structure:
- Alarm 380077 "PROFIBUS/PROFINET: Too many DOs: currently %2, maximum %3 in DO group %1"
- Depending on the versions used, the texts displayed for the SINAMICS parameters and alarms can be incomplete.
- The extended operator control options are guaranteed in conjunction with the drive unit, infeed and the axis drive SERVO-DO. This is the reason why a device-granular view is considered. All SERVO-DOs of a drive unit can either be assigned to the NC or PLC.
- As a maximum, all NC axis assignments can be made on axis drives at the external PROFIBUS DP (X126).
- If the drives are assigned to the NC and distributed across several buses, such as DP and DP integrated, then it must be ensured that each equidistant bus has the same clock cycle settings. It is also true for the clock synchronization via NC with telegram 390 that the cycle settings match for each equidistant bus.
- A DO1 drive unit is required for the internal virtual PROFIBUS DP3 for access to the onboard I/O including probe.
- ADI4 can only be assigned to NC axes. The number of ADI4 does not reduce the maximum number of managed DO1 drive units.
- A 611U connected to SINUMERIK solution line is not supported; it has not been checked as far as its reactions are concerned - and has therefore not been released.
- PLC drives of the SINAMICS S120 CU320-2 DP type communicate on the external PROFIBUS DP-X126 as PN-IO 0x80E5.

Note

PROFIBUS DP (X126)

For all drive units connected to an external PROFIBUS DP (X126) , note the following:

- In the configuration, the user must take into account the supply as well as the switch-on and switch-off behavior in interaction with the other axes and their supply.
 - For the terminal wiring, observe the "Machine Configuration Guidelines" system manual. In the simplest case, the feedback of the Line Module to the PLC drives must be wired (see also: Terminal assignment (Page 71)).
-

9.2.2 Example: Configuration of the drive components

Overview

The SINAMICS drive system for PLC-drives communicates with the PLC via the PROFIBUS DP X126 interface. The commissioning described in this chapter orientates itself on the following example configuration of the SINAMICS drive line-up:

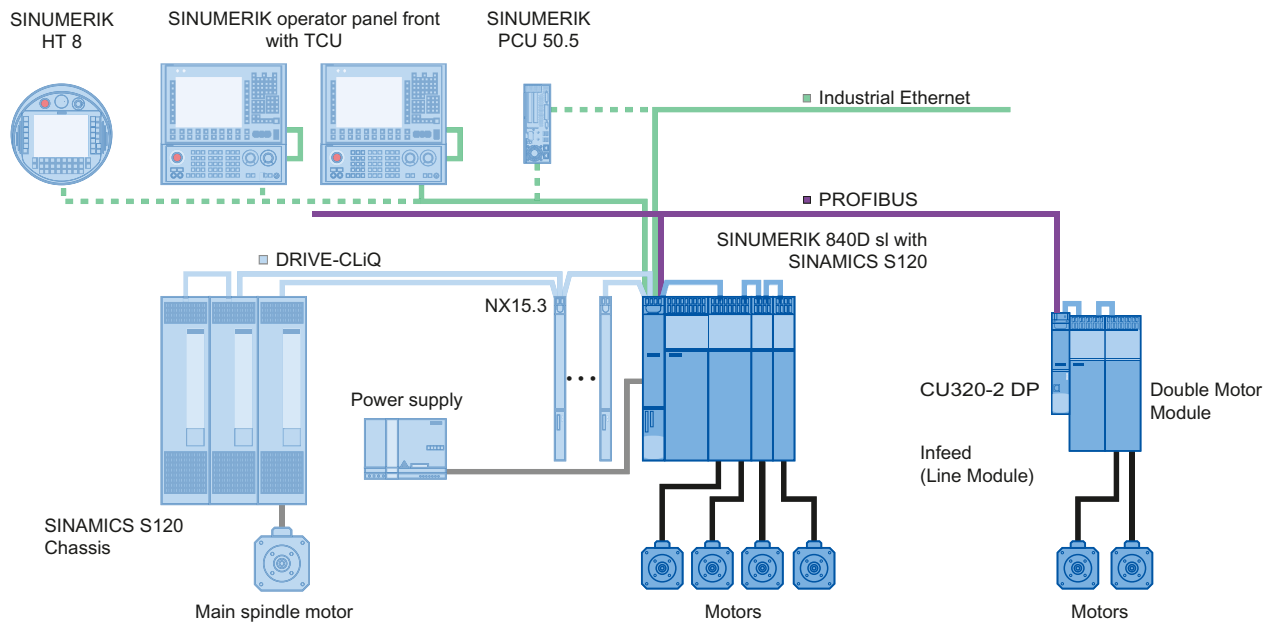


Figure 9-1 Configuration

Already commissioned are:

- NCU 720.3 PN and NX15.3 with additional components.

In this section, the following will be put into operation:

- CU320-2 DP with an infeed (Line Module) and a Double Motor Module.

9.2.3 Commissioning the PLC

Overview

The following steps are performed when commissioning PLC drives for the first time:

1. PLC commissioning
2. Generation of the PLC user program
3. Commissioning the PLC drives
4. Commissioning NCK ⇔ drive communication

Precondition

- You have connected the PG/PC to the PLC (see Connect PG/PC with the PLC (Page 33)).
- You have started the SIMATIC Manager and created a project (see SIMATIC S7 project overview (Page 35)).
- You have inserted a SIMATIC Station-300 in the project (see Inserting SINUMERIK NCU to the HW Config (Page 36)).
- You have started HW Config.
- On the integrated PROFIBUS you have configured an NCU 720.3 PN and NX15.3.

Communication interfaces

The PLC must be notified of the PROFIBUS communication interfaces of SINAMICS. You generate a SIMATIC S7 project using the SIMATIC Manager.

To do this, perform the following steps:

- Insert an S120 CU320-2 DP in HW Config.
- Configure the properties of the PROFIBUS interface.
- Compile the configuration and then download it to the PLC.

See also: PLC commissioning (Page 33) for the integrated drive.

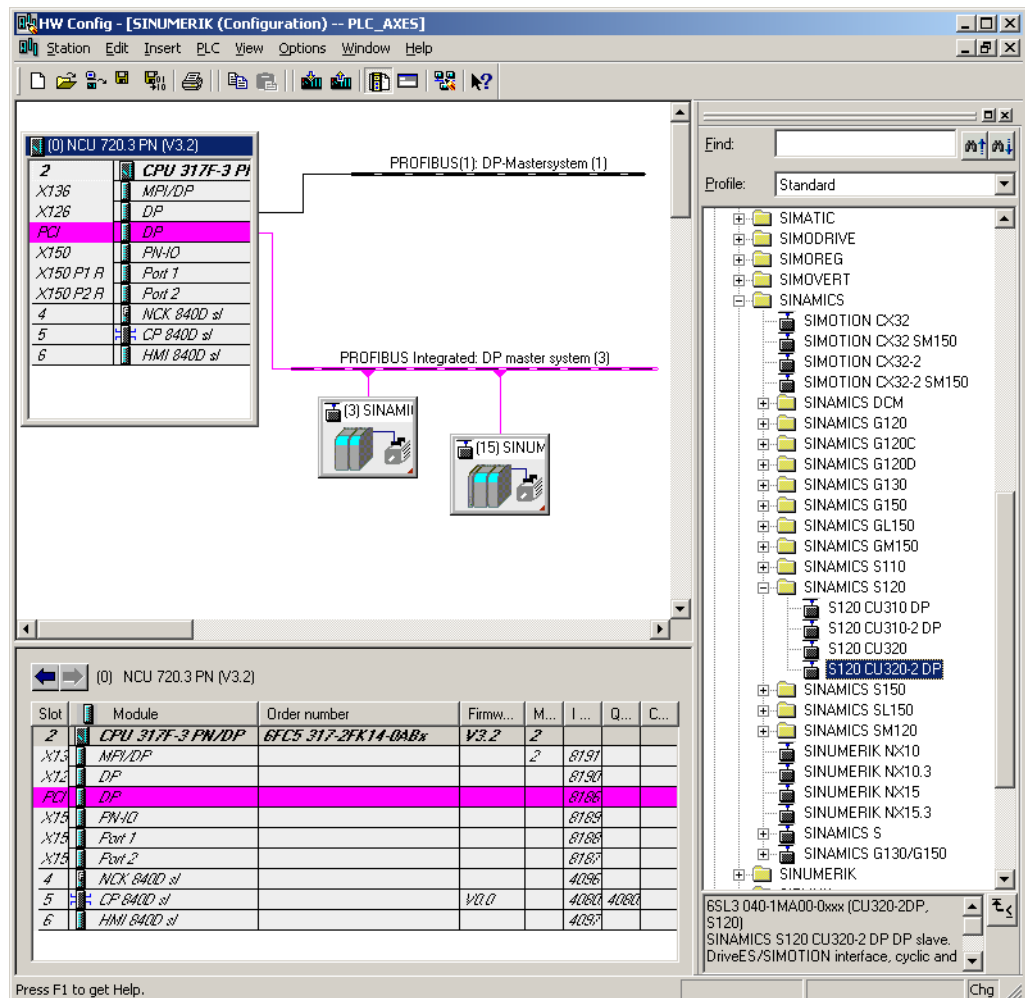
Note

The toolbox must have been installed. The GSD file for SINAMICS S120 from the SINUMERIK toolbox is required for configuration.

Inserting an S120 CU320-2 DP component

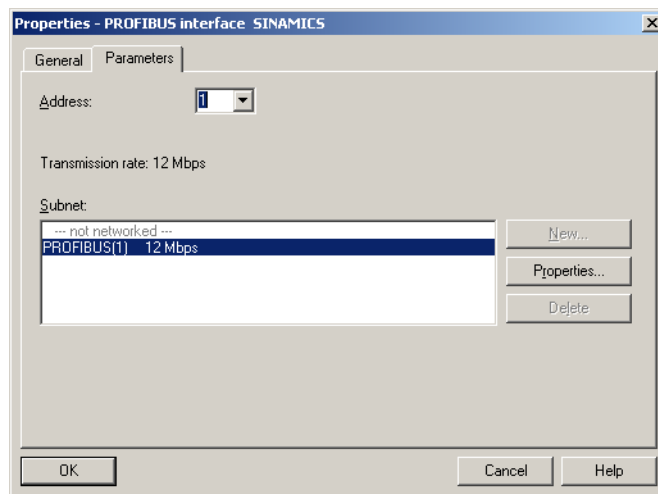
Procedure:

1. Navigate in the catalog to "PROFIBUS DP" → "SINAMICS" → "SINAMICS S120" → "S120 CU320-2 DP":



2. Keeping the left mouse key pressed, drag the "S120 CU320-2 DP" in the station window to PROFIBUS (1): DP master system.

3. After releasing the mouse key, configure the properties of the SINAMICS PROFIBUS interface:



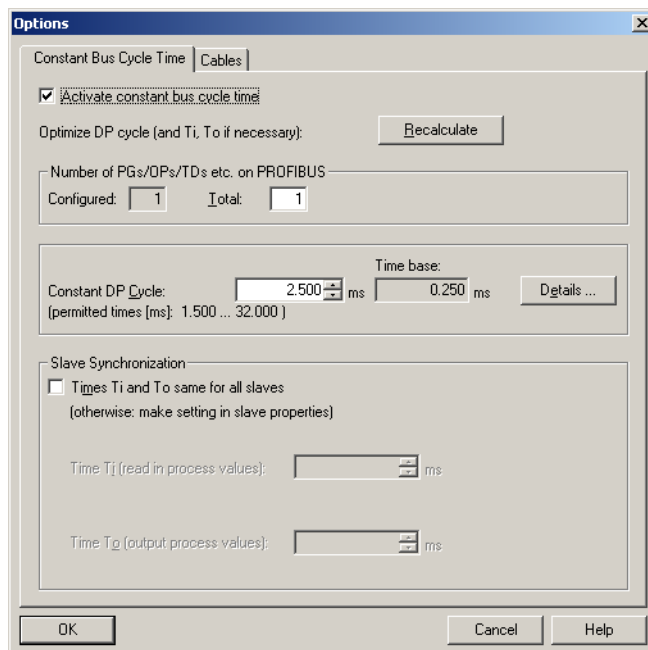
4. Confirm with "OK".
5. In the "Version" selection box, select the firmware version of the Control Unit.

Note

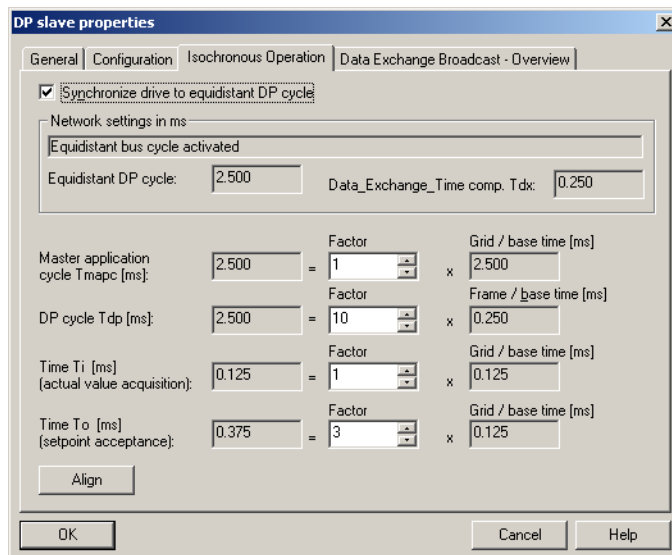
The firmware version must match the version of the CompactFlash card on the CU320-2 DP. Refer to the upgrade instructions for the versions that have been released for PLC drives.

6. Confirm with "OK".

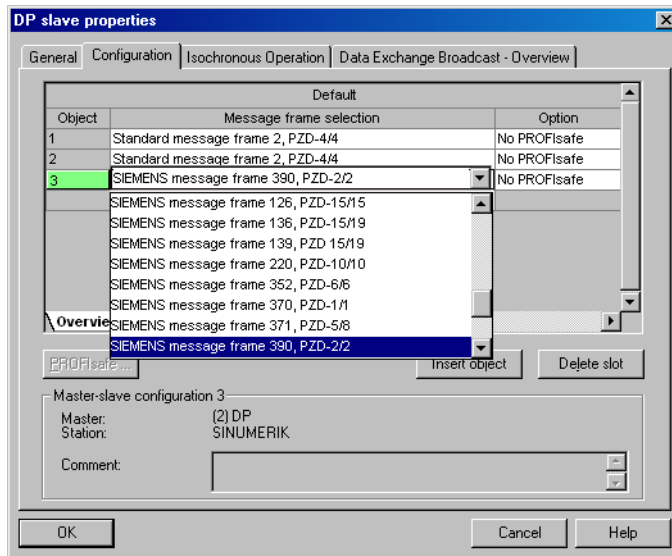
7. In the PROFIBUS DP master system (SINUMERIK NCU) under "Properties" → "Network settings" → "Options" and under the "Equidistance" tab activate the option "Activate equidistant bus cycle".



8. In the "DP Slave Properties" of the CU320-2 DP under the tab "Clock synchronization", activate the option "Synchronize drive to equidistant DP cycle".



9. In the "DP Slave Properties" dialog box, select the "Configuration" tab.



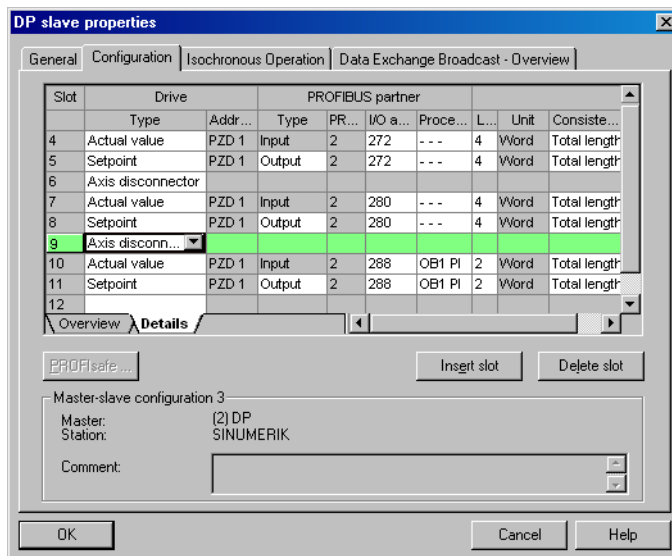
10. Select in the "Overview" the telegrams required for the individual objects (axes and CU320-2 DP):

- "Siemens telegram 2, PZD-4/4" for example, for speed-controlled axes
- "Siemens telegram 390, PZD-2/2" for CU320-2 DP

Note

SIEMENS telegram 390 is required for the time stamp of the PLC alarms.

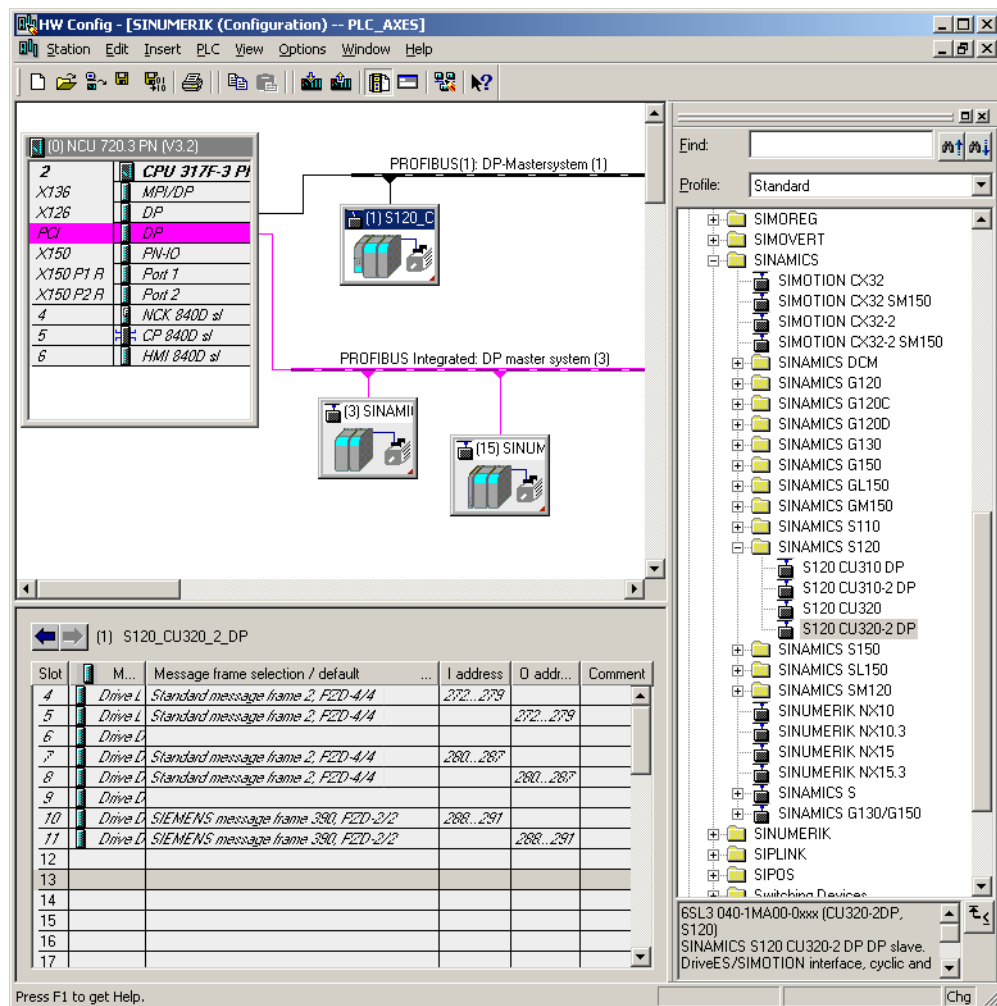
11. Change under "Configuration" to the "Details" view in order to display the associated generated input and output addresses for the individual objects:



12. Confirm with "OK".

To support automatic device commissioning, the input and output addresses must be identical because the addresses in the PLC user program are required for FB283 (Generate PLC user program (Page 304)).

Result



Saving/compiling/loading into the module

Procedure:

1. Select the "Station" → "Save and compile" menu.
2. Click the "Load in module" button to load the configuration to the PLC (End the hardware configuration and load it to the PLC (Page 47)).

The next step is to create the PLC user program.

9.3 Generate PLC user program

Preconditions

This chapter describes the configuration of PLC drives that are not to be operated as NC axes. In the PLC user program the following expansions of the function blocks are required:

- You will need additional S7 function blocks from the SINAMICS toolbox ≥ V2.1.

The SINAMICS toolbox is in the SINUMERIK toolbox in directory BSP_PROG. The path depends on the version, e.g. \8x0d\040504\BSP_PROG\SINAMICS_V21.zip

This Zip file contains a manual in several languages.

- It is also available on the Internet at the following link:

SINAMICS Toolbox V2.1

(<http://support.automation.siemens.com/WW/view/en/25166781>)

Signals "WR_PZD" and "RD_PZD"

The "WR_PZD" and "RD_PZD" signals for FC70 in the example have the following meaning:

Signal	Type	Type	Range of values	Remark
WR_PZD	I	Any	P#Mm.n byte x P#DBno.DBXm.n byte x	Target range for process data, master → slave (control words / setpoints) Here, generally the axis DB is used, i.e. in the pointer, the same DB number must be specified as formal parameter "NR_ACHS_DB". The length of the pointer is 30 bytes for Siemens telegram 136.
RD_PZD	I	Any	P#Mm.n byte x P#DBno.DBXm.n byte x	Target range for process data, slave → master (status words / actual values) Here, generally the axis DB is used, i.e. in the pointer, the same DB number must be specified as formal parameter "NR_ACHS_DB". The length of the pointer is 38 bytes for Siemens telegram 136.

Example with constant speed (fan, pump)

Procedure:

- You have already created a project and find yourself on the main screen of the SIMATIC Manager.
- Select the "File" → "Open" menu and then click the "User projects" tab.
- Open the project example.
- Copy the FB283, FC70, DB70 and DB283 blocks as well as all UDT300xx into your existing project.
- As the DB70 could be used by another program, rename DB70 as DB111!
- Create a new FC73. Do not use the FC73 from the SINAMICS toolbox.

In our example, 4000_{hex} corresponds to the rated speed in drive parameter p2000.

7. Edit the OB1, FC70 and FC73 blocks in accordance with the following examples.

Example of OB1:

...	
...	
CALL FC70	
CALL FC73	
...	
...	

Example of FC70:

CALL FB 283, DB283	
NR_ACHS_DB := 111	
LADDR := 300	//Logical I/O address
LADDR_DIAG := 8186	//Diagnostics address
WR_PZD := P#DB111 DBX172.0 Byte 8	//Source range for outputs
RD_PZD := P#DB111 DBX212.0 Byte 8	//Target range for inputs
CONSIST := TRUE	
RESTART := FALSE	
AXIS_NO := B#16#3	//Drive object number

Example of FC73:

UN E 30.0	//E.g. switch for the enable
SPB frei	
L W#16#47E	//Set all enables
T DB111.DBW 172	
U E 3.7	//MCP483 - reset
= DB111.DBX 173.7	//Reset fault memory
BEA	
L W##16#47E	//All enable signals except ON/OFF1
T DB111.DBW172	
L W##16#4000	//Rated speed in drive parameter p2000
T DB111.DBW174	//Set speed high

8. You have completed the programming of the user program: Now load the project to the PLC (Page 76).

Commissioning the PLC has been completed

For the synchronization of PLC and NCK a reset (warm restart) of the system is required:
Triggering a reset (warm restart) for NCK and drive system (Page 76) The LEDs show the following state:

- NCU: The "RUN" LED illuminates green continuously.
- NCU: Status display shows a "6" with a flashing point.
- CU320-2 DP: The "RDY" LED illuminates green continuously.

⇒ PLC and NCK are in cyclic operation. The initial commissioning of the PLC is completed.

See also

You commission the devices, infeed(s) and drives in the next step:

Guided commissioning of SINAMICS drives (Page 76)

9.4 Commissioning PLC drives

Preconditions

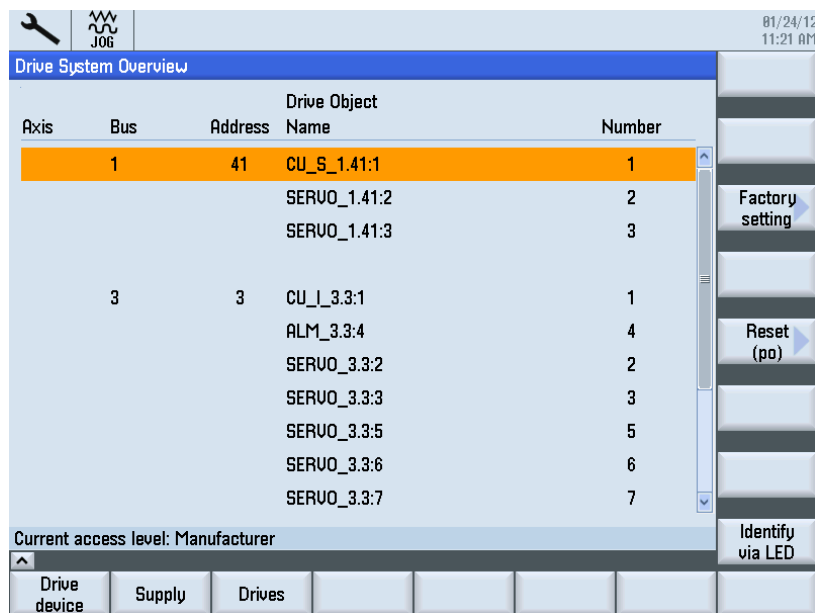
The following steps have already been performed:

- The PLC project was loaded to the PLC.
 - To perform a synchronization, you have initiated a reset (warm restart) for the NCK and the drive system.
 - The PLC and NCK are in the following state after a reset (warm restart):
 - RUN LED illuminates GREEN continuously.
 - Status display shows a "6" with a flashing point.
- ⇒ PLC and NCK are in cyclic operation.

Automatic device configuration

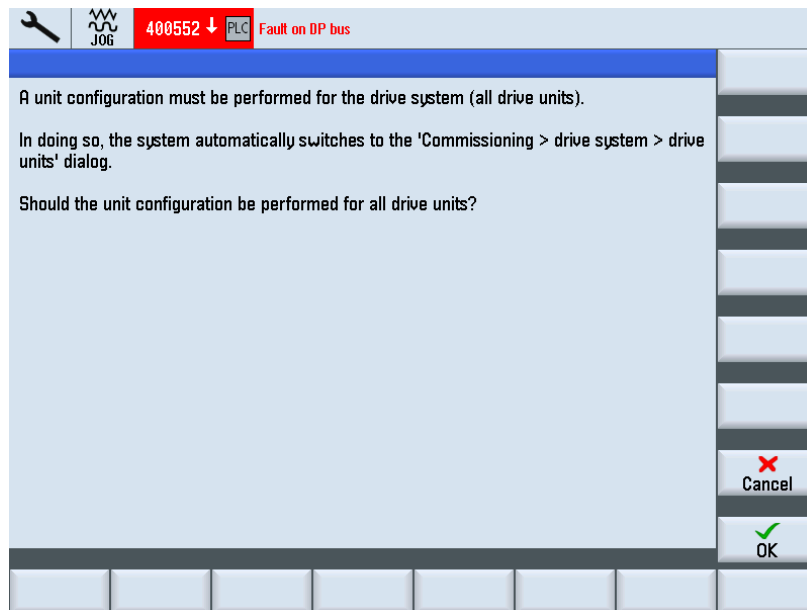
The following description for commissioning briefly discusses the procedure:

1. Select the "Commissioning" → "Drive system" operating area.



2. Press the "Drive unit" softkey to start the automatic device configuration. During commissioning, alarms in the display area for alarms/messages are output.

3. Confirm with "OK". You will then be guided through the individual steps of the automatic device configuration.



The further commissioning corresponds to the SINAMICS commissioning via an integrated PROFIBUS. You are guided through the automatic device configuration up to commissioning of the individual drive objects that have still not been commissioned.

See also

For additional commissioning steps, please refer to Chapter Commissioning NC-controlled drives (Page 67) from Chapter Automatic device configuration (Page 78).

9.5 Checking the communication to the drive

Check configuration

The PLC alarms of the drives must have an identical time stamp with the NCK.

For the configuration in the hardware configuration, define the associated Siemens telegram 390 for the SINAMICS CU. The corresponding logical input and output addresses of this communication interface are entered in the following machine data item:

- MD13120[n] CONTROL_UNIT_LOGIC_ADDRESS
- MD13120[1]...[5] are reserved for NX expansion modules.

Note

You can view these logical addresses in the HW configuration when configuring the properties of SINAMICS components under "Details".

Procedure:

1. Check the logical address for SINAMICS CU in the "Commissioning" → "Machine data" → "General MD" operating area and enter, for example, the following value:

MD13120[6] = 288

2. Press the "Reset (po)" softkey to accept the changed machine data.

This completes the commissioning of the PLC drives.

9.6 Safety functions for PLC drives

Introduction

This section only partially describes how a PLC drive can be integrated in a safety-related application. In this case, the published supplement of the PROFIdrive profile that includes drive-based safety functions via the PROFIsafe supplement with telegram 30 is used.

Basic procedure

The following steps are necessary to integrate drive-based safety functions:

- Configuration with SIMATIC Manager under HW Config.
- Embedding in safe programmable logic (SPL).
- Configuration of test cases with SinuCom NC ATW that must go through an acceptance procedure.

Literature

For the implementation, reference is made to the following function manuals for safety functions which are binding for the safety-related version:

- SINUMERIK 840D sl "Safety Integrated" Function Manual
- SINAMICS S120 "Safety Integrated" Function Manual, Chapter: "Structure of telegram 30".

9.6.1 Configuring PROFIsafe

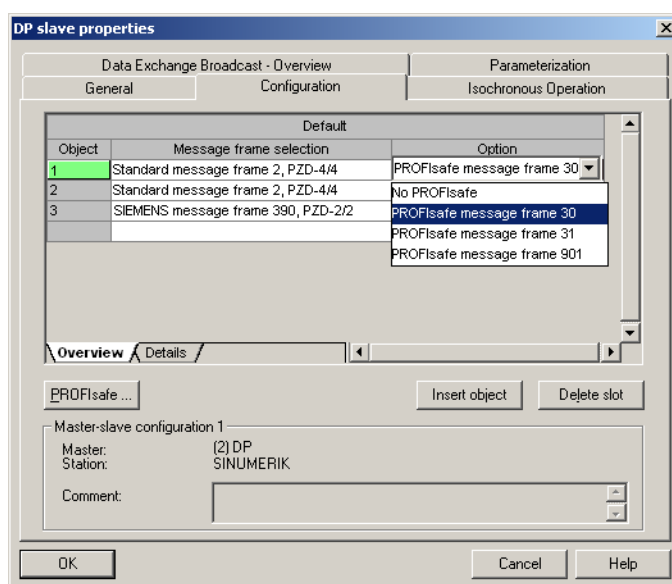
Precondition

In order to configure PROFIsafe, it is necessary that the "S7 Configurations Pack" option is installed.

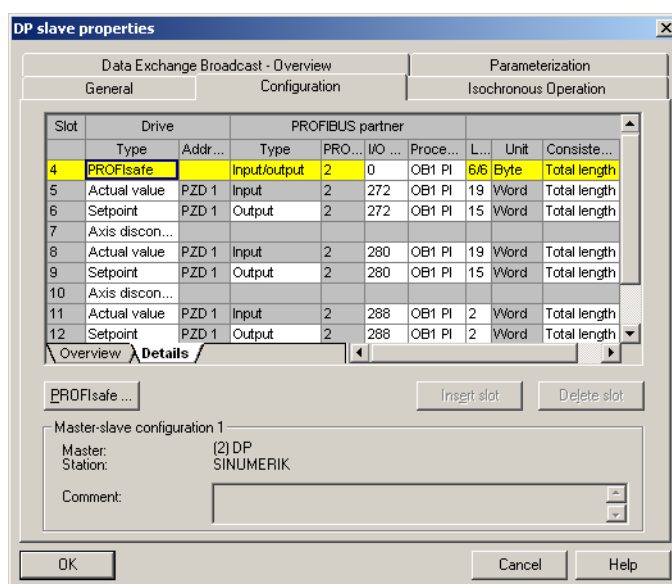
Configuring the operating sequence for PROFIsafe

Procedure:

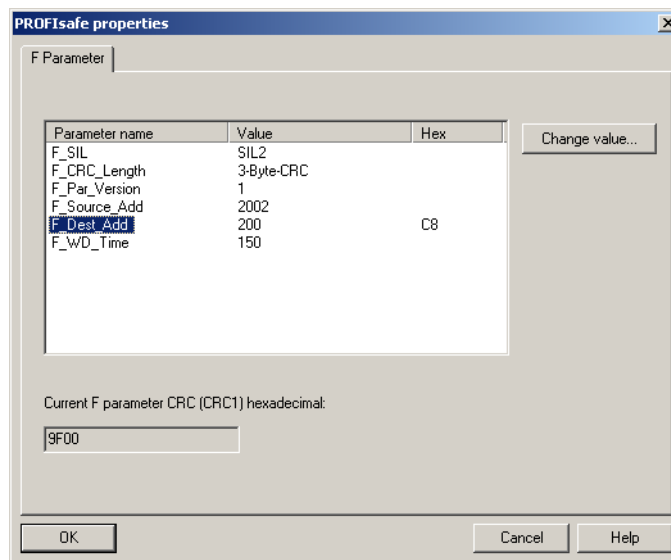
1. For this telegram, select the PROFIsafe telegram 30 in the "Option" selection field.



2. Under the "Details" tab, set the input/output addresses. The PROFIsafe option requires an additional 6 bytes.

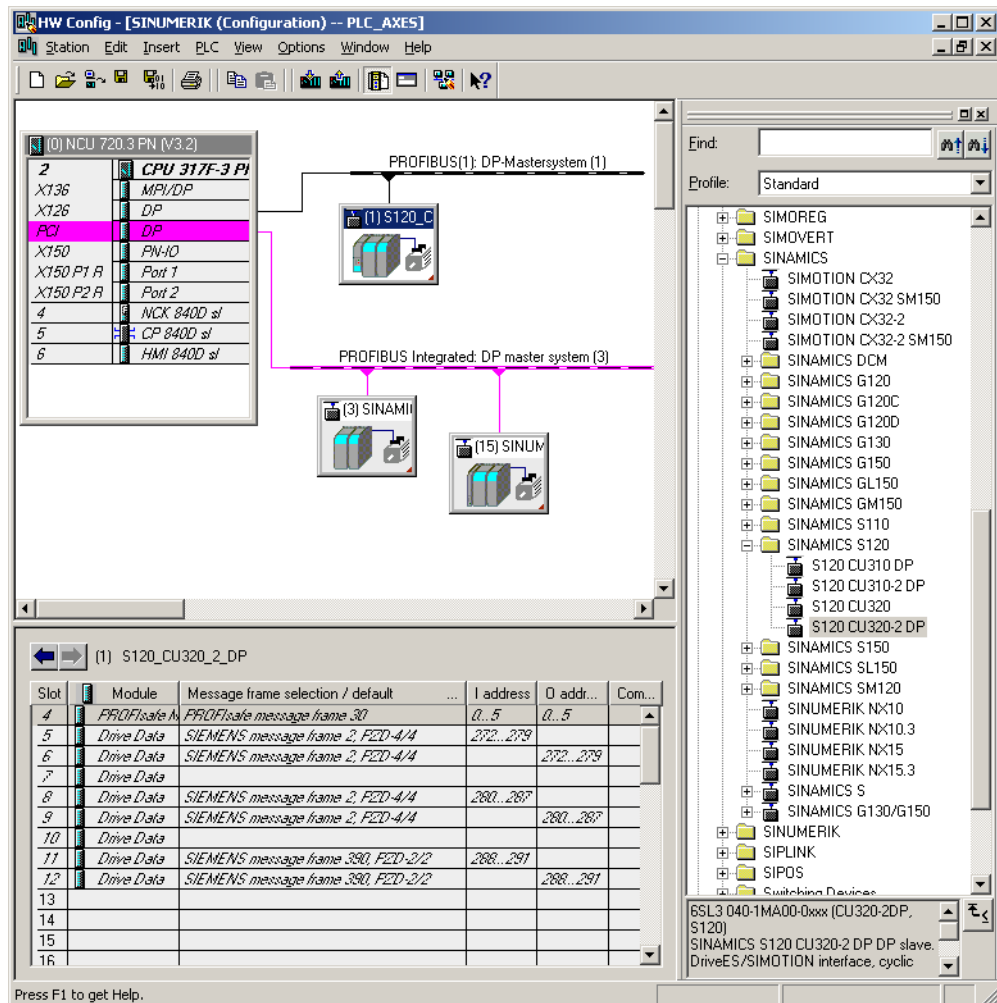


3. Press the "PROFIsafe ..." button to set the F parameters.
4. To change the "F_Dest_Add" parameter, in the column, select "F_Dest_Add" in the "Parameter Name" column and click the "Change value ..." button.



5. Check the following values/settings:
 - The value of the "F_Dest_Add" parameter must be entered as a hexadecimal value in p9610 and p9810 of the corresponding drive (e.g. 200_{dec} corresponds to C8_{hex}).
 - The value of the "F_Source_Add" must match the other used PROFIsafe modules and also be entered in MD10385 \$MN_PROFISAFE_MASTER_ADRESS.
 - It must be ensured that the same source address is set for all PROFIsafe modules.

Result of the PROFIsafe configuring:



9.6.2 Example: Embedding in safe programmable logic (SPL)

Introduction

The following machine data and files must be taken into account when embedding telegram 30 in a safe programmable logic:

- NC machine data
- Drive machine data
- "safe.SPF" file
- PLC program expansion

NC machine data

- Not bold: Values already used by PROFIsafe / F-Send/F-Rec.
- **Bold:** Values that have been added as a result of telegram 30.

The SPL PROFIsafe configuration for the basic safety functions STO without SSI are then shown as example:

Archive excerpt	Comment
CHANDATA(1)	
N10385 \$MN_PROFISAFE_MASTER_ADDRESS='H50007d2'	
N10386 \$MN_PROFISAFE_IN_ADDRESS[0]='H50000c8'	;> entry from HW Config
N10387 \$MN_PROFISAFE_OUT_ADDRESS[0]='H50000c8'	;> entry from HW Config
...	
N10390 \$MN_PROFISAFE_IN_ASSIGN[0]=9011	;> INSE[9] for S_STW1.0 No Safe Torque Off
	;> INSE[10] for S_STW1.1 No Safe Stop 1
	;> INSE[11] for S_STW1.7 INTERNAL_EVENT_ACK
	; No extended functions
...	
N10400 \$MN_PROFISAFE_OUT_ASSIGN[0]=9011	;> OUTSE[9] for S_ZSW1.0 Power removed
	;> OUTSE[10] for S_ZSW1.1 Safe Stop 1 not active
	;> OUTSE[11] for S_ZSW1.7 INTERNAL_EVENT
	; No extended functions
...	
N13300 \$MN_PROFISAFE_IN_FILTER[0]='H83'	
...	
N13320 \$MN_PROFISAFE_OUT_FILTER[0]='H83'	
...	

Drive machine data

- Values that have been added as a result of telegram 30:

p9601=p9801=0x8

p9610=p9810=0xC8

"safe.SPF" file

Program example	Comment
IDS = 40 DO \$A_OUTSE[09] = \$A_INSE[2]	;If the cover is locked then deselect STO
IDS = 41 DO \$A_OUTSE[10] = \$A_INSE[2]	;If the cover is locked then deselect SSI

PLC program expansion

Program example	Comment
U "SPL".SPL_DATA.INSEP[2];	// => cover switch locked?
= "SPL".SPL_DATA.OUTSEP[9];	// \$A_OUTSE[9] =1 => Deselect STO
= "SPL".SPL_DATA.OUTSEP[10];	// \$A_OUTSE[10] =1 => Deselect SS1
//Enable signal OFF1 set:	
UN "SPL".SPL_DATA.INSEP[9];	// => No STO?
UN "SPL".SPL_DATA.INSEP[10];	// => No SS1?
U E 0.0;	// of course, only if OFF1 is also requested by switch
=	
"CU320_A".Speed_Control.WR_PZD_DREHZAHL.STW1	
.Aus1 ;	

9.6.3 Configuration of test cases with SinuCom NC SI-ATW that must go through an acceptance procedure

Precondition

SinuCom NC SI-ATW, which can be used for the acceptance of safety-related SINUMERIK Safety Integrated functions, can also be used to accept certain drive-based Safety Integrated functions. The alarms 201600 to 201799 of the drive-based Safety Integrated are displayed on the controller.

The following example for STO (Safe Torque Off)/SH (safe standstill) of an external SINAMICS CU3xx device shows these functions.

Operator input options when ATW is running

The tests for the drives of the CU320 are integrated into the ATW using the "Function inter-relationships". For the parameters there are two options:

1. The contents of the parameters are entered into the result box.
2. The "setpoints" are located in the condition box and are confirmed in the result box with "OK" if there is a match.

Figure 9-2 Test 1: Result

Figure 9-3 Test 2: Result

Test 3: Testing the safe shutdown (STO):

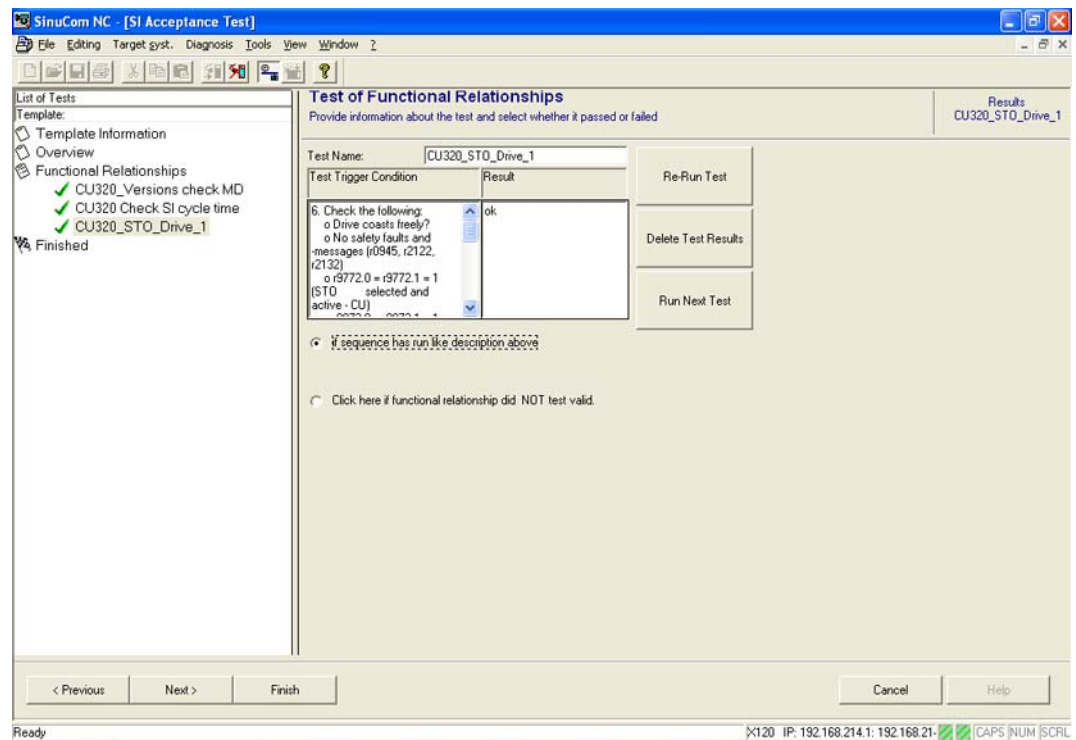


Figure 9-4 Test 3: Result

There is a separate test for each drive.

References

SINAMICS S120 Safety Integrated Function Manual (FHS)

See also

Safety functions for PLC drives (Page 310)

Saving and managing data

10.1 Saving data

Time of the data backup

The following times are recommended for performing a data backup:

- After a commissioning
- After changing machine-specific settings
- After replacing a hardware component
- For a software upgrade
- Before the activation of memory-configuring machine data

Data backup for DRIVE-CLiQ motors:

We would recommend backing up the DRIVE-CLiQ motor data onto a CompactFlash card. Parameter p4692 = "1" must be set.

Creating and importing a commissioning archive

There are the following ways to create and reload archives:

- The "Commissioning archive" softkey offers the following selection:
 - Creating a commissioning archive
 - Creating a PLC hardware upgrade archive (only SDBs)
 - Importing a commissioning archive
 - Creating an original status archive
 - Reading in an original status archive
- The "System data" softkey can be used to select and import specific archives from the data structure.

A commissioning archive is saved as a file of the ".arc" type.

Note

Archives of this type can be processed with the SinuCom ARC commissioning and service software.

What data is saved?

Components	data
NC data	<ul style="list-style-type: none"> Machine data Setting data Option data Global (GUD) and local (LUD) user data Tool and magazine data Protection zone data R parameters Zero offsets Compensation data Workpieces, global part programs and sub-programs Standard and user cycles Definitions and macros
<ul style="list-style-type: none"> With compensation data 	<ul style="list-style-type: none"> QEC - quadrant error compensation CEC - operation/angularity compensation EEC - leadscrew pitch / encoder error compensation <p>Note: It only makes sense to archive machine-specific compensation data if the commissioning file is reloaded into the same controller.</p>
<ul style="list-style-type: none"> With compile cycles 	<p>The compile cycles (* .elf) option is displayed only if compile cycles are also available.</p>
PLC data	<ul style="list-style-type: none"> OB (organization blocks) FB (function blocks) FC (functions) DB (data blocks) SFB (system function blocks) SFC (system functions) SDB (system data blocks). <p>System data blocks are only used to back up the hardware configuration (not the program logic).</p>

Components	data
Drive data	Either in binary or ASCII format
HMI data	<ul style="list-style-type: none"> • Texts: PLC alarm texts, cycle alarm texts, part program message texts from the machine manufacturer • Templates: Individual templates, workpiece templates • Applications: Software applications, for example of the machine manufacturer • Configurations • Configuration: Configurations, incl. display machine data • Help: Online help files • Version data • Reports: For example, action log, screenshots • Program lists • Dictionaries: For Chinese simplified and Chinese traditional (IME) • Data backups: Channel data, axis data, etc. in ASCII format • Programs on a local drive: Programs that are in the user memory area of the CompactFlash card.

10.1.1 Backup of PLC data

PLC operating state

When creating a commissioning archive with PLC data, the PLC image that is saved during this process depends on the operating state of the PLC at the time of creation:

- Original image
- Instantaneous image
- Inconsistent image

The operating state of the PLC can be changed in the following ways:

- With SIMATIC STEP 7 Manager
- With the PLC mode selector on the NCU:
Position " 2" → STOP, position " 0" → RUN

Operating sequence for original image

The original image of the PLC is represented by the PLC-data state immediately after loading the S7 project into the PLC.

1. Set the PLC to the STOP operating state.
2. Load the appropriate S7 project into the PLC using SIMATIC Manager STEP 7.
3. Create a commissioning archive with PLC data.
4. Set the PLC to the RUN operating state.

Operating sequence for instantaneous image

If you cannot create an original image, you can save an instantaneous image as an alternative.

1. Set the PLC to the STOP operating state.
2. Archive the PLC data.
3. Set the PLC to the RUN operating state.

Operating sequence for inconsistent image

An inconsistent image results if a commissioning file with PLC data is created and the PLC is in the RUN state (cyclic operation). The data blocks of the PLC are saved at different times with contents that have changed in the meanwhile. This may result in a data inconsistency that, once the data backup has been copied back to the PLC, may under certain circumstances result in a PLC stop in the user program.

NOTICE
Ensure data consistency
The creation of a commissioning file with PLC data while the PLC is in RUN state (cyclic operation) may result in an inconsistent PLC image in the commissioning archive. After this commissioning archive has been copied back, the data inconsistency in the PLC user program may under certain circumstances result in a PLC stop.

10.1.2 Creating a commissioning archive

Precondition

The following access levels are required:

- In order to create a commissioning archive, at least access level 4 (key-operated switch 3) is required.
- In order to import a commissioning archive, at least access level 2 (service) is required.

To prevent a topology error, Control Unit parameter p9906 (topology comparison stage of all components) should be set to "Medium" to import a commissioning archive.

Creating a commissioning archive

Series commissioning means bringing a series of control systems to the same initial state as regards their data. A commissioning archive contains NC, PLC, drive and HMI data. Compensation data of the NC can also be optionally saved. For a data backup, the drive data is saved as binary data that cannot be read.

Procedure:

1. To create a commissioning archive, select: "Commissioning" → forward key → "Commissioning archives" → "Creating a commissioning archive" option operating area:

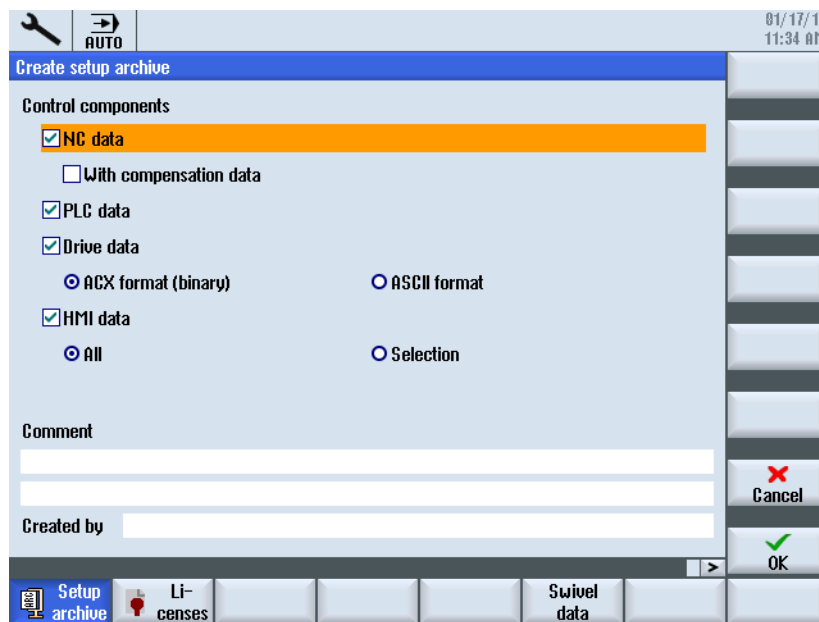


Figure 10-1 Commissioning archives

2. Select the data to be backed up:
 - NC data: With/without compensation data
 - PLC data
 - Drive data: Binary/ASCII
 - HMI data: All/selection
3. Enter an archive name.
4. The following directories are offered as a storage location for the archive:
 - Archives/user or archives/manufacture on CompactFlash card or PCU 50
 - A logical drive, e.g. USB FlashDrive

Memory locations

Archives can be stored in the following directories:

- Archives/user or archives/manufacture on CompactFlash card or PCU 50
Absolute path specification: **/user/sinumerik/data/archive** or **/oem/sinumerik/data/archive**
- All configured logical drives (USB, network drives)

Note

USB FlashDrive

USB FlashDrives are not suitable as persistent memory media.

10.2 Managing data

Application

The "Manage data" function is used to support and simplify the commissioning and provides functions for backup, load and comparison of machine, setting, compensation and drive data.

In contrast to a commissioning archive, only a single control object (axis, channel, servo, infeed, etc.) is saved in ASCII format (*.TEA). This file can be edited and transferred to other control objects of the same type. The "Manage data" function is also the basis for copying DO for SINAMICS drives.

Managing data

The "Manage data" function offers the following options:

- Transfer data within the controller
- Save data to a file
- Load data in a file
- Compare data

The function is called from "Commissioning" → "Machine data" → "Manage data".

Example of "transfer data within the controller":

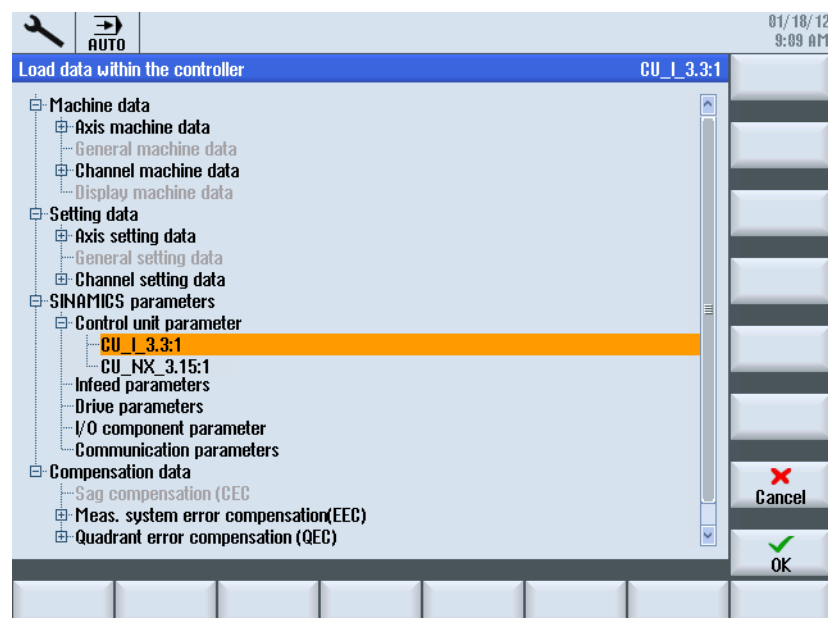


Figure 10-2 Managing data

The following data can be saved and stored under the following absolute path on the CompactFlash card:

- **user/sinumerik/hmi/data/backup/ec** for compensation data
- **user/sinumerik/hmi/data/backup/md** for machine data
- **user/sinumerik/hmi/data/backup/sd** for setting data
- **user/sinumerik/hmi/data/backup/snx** for SINAMICS parameters

10.2.1 How to transfer data within the controller

Transfer data within the control

NOTICE
Protection of the machine For safety reasons, the machine and setting data should only be transferred when the enable is locked.

Procedure:

1. Select the "Transfer data within the control" option.
2. Select the source data in the data structure and confirm with "OK".
3. In the drop-down list, select an object, e.g. a different axis or a different drive object, to which you want to transfer the data and confirm with "OK".
4. Observe the safety instructions and check the enable signals at the machine and the drive.
5. For drive data, the "Load" softkey is used to transfer the data to the target object.

10.2.2 To save and load data

Save data to a file

Procedure:

1. Select the "Save data to a file" option.
2. In the data structure, select the data that you want to save to a file and confirm with "OK".
3. Select as the storage location, a directory or a USB storage medium and enter a name.

Note**SINAMICS parameters**

An ASCII file (*.TEA) is always generated when saving.

Three files of the following type are generated when saving the drive data:

- A binary file (*.ACX) that cannot be read.
- An ASCII file (*.TEA) that can be read or edited in the ASCII editor.
- A log file (*.log) that contains message texts (error situation) or is empty (successful storage).

Loading data from a file**NOTICE****Protection of the machine**

For safety reasons, the machine and setting data should only be transferred when the enable is locked.

Procedure:

1. Select the "Load data from a file" option.
2. In the data structure, select the saved file and confirm with "OK".
3. In the drop-down list, select an object, e.g. a different axis or a different drive object, to which you want to transfer the data and confirm with "OK".
4. Observe the safety instructions and check the enable signals at the machine and the drive.
5. For drive data, the "Load" softkey is used to transfer the data to the target object.

10.2.3 How to compare data**Compare data**

You can select different data sources for the data comparison: Store the current data in files on the controller or data.

Procedure:

1. Select the "Compare data" option.
2. In the data structure, select the data that you want to compare.
3. Press the "Add to list" softkey to transfer the data to the list in the lower area of the display.
4. Press the "Delete from list" softkey to remove the data again.

5. If the list contains more than two data objects, you can activate the checkbox to compare two or more data objects from the list.
6. Press the "Compare" softkey to start the comparison. The display of the comparison results can take some time for extensive parameter lists.
7. Press the "Legend" softkey to display or hide the legend. The following display is the default:
 - Different parameters are displayed.
 - The same parameters are not displayed.
 - Parameters not available everywhere are displayed.

Licensing

11.1 SINUMERIK License Key

Basic information on license keys

If a license is required for a product, then with the purchase of the license the purchaser receives a CoL as proof for the rights to use this product and a corresponding license key as to the "technical representative" of this license. In conjunction with software products, the license key usually must be available on the hardware on which the software product is executed.

SINUMERIK license keys

Depending on the software product, there are license keys with different technical properties. The essential properties of a SINUMERIK license key are:

- **Hardware reference**
The hardware serial number included in the SINUMERIK license key provides a direct link between the license key and the hardware on which it can be used. In other words, a license key created for the hardware serial number of a specific CompactFlash card is only valid for this CompactFlash card and will be rejected on other CompactFlash cards as invalid.
- **Total number of assigned licenses**
A SINUMERIK license key not only refers to a single license, instead it is the "technical representative" of all licenses that are assigned to the hardware at the time of its generation.

Content of the CompactFlash card

The CompactFlash card contains not only the system and user software as well as the retentive system and user data, but also the data relevant for the license management of SINUMERIK software products of a controller:

- Hardware serial number
- License information including the license key

The CompactFlash card thus represents the identity of a SINUMERIK controller. For this reason, assigning licenses to a controller always occurs using the hardware serial number.

This has the advantage that the CompactFlash card can be inserted into a replacement NCU in the event of failure and all data is retained.

CompactFlash card as a spare part

If the CompactFlash card of a SINUMERIK controller is replaced, for example, because of defective hardware, the license key loses its validity and the system is no longer operational.

In case of defective hardware of the CompactFlash card, contact the "Technical Support". They will then send you a new license key without delay. The following data is required:

- Hardware serial number of the defective CompactFlash card
- Hardware serial number of the new CompactFlash card

Note

Only CompactFlash cards can be used that were released as spare part, as only these are known to the license database.

Determining the hardware serial number

The hardware serial number is a permanent part of the CompactFlash card. It is used to identify a control system uniquely. The hardware serial number can be determined by:

- Certificate of License (CoL)
- SINUMERIK user interface
- Label on the CompactFlash card

Note

Hardware serial number and CoL

The hardware serial number is located only on a CoL of the system software or if the license was ordered bundled, in other words the system software came together with options.

11.2 Web License Manager

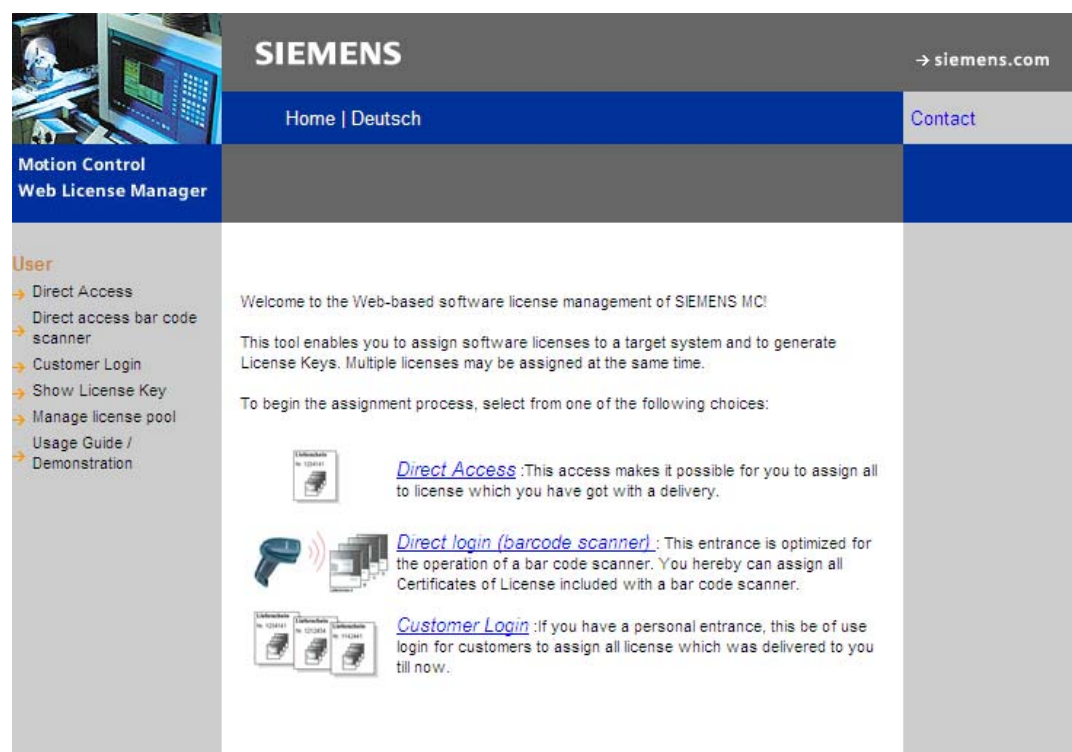
Overview

The use of the installed system software and the options activated on a SINUMERIK control system require that the licenses purchased for this purpose are assigned to the hardware. In the course of this assignment, a license key is generated from the license numbers of the system software, the options, as well as the hardware serial number. Here, a license database administered by Siemens is accessed via the Internet. Finally, the license information including the license key is transferred to the hardware.

The license database can be accessed using the Web License Manager.

Web License Manager

By using the Web License Manager, you can assign licenses to the hardware in a standard Web browser. To conclude the assignment, the license key must be entered at the controller via the user interface.



Internet links

Web License Manager (<http://www.siemens.com/automation/license>)

Siemens Industry Mall (<http://mall.automation.siemens.com>)

11.3 License database

License database access

The license database contains all relevant license information required for the license management of SINUMERIK software products. The central management of the license information in the license database ensures that the existing license information regarding a piece of hardware is always up to date.

Direct access

The direct access in the Web License Manager is made with:

- License number
- Delivery note number

The direct access enables the direct assignment of licenses for which the license numbers are available, e.g. in the form of a CoL.

Direct access with barcode scanner

The direct access in the Web License Manager is made with:

- Hardware serial number
- Product selection

The direct access enables the assignment of licenses with a barcode scanner for which the license numbers are available as a barcode, for example in the form of a CoL.

Customer login

The customer login in the Web License Manager is made with:

- User name
- Password

The customer login enables the assignment of all the licenses available to the machine manufacturer that are delivered at the time of the login and have not yet been assigned to any machine. Here, the license numbers of licenses that can still be assigned need not be directly at hand, instead these are displayed from within the license database.

Note

Obtaining access data

You can obtain the address data for the customer login from the Siemens Industry Mall under the associated selected region with: "> Register" (above).

11.4 How to perform the assignment

Assigning a license to a piece of hardware

1. Determine the hardware serial number and the product name ("type of hardware") on the user interface via the licensing dialog:

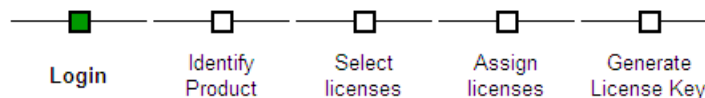
Commissioning > menu forward key > Licenses > Overview operating area

Note

Ensure that the hardware serial number displayed is also really the one you want to make the assignment for. The assignment of a license to a piece of hardware cannot be reversed via the Web License Manager.

2. Go to the Internet page of the Web License Manager.
3. Click the appropriate access to the license database:
 - Direct access
 - Direct access (barcode scanner)
 - Customer login
4. Follow the instructions in the Web License Manager.

A progress bar shows you the individual steps:



5. Check the details of the selected licenses before confirmation of the assignment process.

Note

After confirmation, the generated license key irrevocably links the selected licenses with the specified hardware.

6. Confirm the assignment process.
7. After completing the assignment process, enter the license key displayed on the Web License Manager into the license dialog of the user interface.

Commissioning > menu forward key > Licenses > Overview operating area

8. Press the <INPUT> button to confirm the input of the new license key.

Displaying the license key and sending via e-mail

For archiving or for documentation of the associated machine, you can also send a license report with the grouping of all assigned licenses. Follow the instructions in the Web License Manager under "Display License Key".

11.5 Import licensing terms

Product

A product is marked by the data below within the license management of SINUMERIK
→ software products:

- Product designation
- Order number:
- → License number

Software product

The term software product is generally used to describe a product that is installed on a piece of → hardware to process data. Within the license management of SINUMERIK software products, a corresponding → license is required to use each software product.

Certificate of License (CoL)

The CoL is the proof of the → license. The product may only be used by the holder of the → license or authorized persons. The CoL includes the following data relevant for the license management:

- Product name
- → License number
- Delivery note number
- → Hardware serial number

Hardware

In the context of license management of SINUMERIK → software products, hardware refers to the component of a SINUMERIK control system to which → licenses are assigned on the basis of its unique identifier. The license information is also saved to non-volatile memory on this component, e.g. on a → CompactFlash card.

CompactFlash card

As the carrier of all non-volatile data in a SINUMERIK solution line control system, the CompactFlash card represents the identity of this control system. The CompactFlash card is a memory card that can be plugged into the → control unit from outside. The CompactFlash card also contains the following data relevant for the license management:

- → Hardware serial number
- License information including the → license key

Hardware serial number

The hardware serial number is a permanent part of the → CompactFlash card. It is used to identify a control system uniquely. The hardware serial number can be determined by:

- → Certificate of License
- User interface
- Label on the CompactFlash card

License

A license gives the user the legal right to use a → software product. Evidence of this right is provided by the following:

- → Certificate of License (CoL)
- → License key

License number

The license number is the feature of a → license used for its unique identification.

License key

The License Key is the "technical representative" of the sum of all the → licenses that are assigned to one particular piece of → hardware, which is uniquely marked by its → hardware serial number.

Option

One option is a SINUMERIK → software product that is not contained in the basic version and which requires the purchase of a → license for its use.

Cycle protection (option)

12.1 Overview, cycle protection

Functionality

With cycle protection, cycles can be encrypted and then stored, protected in the controller. The processing of cycles with cycle protection in the NC is possible without restrictions.



Software option

You require the following software option in order to use this function: "Lock MyCycles" (MLFB: 6FC5800-0AP54-0YB0).

Note

This type of encryption is in compliance with export restrictions and embargo regulations.

In order to protect the manufacturer's know-how, any type of view is inhibited for cycles with cycle protection. If service is required the machine manufacturer must provide the unencrypted cycle.

Note

End user

When using encrypted cycles of a machine manufacturer, when problems occur, then only the service department of the machine manufacturer should be contacted.

Machine manufacturer

When using encrypted cycles, the machine manufacturer must ensure that original, unencrypted cycles are archived with the appropriate version management.

Copying encrypted cycles

The encrypted cycle can be copied and can therefore be used at other machines.

- **Using encrypted cycles at only one machine**

If the cycle must not be used at another machine, then the cycle can be permanently linked to a particular machine. The machine data MD18030 \$MN_HW_SERIAL_NUMBER can be used for this purpose.

When the controller boots, the unique hardware serial number of the CompactFlash card is saved in this machine data. If a cycle is to be permanently linked to a machine, then in the call header of the cycle, the serial number of the CompactFlash card must be queried (MD18030 \$MN_HW_SERIAL_NUMBER). If the cycle identifies a serial number that does not match, then an alarm can be output in the cycle and so prevents further processing. As the code of the cycle is encrypted, there is always a fixed link to a defined hardware.

- **Using encrypted cycles for several machine data**

If a cycle is to be permanently linked to several, defined machines, the cycle must be entered into each hardware serial number. The cycle must be re-encrypted with these hardware serial numbers.

Handling encrypted cycles

A _CPF file can be deleted or unloaded just like an _SPF or _MPF file. All the encrypted _CPF files are also backed-up when an archive is generated.

- An encrypted cycle cannot be directly selected for processing. It can only be called from a program - or directly in MDI.
- An encrypted cycle cannot be processed with the "Process external" function.

12.2 Preprocessing

File extensions

The cycle to be protected is encrypted on an external PC using the Lock MyCycles program. The encrypted cycle has the extension `_CPF` (Coded Program File).

The following predefined extensions are relevant for the file extensions:

- `_MPF` "Main Program File" for unencrypted main programs; ASCII format
- `_SPF` "Sub-Program File" for unencrypted sub-programs; ASCII format
- `_CYC` "Cycle" for pre-compiled file; binary format

The following file extensions are available for encrypted cycles:

- `_CPF` "Coded Program File" for encrypted files in binary format

The `_CPF` files are either loaded to `/_N_CST_DIR`, `/_N_CMA_DIR` or `/_N_CUS_DIR`. These files are visible there and can be processed just like the previous part programs (`_MPF`, `_SPF`). To execute a `_CPF` file, a Power On is required after loading the cycles.

If no power on is performed, the processing of a `_CPF` file causes the following alarm:

15176 "Program %3 can be executed only after power on".

Note

A machine manufacturer cycle can be called from a main program using the cycle name and an extension, for example `_SPF`. This is possible in the `CALL`, `PCALL` command or also directly with the name.

If this machine manufacturer cycle is loaded encrypted as `_CPF`, all sub-program calls with extension must be changed to `_CPF`.

Preprocessing

As well as `_SPF` files, encrypted files can be preprocessed. To activate preprocessing, the MD10700 `$MN_PREPROCESSING_LEVEL` machine data must be set. Pre-processing is always recommended for runtime reasons.

For pre-processing, an NC program (`_MPF`) or cycle (`_SPF`) must be converted from the ASCII format into the binary format (compiled). The following NC alarm is issued if, at the time of execution, the compilation is older than the encrypted cycle file:

15176 "Program%3 can be executed only after power on".

12.3 Call as sub-program

Sub-program calls without extensions

A directory can include an encrypted file file _CPF and also an unencrypted file _SPF with the same name, e.g. CYCLE1. If the unencrypted _SPF file is pre-processed, then the following are located in directory:

- CYCLE1.SPF ; unencrypted cycle
- CYCLE1.CYC ; compilation unencrypted cycle
- CYCLE1.CPF ; encrypted cycle

For a call in the part program without extension, e.g. N5 CYCLE1(1.2) the call is made with the following priority:

- CYCLE1.CYC
- CYCLE1.SPF
- CYCLE1.CPF

If only the encrypted file (*.CPF) is in a directory, for a call without extension, nothing has to be changed. The encrypted file or its compilation is called. In the case of service, an unencrypted file (*.SPF) is loaded. As this file has a higher priority, for the same call without extension, this file is called.

Note

An unencrypted file and its compilation have a higher priority than an encrypted file.

Sub-program calls with extensions

Sub-program calls with extension are:

- Direct call N5 CYCLE1_SPF
- Indirect sub-program call (CALL) N5 CALL "CYCLE1_SPF"
- Sub-program call with path data (PCALL) N5 PCALL /_N_CMA_DIR /_N_CYCLE1_SPF

The following extensions are possible:

- N3_MPF; calls the unencrypted file.
- N5 _SPF ; calls the unencrypted cycle.
- N10 _CYC ; calls the compilation of the unencrypted cycle.
- N15 _CPF ; calls the encrypted cycle or its compilation.

If a previous unencrypted cycle CYCLE1 is called with _SPF and this is now only loaded encrypted as _CPF, then all of the calls must be adapted.

NC language commands with absolute path data

Using the following commands, files can be accessed in the passive file system from the part program. In this case, absolute path data with extensions are used.

- WRITE: Data cannot be attached to a _CPF file, return 4 "incorrect file type".
- READ: Lines cannot be read from a _CPF file, return 4 "incorrect file type".
- DELETE: _CPF files can be deleted.
- ISFILE: A check can be made as to whether a _CPF file is available.
- FILEDATE
- FILETIME
- FILESIZE
- FILESTAT
- FILEINFO

All commands can also be called for _CPF files. The commands then supply the corresponding information.

12.4 Processing the program

Actual block display

If an encrypted cycle is executed, then DISPLOF is always active, independent of the programmed PROC attributes. DISPLOF and DISPLON in the block have no effect. If an alarm occurs in the cycle, when programming ACTBLOCNO, the block number is not output in the alarm line, but always just the line number.

Basic block display

If a _CPF cycle is executed, for an active basis block display, the absolute end of block is still displayed. In the single block, this information corresponds to the display of the actual axis values and can also be entered there.

Version display

If a version is entered in the header of an encrypted _CPF cycle, then this version is displayed in the contents screen of a cycle directory, just the same as for unencrypted cycles.

Simulation

The absolute end values are displayed during the processing of a _CPF file in the simulation.

New installation/upgrading

13.1 With the help of an NCU service system

Introduction

The CNC software on the CompactFlash card can be newly installed or upgraded.

- A reinstallation is required if there is no CNC software on the CompactFlash card (see Chapter New installation (Page 343)).
- An upgrade is required if an older CNC software is available on the CompactFlash card (see Chapter Upgrading (Page 350)).

Tools for reinstallation/upgrade

The following tools allow you to perform a reinstallation/upgrade:

- USB FlashDrive
- WinSCP on PC/PG
- VNC viewer on PC/PG

Literature

A reinstallation/upgrade always requires a bootable USB FlashDrive. In order that this USB FlashDrive is capable of being booted, an "NCU Service System" must be installed on it.

This description and other details can be found in:

Base Software and Operating Software Commissioning Manual, NCU operating system (IM7)

13.1.1 New installation

Introduction

No CNC software was installed on the CompactFlash Card. The CompactFlash Card is empty.

You have the following options of initiating a new installation of the CNC software:

- Automatic installation using USB-FlashDrive
- Installation using USB-FlashDrive
- Installation using WinSCP on PG/PC
- Installation using VNC Viewer on PG/PC

13.1.1.1 Automatic installation of the CNC software using USB-FlashDrive

Flow diagram

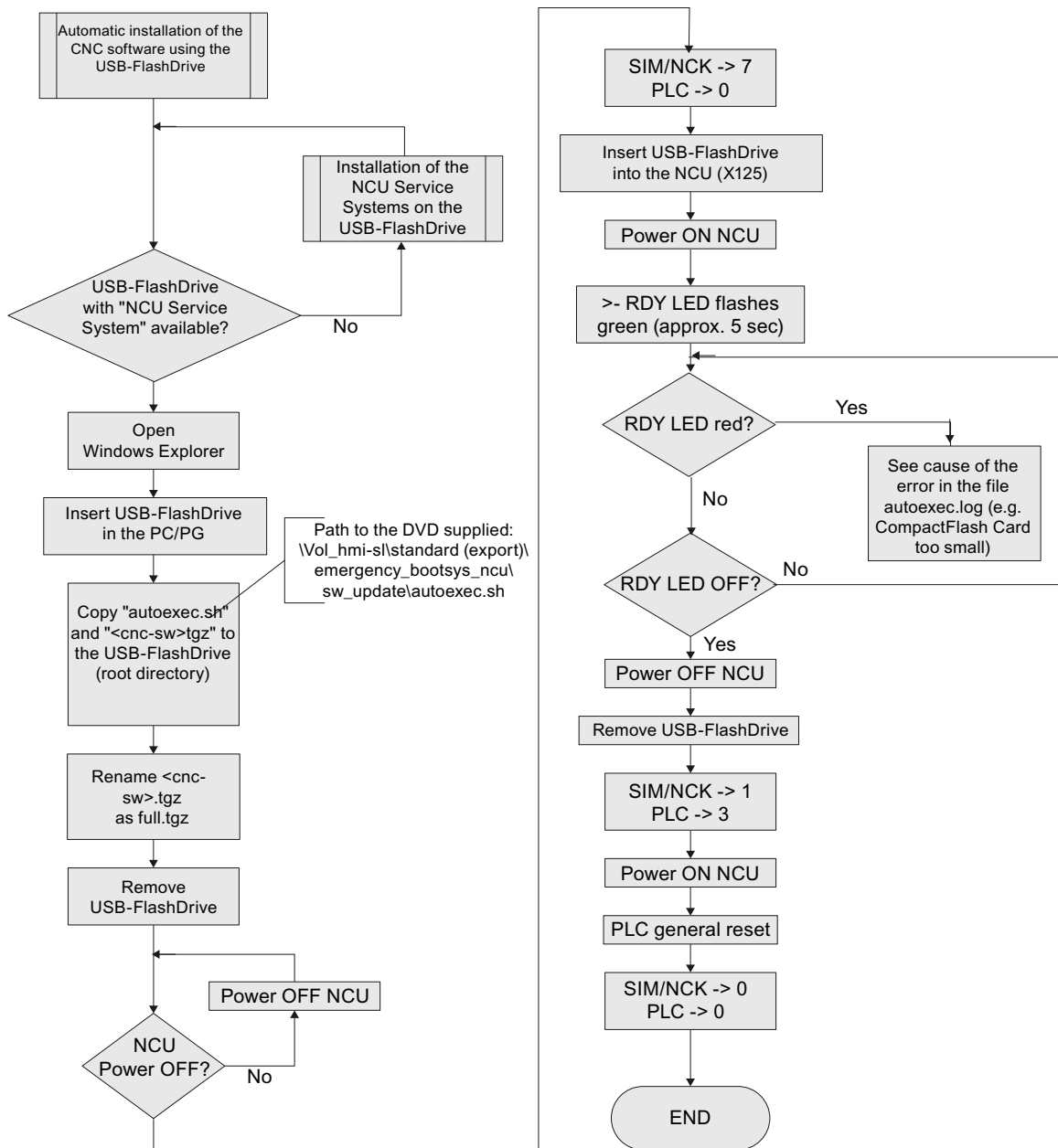


Figure 13-1 Automatic installation using USB-FlashDrive

13.1.1.2 Installation of the CNC software using USB-FlashDrive

Flow diagram

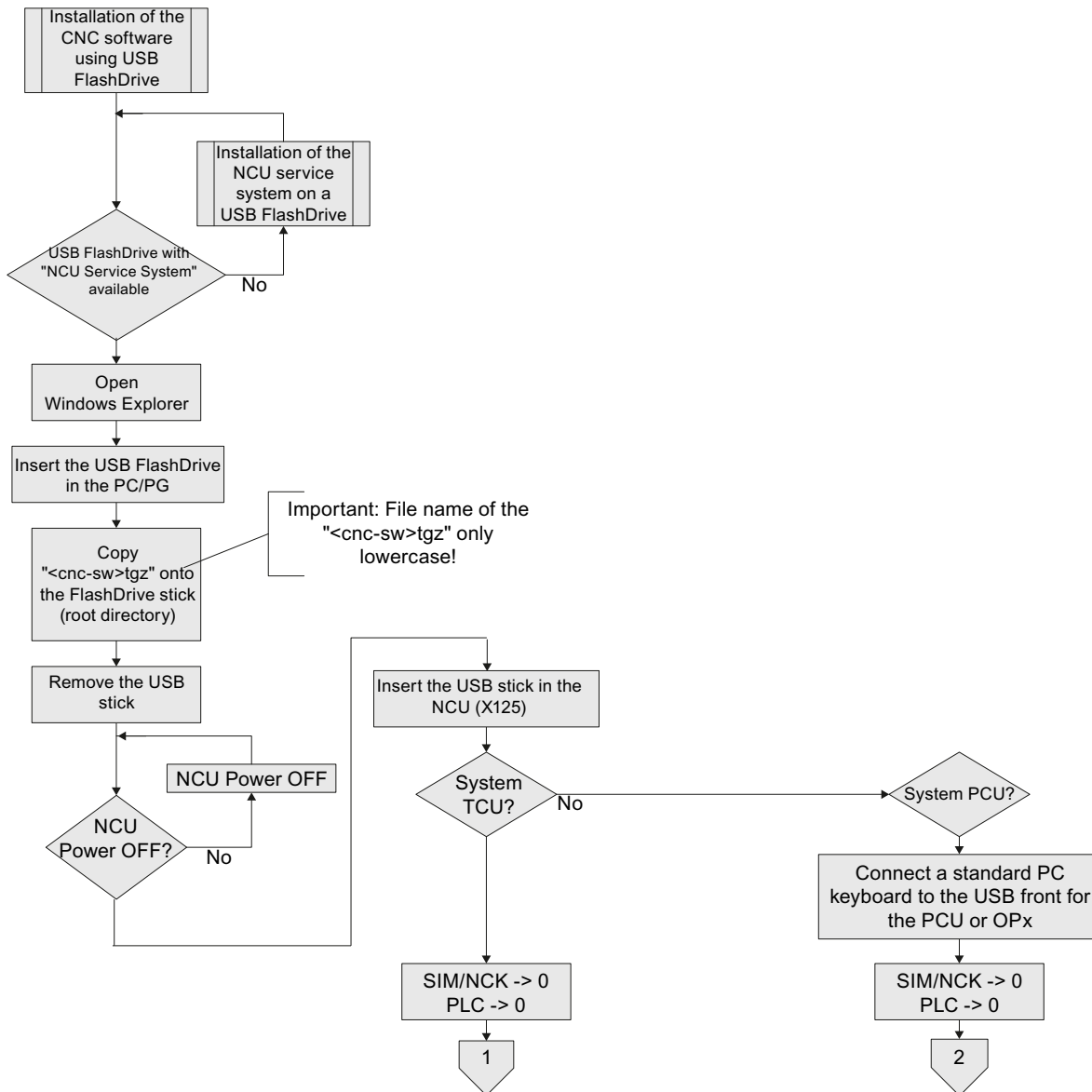


Figure 13-2 Installing the control software using USB-FlashDrive

Flow diagram - installation of the system TCU (1) continued

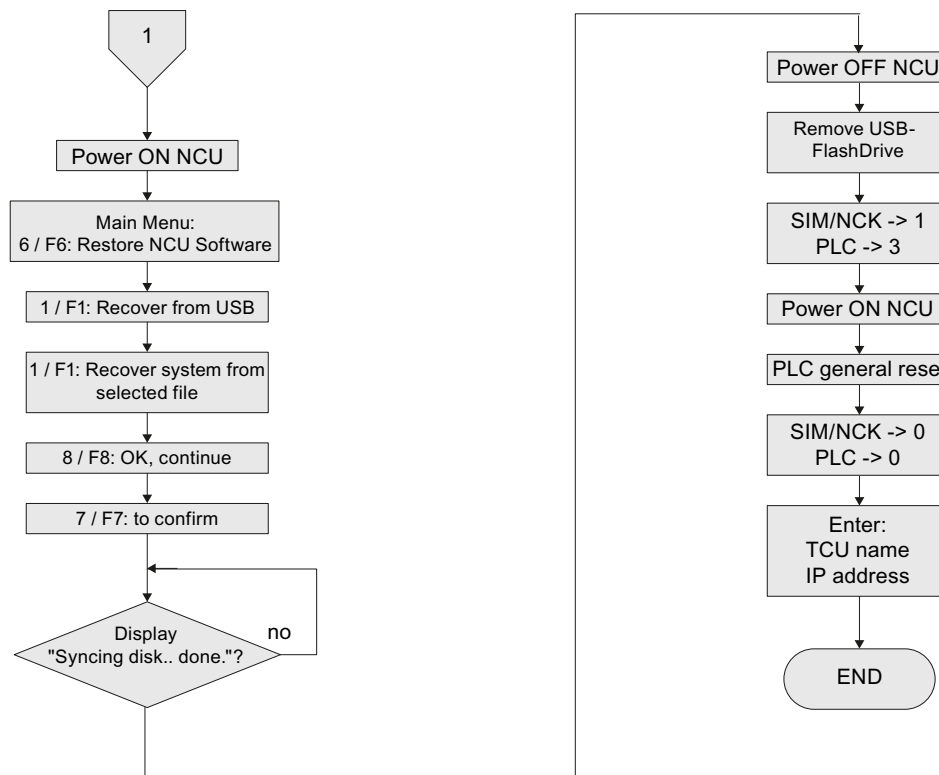


Figure 13-3 Installing the control software using USB-FlashDrive - continued (TCU system)

Flow diagram - installation of the system PCU (2) continued

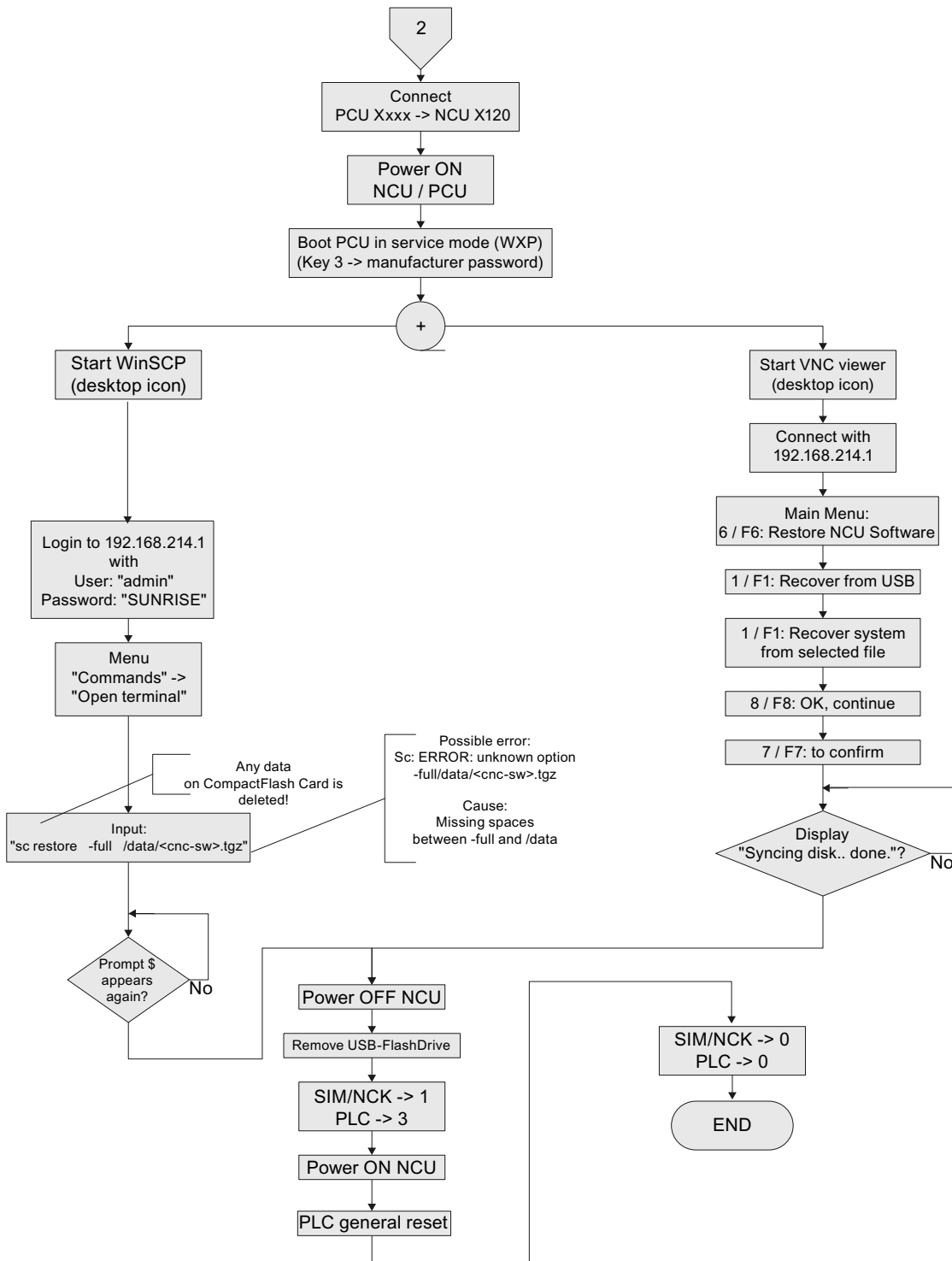


Figure 13-4 Installing the control software using USB-FlashDrive - continued (PCU system)

13.1.1.3 Installation of the CNC software using WinSCP on PC/PG

Flow diagram

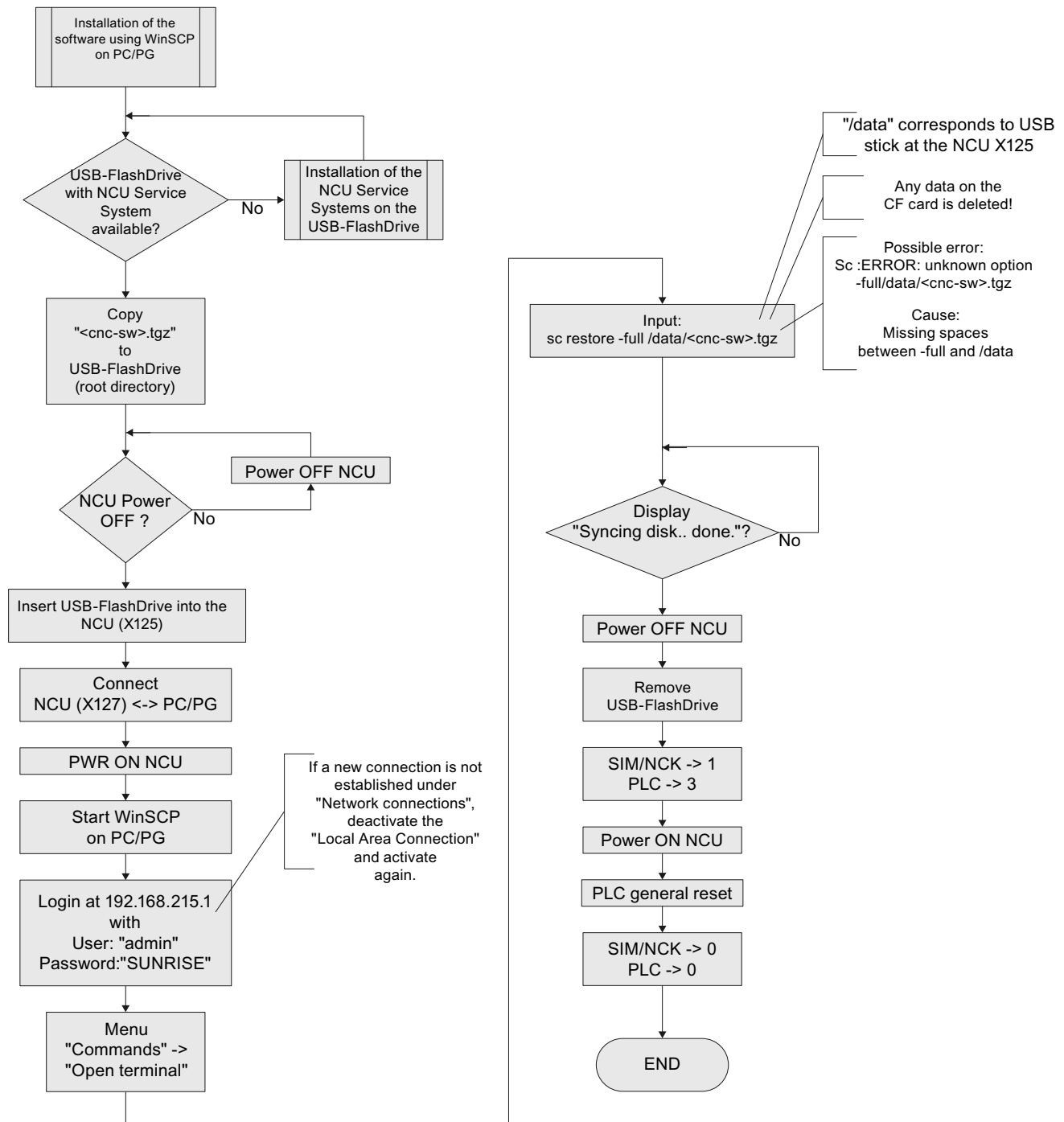


Figure 13-5 Installation using WinSCP on PG/PC

13.1.1.4 Installation of the CNC software using VNC Viewer on PC/PG

Flow diagram

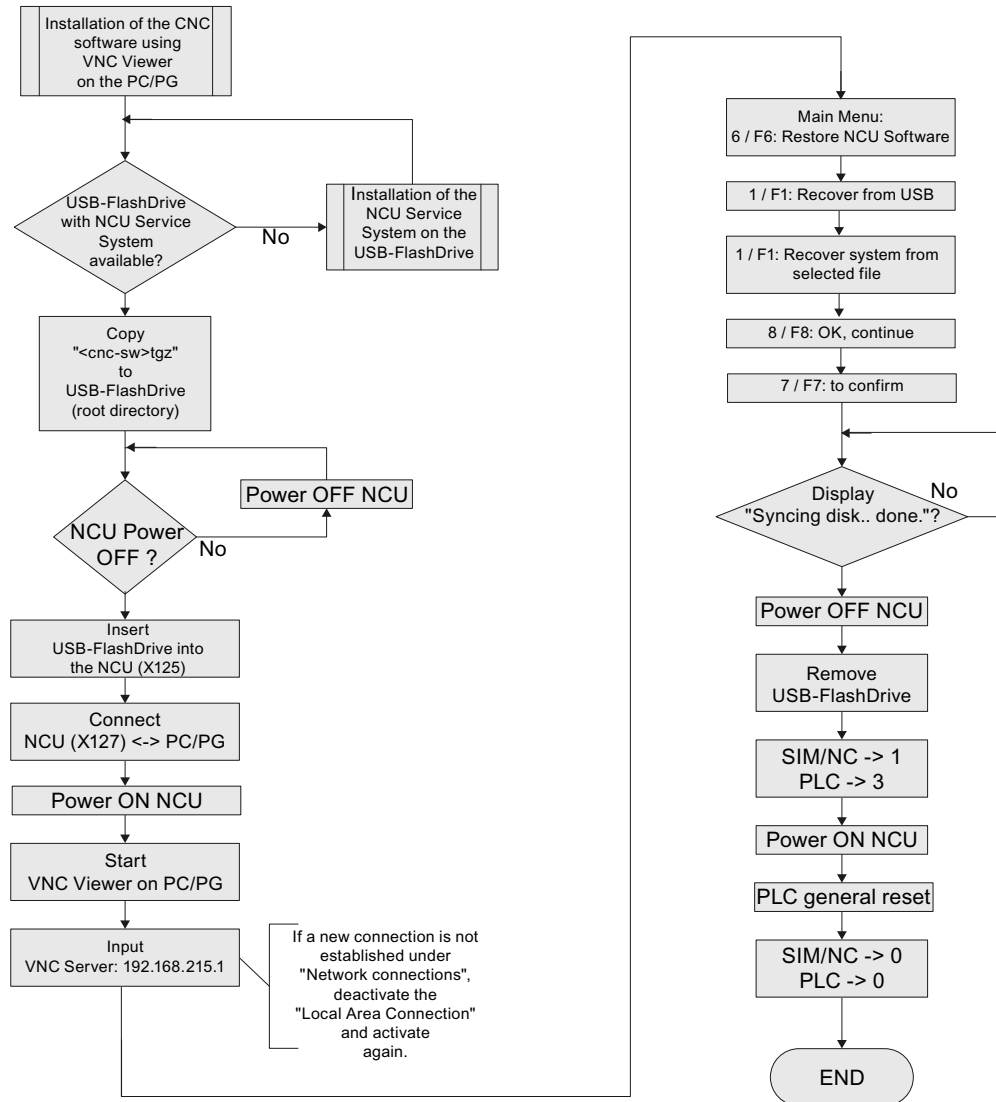


Figure 13-6 Installation using VNC Viewer on PG/PC

13.1.2 Upgrading

Upgrade options

You have the following options of upgrading the CNC software:

- Automatic upgrade using USB-FlashDrive
- Upgrade using USB-FlashDrive
- Upgrade using WinSCP on PG/PC
- Upgrade using VNC Viewer on PG/PC

Note

An upgrade is possible as of CNC software 2.xx. An upgrade from other software versions is not permitted. In this case, a new installation is required.

Before the upgrade, you can backup the complete CompactFlash card. Using Restore, you can write back this backup to the CompactFlash card.

Data backup before upgrades

Carry out a data backup before each upgrade:

- Commissioning archive of NC/PLC/drive data
- Load the PLC project into the PC/PG (STEP 7)
- License key

When the software is upgraded, all user data is kept on the CompactFlash card in the directories /user, /addon, /oem. The license key is kept as well.

Prior to overwriting a licensed CompactFlash card, a backup of the license key is absolutely necessary. The key is available in the 'keys.txt' file and stored under the path /card/keys/sinumerik. The backup of the key can be performed, for example, with WinSCP, from the PG/PC.

Note

The licenses are permanently assigned to the CompactFlash card (card ID) and can only be used on this card.

The license key can be read back via Web License Manager (Page 331) using the card number.

Automatic upgrading

For an automatic upgrade with autoexec.sh from the USB-FlashDrive, the CompactFlash card is first backed up.

The backup file "card_img.tgz" is saved under the following directory:

/machines/[machine name+serial number of the CompactflashCard]

An existing data backup is not overwritten. In this case, the operation is exited with an error. The upgrade is made once the backup has been successfully completed.

13.1.2.1 Backup/Restore

Introduction

Before the upgrade, you can backup the complete CompactFlash Card. Using Restore, you can write back this backup to the CompactFlash Card.

Automatic backup of the complete CompactFlash Card

Flow diagram

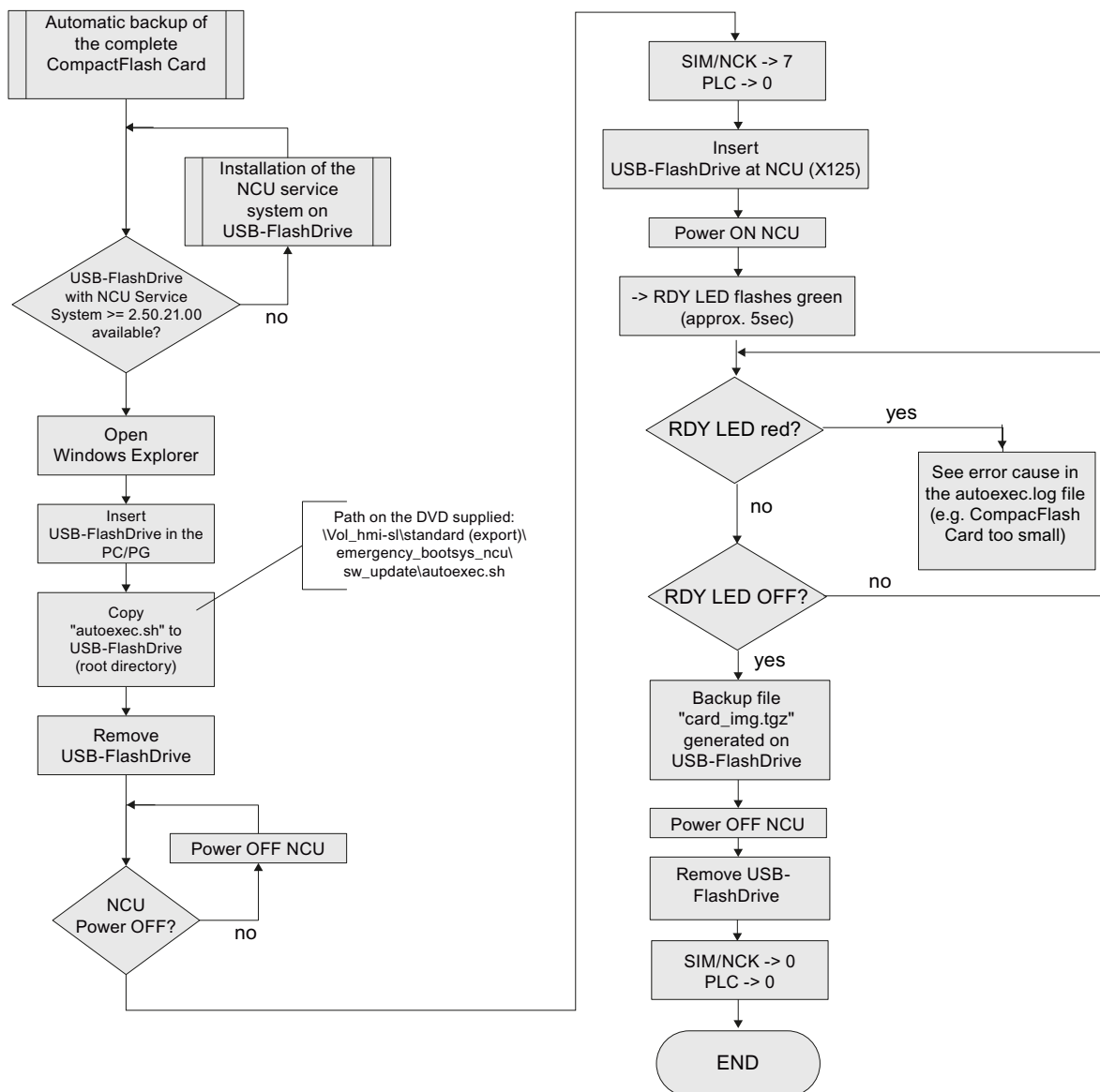


Figure 13-7 Automatic backup of the complete CompactFlash Card

Automatic restoration of the complete CompactFlash Card

Flow diagram

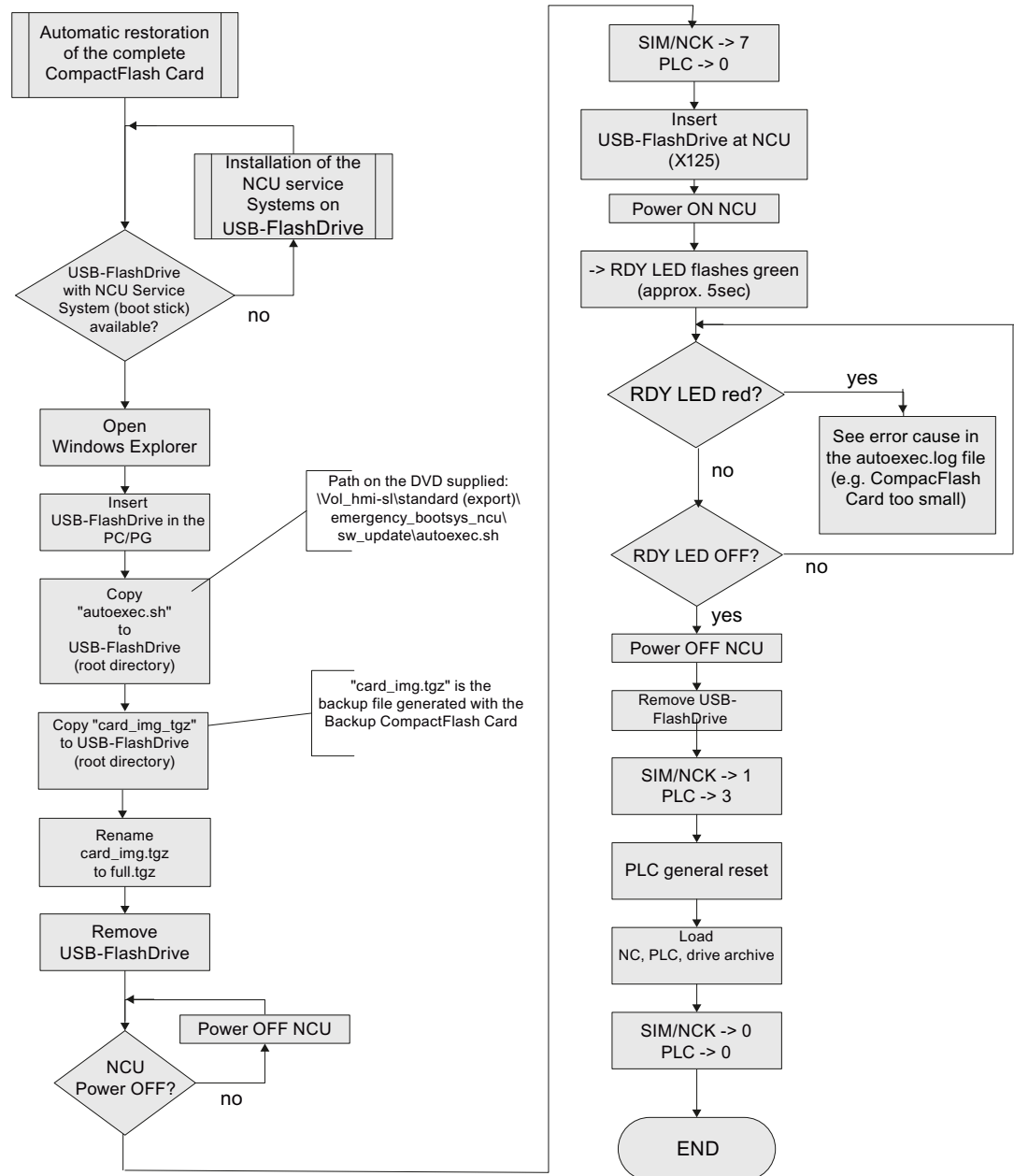


Figure 13-8 Automatic restoration of the complete CompactFlash Card

13.1.2.2 Automatic upgrade of the CNC software using USB-FlashDrive

Flow diagram

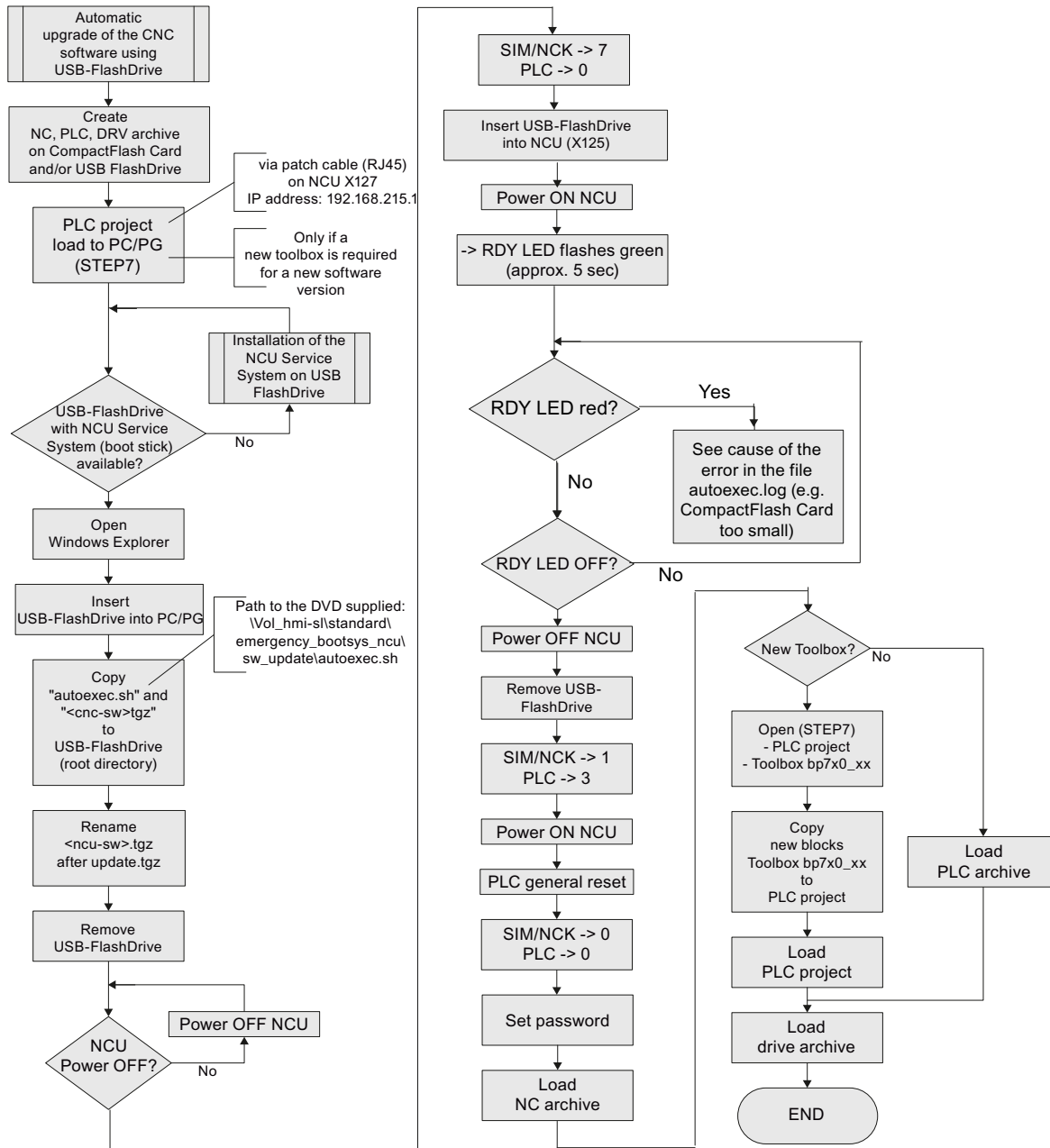


Figure 13-9 Automatic upgrade of the CNC software using USB-FlashDrive

13.1.2.3 Upgrading the CNC software using USB-FlashDrive

Flow diagram

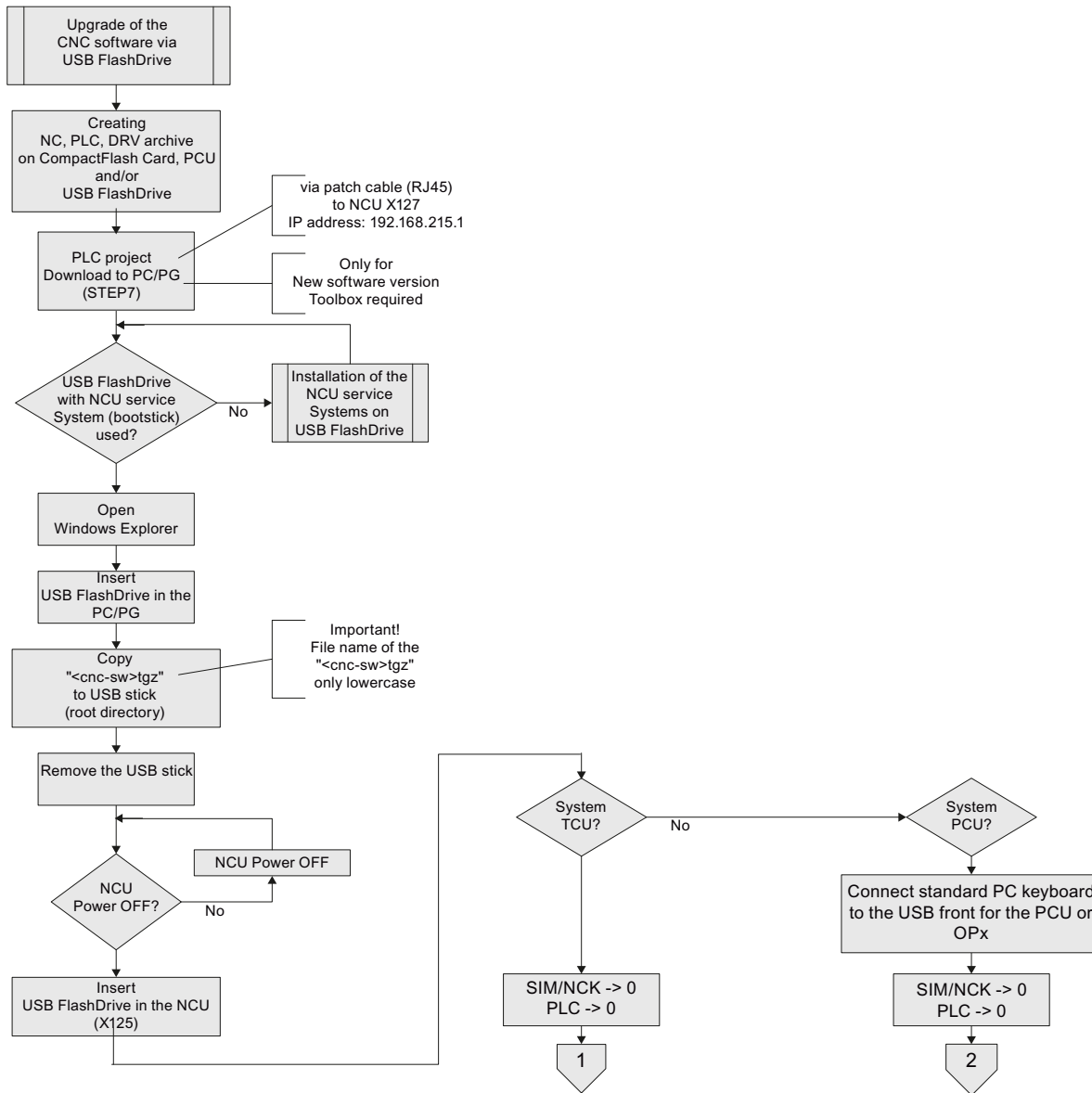


Figure 13-10 Upgrading the CNC software using USB-FlashDrive

Flow diagram - continued system TCU (1)

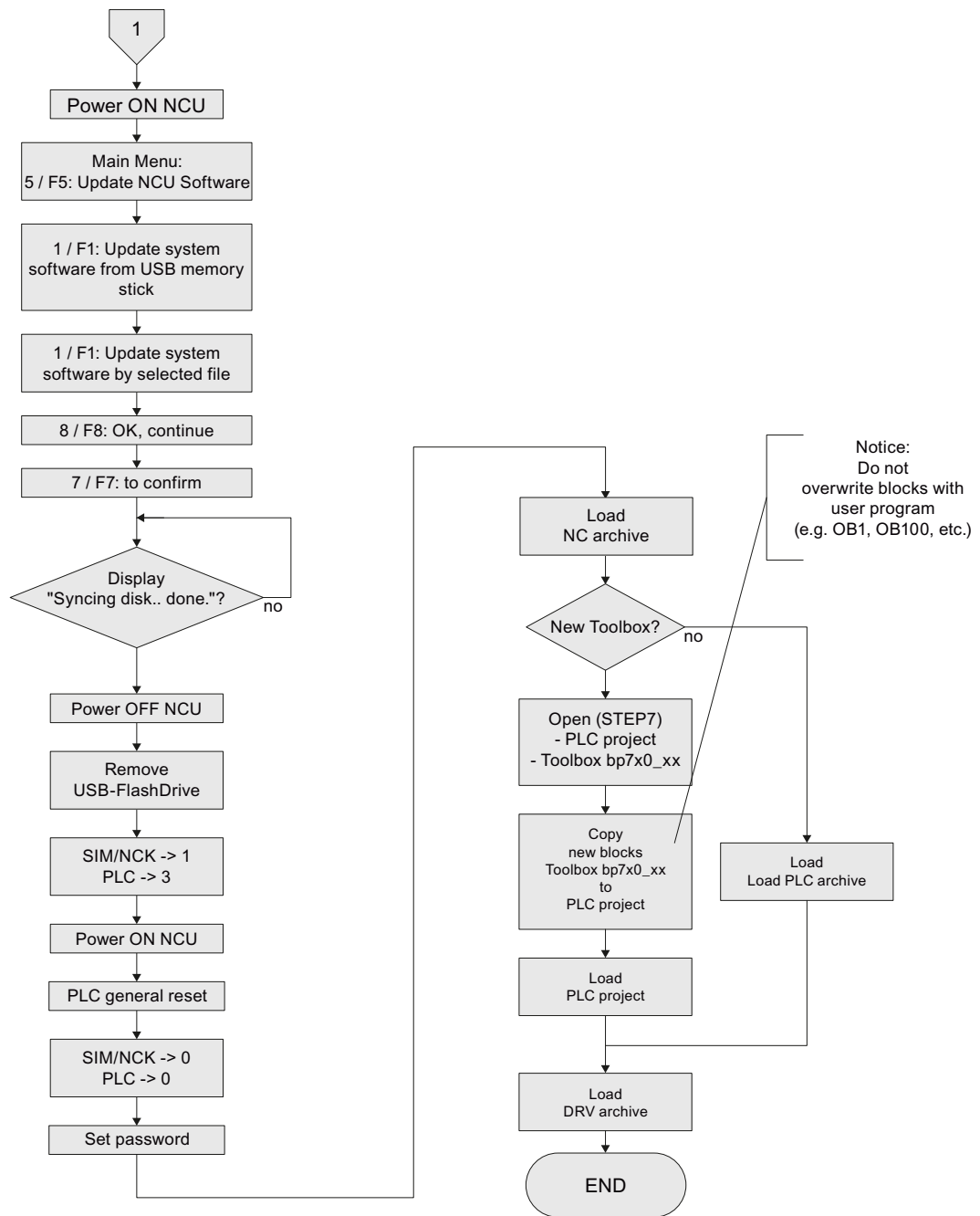


Figure 13-11 Upgrading the CNC software using USB-FlashDrive - continued (TCU system)

Flow diagram - continued PCU system (2)

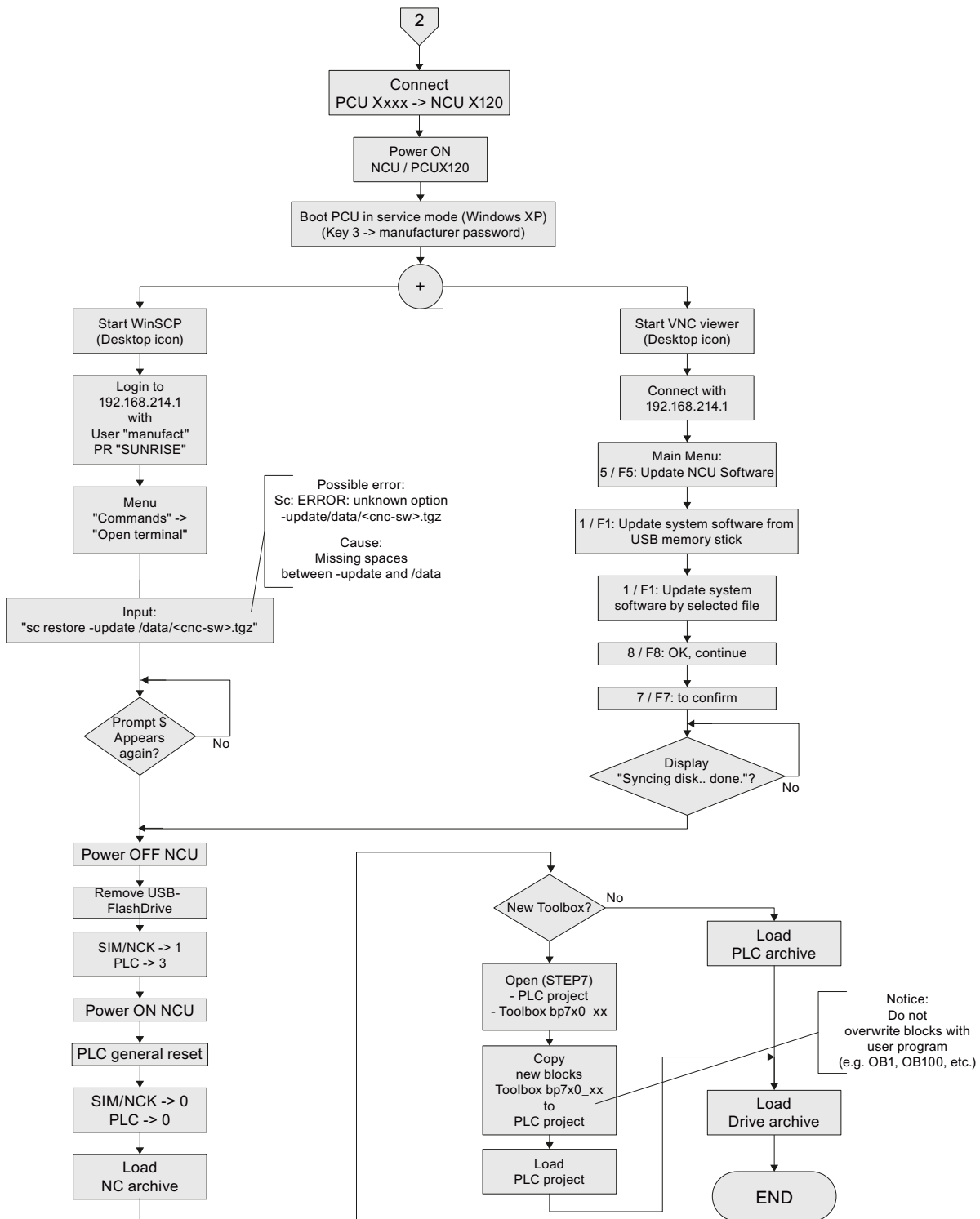


Figure 13-12 Upgrading the CNC software using USB-FlashDrive - continued (PCU system)

13.1.2.4 Upgrading the CNC software using WinSCP on PC/PG

Flow diagram

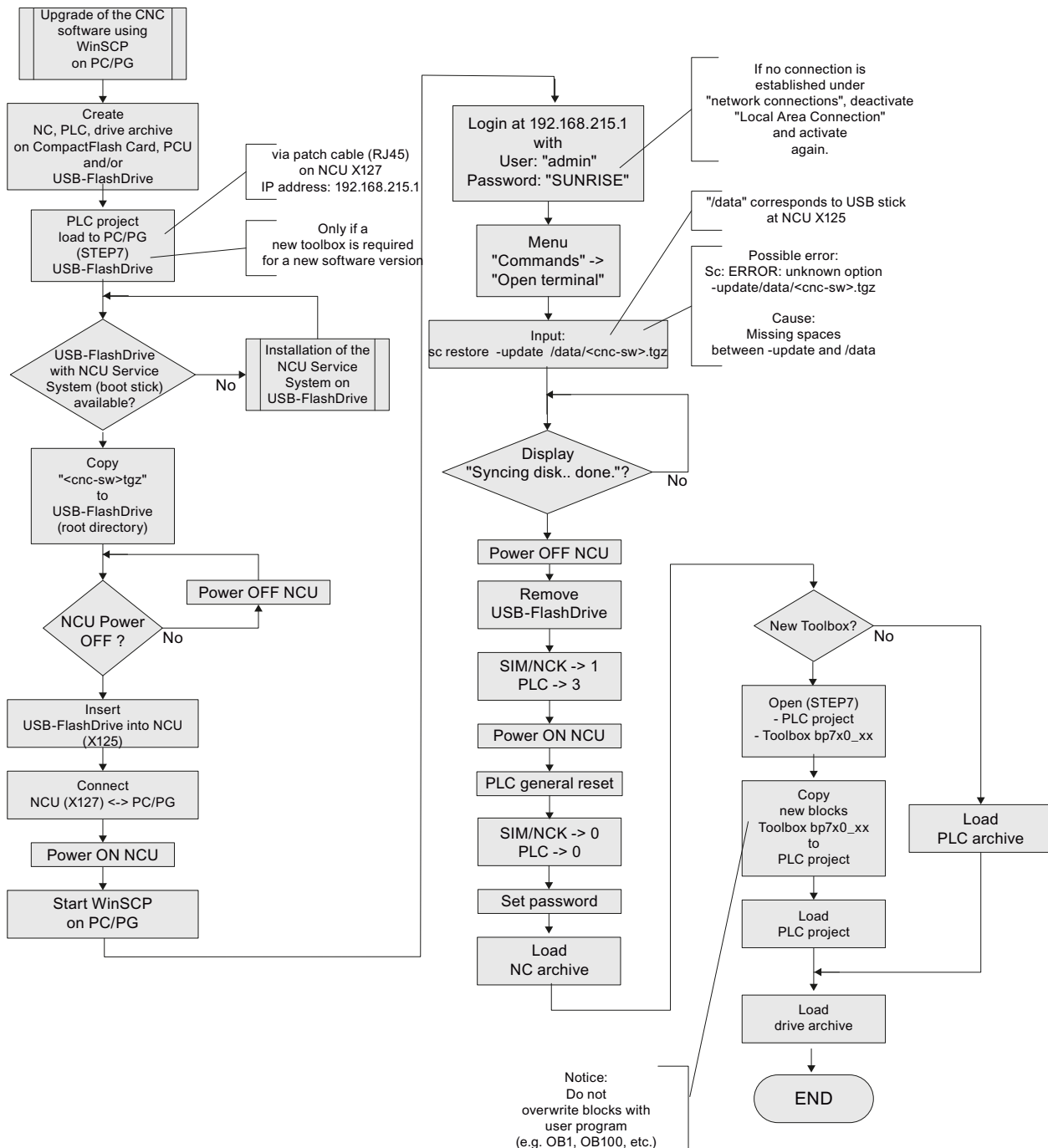


Figure 13-13 Upgrading the CNC software using WinSCP on PG/PC

13.1.2.5 Upgrading the CNC software using VNC Viewer on PC/PG

Flow diagram

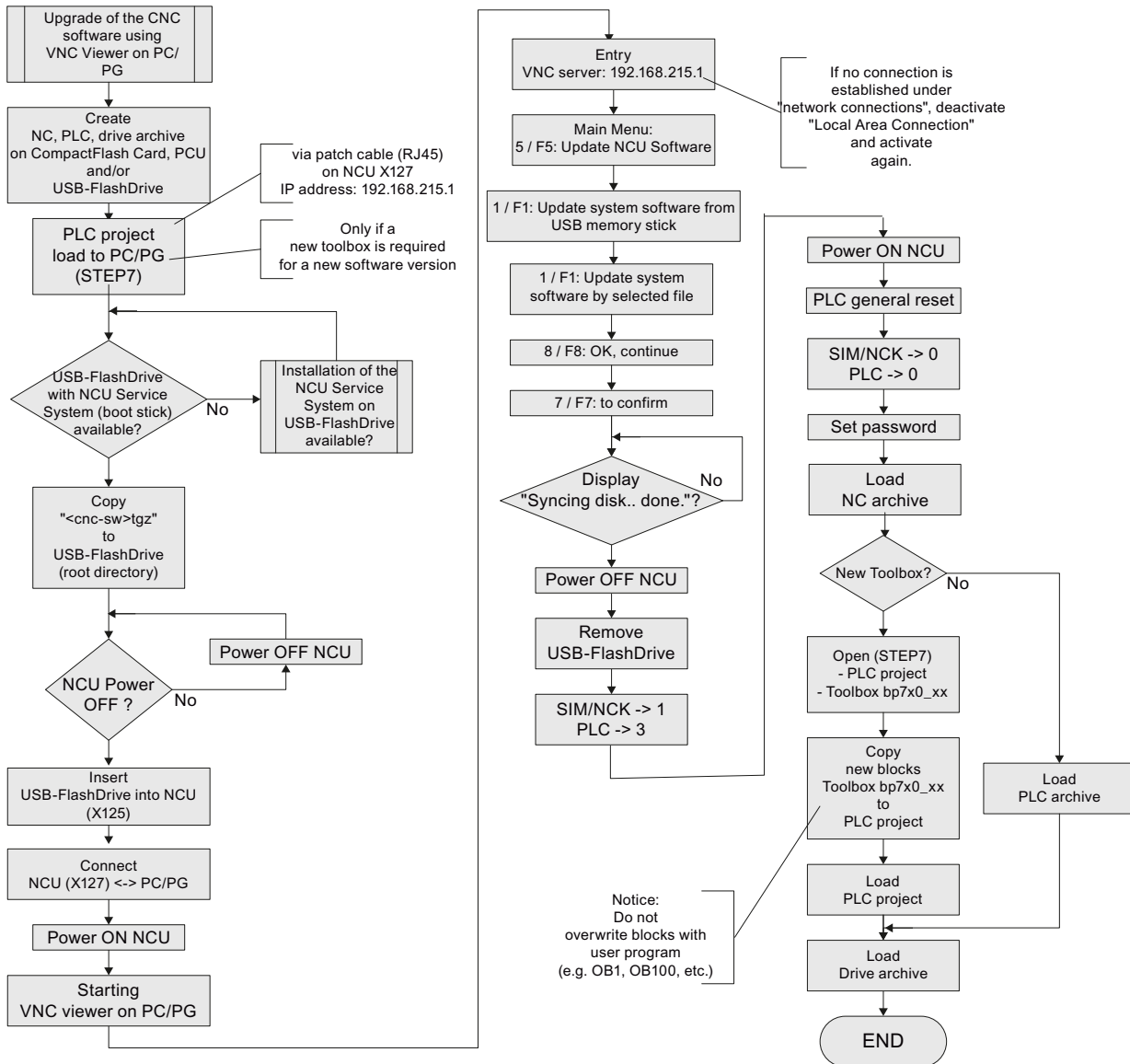


Figure 13-14 Upgrading the CNC software using VNC Viewer on PC/PG

13.2 With the help of the "Create MyConfig" software

Precondition

Precondition for the configuring of a package for the automatic reinstallation/upgrade is that the "Create MyConfig" software as of version 4.5 is installed on your PG/PC.

Basic procedure

The descriptions for reinstallation/upgrading with Create MyConfig include the basic steps for configuring and subsequent automatic reinstallation/upgrading of an NCU.

The "Create MyConfig Expert" software also provides detailed online help.

13.2.1 Automatic reinstallation with Create MyConfig (CMC)

Preconditions

The following preconditions must be met for the CompactFlash card of the NCU:

- The CompactFlash card of the NCU is empty or contains executable NCU software.
If any CNC software and possibly irrelevant user data are on the CompactFlash card, then these are lost when the software is newly installed.
- You have a <name>.tgz file (cnc-sw.tgz) with the actual software.
- You want to initiate a new installation of the NCU via a USB FlashDrive.
- If the CompactFlash card is empty or does not contain executable CNC software, you need a USB FlashDrive with installed "NCU Service System".

Operating sequence

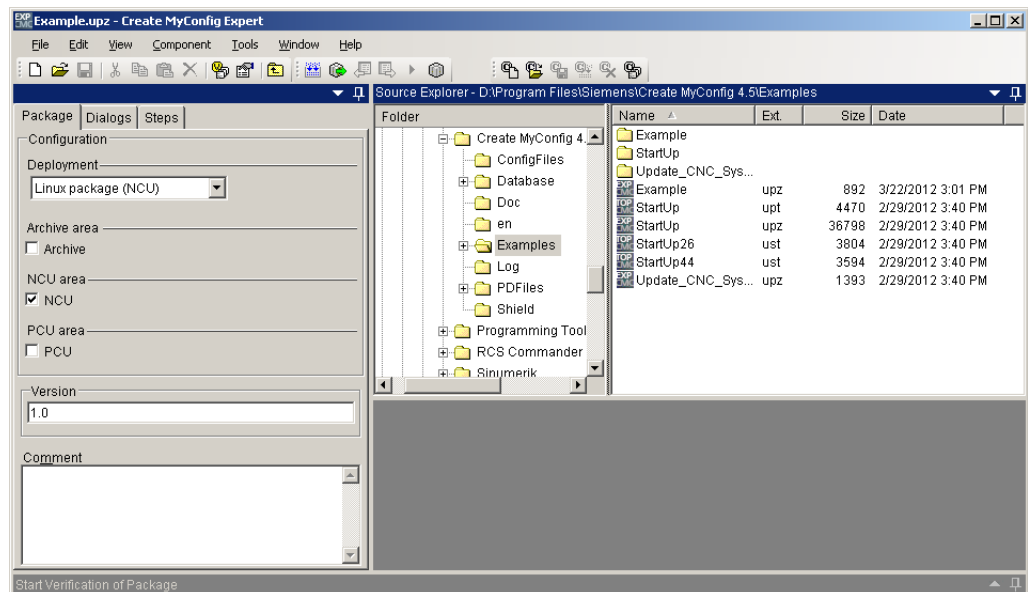
In order to configure a package for the reinstallation of the CNC software with "Create MyConfig Expert":

1. Start the "Create MyConfig Expert" software.

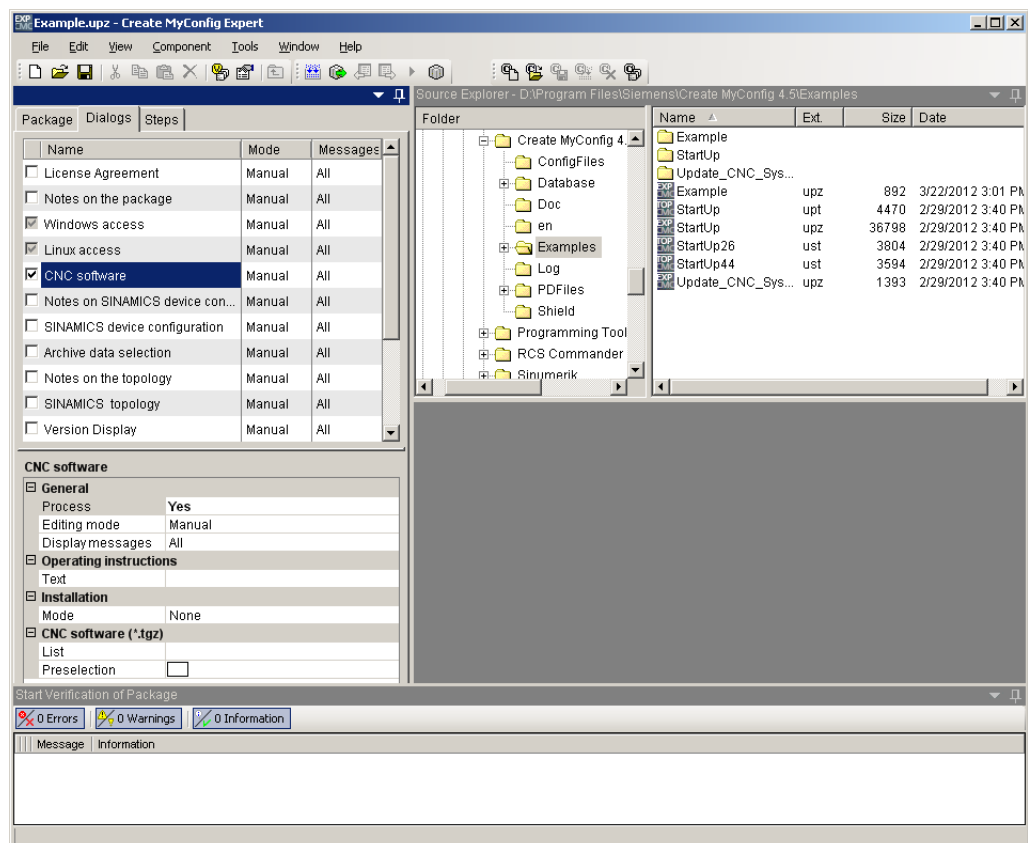
With this software you configure an Installer package that initiates a reinstallation from the USB Flashdrive to the CompactFlash card of the NCU.

2. Create a new project under "File" > "New" > "New Project".

3. Activate the "NCU" area under the "Package" tab.



4. Activate the "NCU software" window from the "Dialogs" tab.



5. In the context menu, select > right mouse button > "Edit mode for all dialog boxes" > "Automatic".

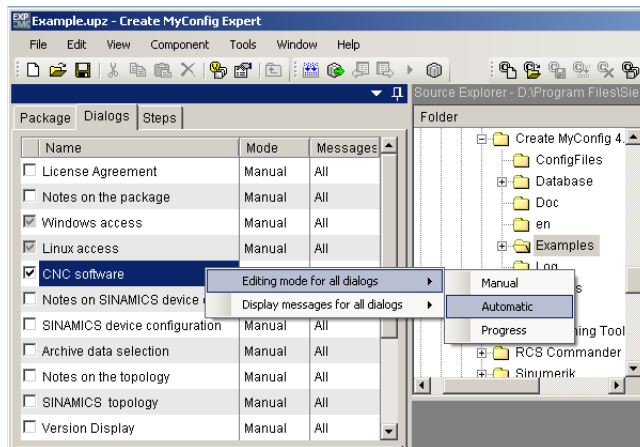
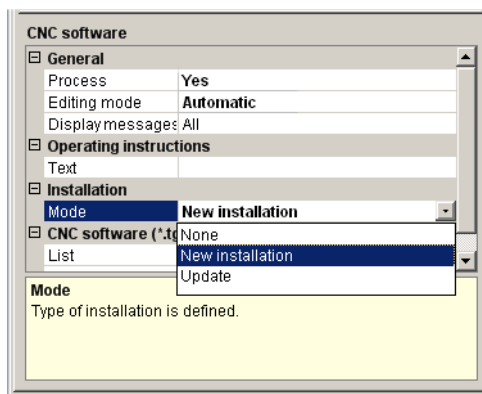


Figure 13-15 Automatic edit mode

6. In the "CNC software" window under "Installation", select the "New installation" mode.



7. For the file "<name>.tgz" you have the following options:

- The file is embedded in the project or linked to the project.

For the automatic reinstallation, insert the "<name>.tgz" file in the project under "CNC software (*.tgz)". To do this, enter the name of the tgz file in the "Preselection" area.

- Copy the file to the USB FlashDrive in the root directory in which the package is stored subsequently. The file is automatically selected while the package is running.

Enter the name with the prefix "./" in the "Preselection" field under "CNC software (*.tgz)": ./<name>.tgz

8. Create a package "<name>.usz" via the menu "File" > "Transfer" > "Linux package (NCU)" and select as target path the root directory of the USB FlashDrive.

Create MyConfig Expert saves the project, performs a validation run, creates and saves the package under the specified target path.

A "<name>.usz" package is then located in the root directory of the USB FlashDrive. Depending on the configuration in the previous step, the "<name>.tgz" file is also located next to the package.

Note

The USB FlashDrive must only be bootable if the CompactFlash card of the NCU does not contain executable CNC system software.

9. Insert the USB FlashDrive into a USB socket (X125 or X135) of the NCU.

10. Switch the control system off and on again.

Provided that when configuring you configured the "Edit mode of all dialogs" > "Automatic", then the package is automatically executed when the control system boots-up. The dialogs are displayed, but require no operator actions.

The CNC software has been installed once the package has been completed.

A logbook about the activities that have been performed can be saved. The logbook documents all activities performed during the new installation.

11. Switch-off the control system.

12. Remove the USB FlashDrive.

13. Commissioning work can continue after the control system has been switched on.

Optional additional functions for the installation of the CNC software

In the same package - after the CNC software has been installed - the following actions can be optionally configured, which can either run completely automatically or conditionally at the machine:

- Loading an SDB Archive
- SINAMICS device configuration
- Renaming DO, SINAMICS components and DO numbers
- Assignment of the drives to NC axes
- Manipulation of display machine data
- Manipulation of individual NC and drive data
- Loading PLC user programs or individual blocks
- Installation of user software
- Copying, deleting and manipulating files on the CompactFlash card
- Conditional execution of actions, executing, deleting, copying and manipulating
- Messages and interactions to the operator

13.2.2 Automatic upgrade with Create MyConfig (CMC)

Introduction

Note

For details on upgrading the CNC software versions, read the "siemensd.rtf" (German) or "siemense.rtf" (English) file on the product CD of Create MyConfig.

When the software is upgraded, all user data is kept on the CompactFlash card and in the control areas NC, PLC, and drives. The NC and drive data is automatically transferred into the new CNC software version. Archives neither have to be created nor imported again.

The "NCK commissioning switch" and "PLC mode selector switch" remain during the upgrade in position "0".

In conjunction with an upgrade, using the same package, the automatic generation of a backup can be configured, which is then stored on the USB FlashDrive. It is not necessary to first generate an archive.

Note

After the CNC software has been upgraded, adaptations may be required. Using the Create MyConfig Expert, these adaptations can also be configured and therefore automatically executed.

For information about the necessary adaptations, please refer to the upgrade instructions of the respective CNC software versions.

Operating sequence

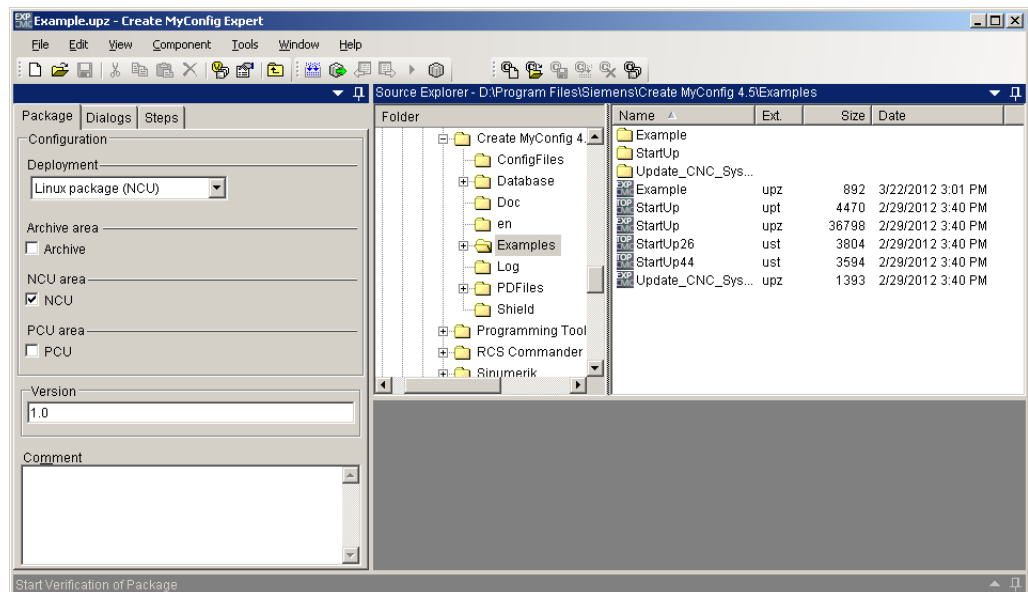
In order to configure a package for the upgrade of the CNC software with "Create MyConfig Expert":

1. You have started the "Create MyConfig Expert" software.

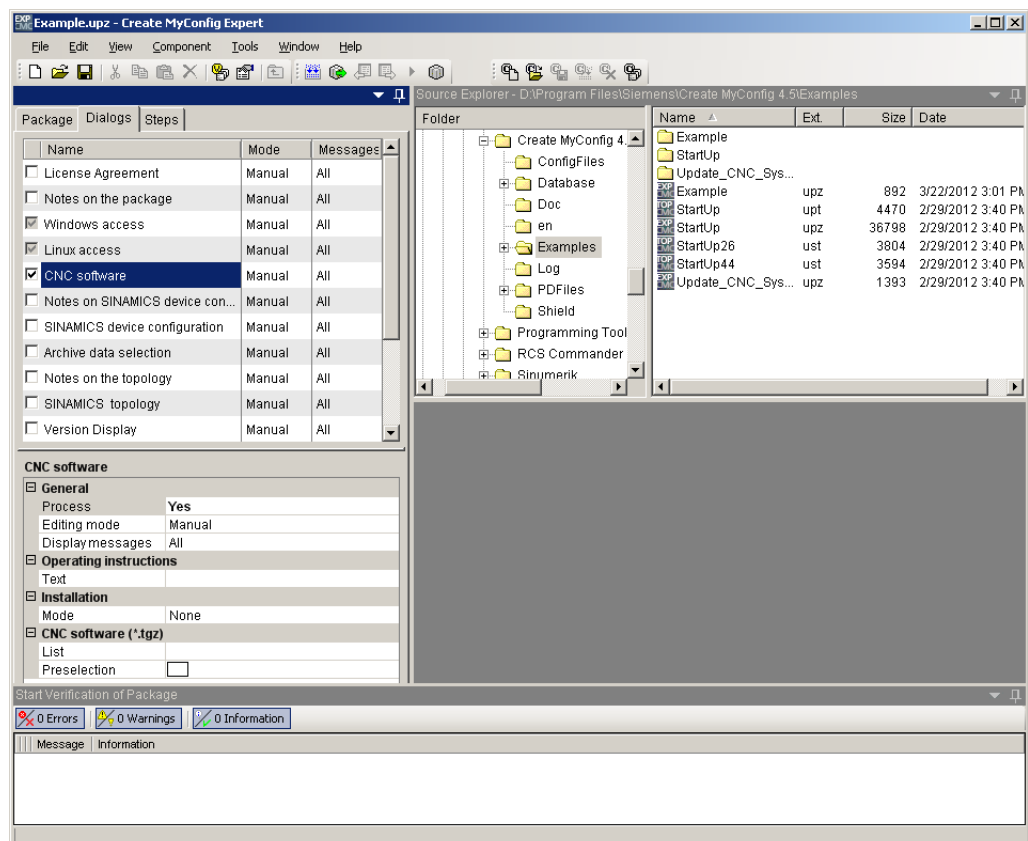
Using this software, you configure a package that initiates an upgrade of the CNC software on the CompactFlash card of the NCU.

2. You have created a new project under "File" > "New" > "New Project".

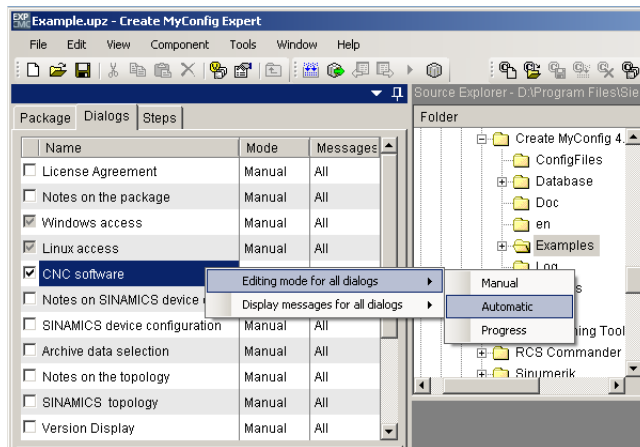
3. Activate the "NCU" area under the "Package" tab.



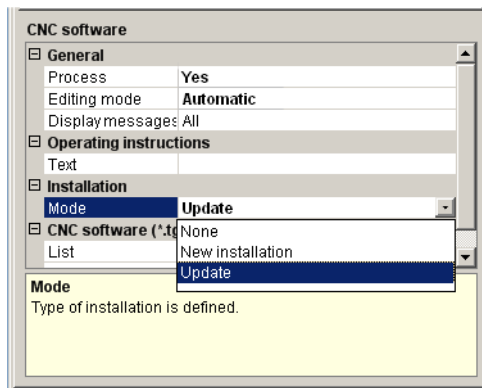
4. Activate the "NCU software" window from the "Dialogs" tab.



5. In the context menu, select > right mouse button > "Edit mode for all dialog boxes" > "Automatic".



6. In the "CNC software" window under "Installation", select the "Upgrade" mode.



7. For the <name>.tgz files you have the following options:
 - The file is embedded in the project or linked to the project.
For the automatic reinstallation, insert the "<name>.tgz" file in the project under "CNC software (*.tgz)". To do this, enter the name of the tgz file in the "Preselection" area.
 - Copy the file to the USB FlashDrive in the root directory in which the package is stored subsequently. The file is automatically selected while the package is running.
Enter the name with the prefix "/" in the "Preselection" field under "CNC software (*.tgz)": ./<name>.tgz
8. Create a package "<name>.usz" via the menu "File" > "Transfer" > "Linux package (NCU)" and select as target path the root directory of the USB FlashDrive.
Create MyConfig Expert saves the project, performs a validation run, creates and saves the package under the specified target path.
A "<name>.usz" package is then located in the root directory of the USB FlashDrive. Depending on the configuration in the previous step, the "<name>.tgz" file is also located next to the package.

9. Insert the USB FlashDrive into a USB socket (X125 or X135) of the NCU.

10. Switch the control system off and on again.

Provided that when configuring you configured the "Edit mode of all dialogs" → "Automatic", then the package is automatically executed when the control system boots-up. The CNC software has been upgraded and all data is available again after the package has been completed on the NCU.

A logbook about the activities that have been performed can be saved. The logbook documents all activities performed during the upgrade.

11. Switch-off the control system.

12. Remove the USB FlashDrive.

13. The machine is ready for operation again after switch-on.

Optional additional functions when upgrading the CNC software

In the same package - after the CNC software has been installed - the following actions can be optionally configured, which can either run completely automatically or conditionally at the machine:

- Manipulation of display machine data
- Manipulation of individual NC and drive data
- Loading PLC user programs or individual blocks
- Installation of user software
- Copying, deleting and manipulating files on the CompactFlash card
- Conditional execution of actions, executing, deleting, copying and manipulating
- Messages and interactions to the operator

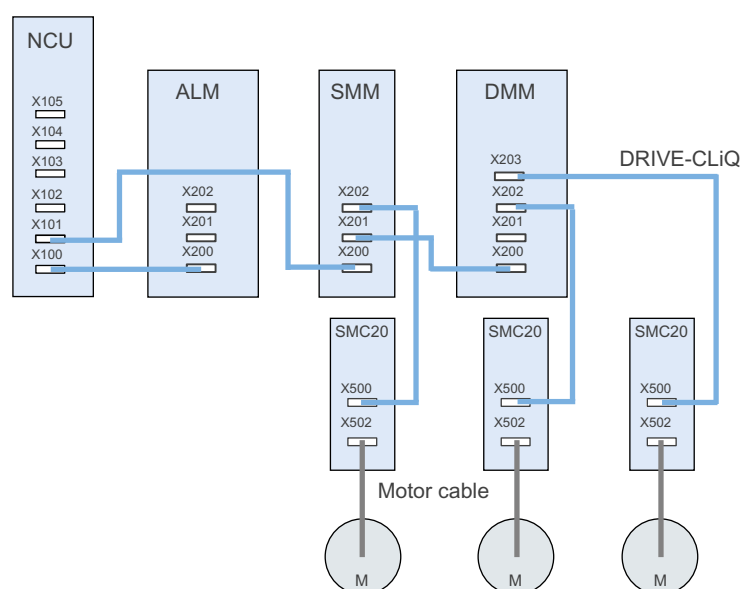
Fundamentals

14.1 Basic information on SINAMICS S120

14.1.1 Rules for wiring the DRIVE-CLiQ interface

Topology rules

When wiring components with DRIVE-CLiQ, the following rules apply: The rules are subdivided into **obligatory rules**, which must be observed, and **optional rules**, which enable automatic topology detection if they are adhered to.



NCU	SINUMERIK control system
ALM	Active Line Module
SMM	Single Motor Module
DMM	Double Motor Module
M	Motor

Figure 14-1 Topology example

Obligatory rules:

- A maximum of 198 DRIVE-CLiQ node components can be connected for each NCU.
- Up to 16 nodes can be connected to a DRIVE-CLiQ socket.
- A maximum of 7 nodes can be connected in one row. A row is always considered from the perspective of the closed-loop control module.
- Ring wiring is not permitted.
- Components must not be double-wired.

Optional rules:

When the optional rules for the DRIVE-CLiQ wiring are observed the components concerned will be automatically assigned to the drives:

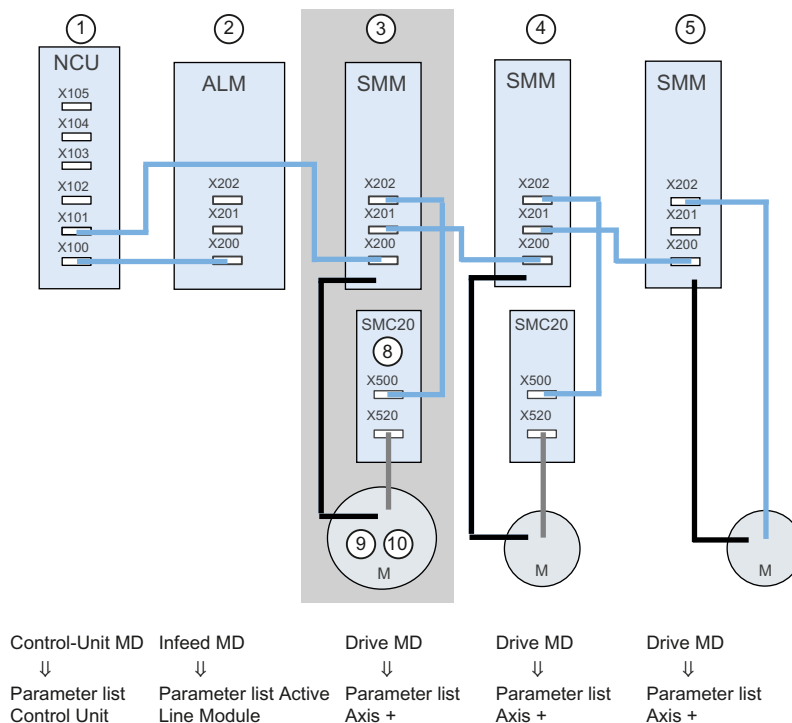
- For one motor module, the related motor encoder must also be connected.
- Due to the improved performance utilization, use as many DRIVE-CLiQ points on the NCU as possible.
- It is essential that you comply with the optional rules when using the macro. This is the only way to achieve a proper assignment of the drive components.

14.1.2 Drive objects and drive components

Example of a drive line-up

The components that belong to the drive group are reflected in the parameterization in a drive object. Each drive object has its own parameter list.

Using the example of a SINAMICS S120 drive line-up, the significance of the drive components on drive objects is shown:



Drive object DO3 comprises the following components:

- ③ Single Motor Module
- ⑧ SMC20
- ⑨ Motor encoder
- ⑩ Motor

Figure 14-2 Drive group

The component number is assigned by the drive after detection of the DRIVE-CLiQ topology. You can see the respective component numbers in the parameter list for the relevant drive object in the operator area "Start-up" → "Machine data" → "Drive MD" → "Axis + ":

Parameter	Parameter designation
p0121	Power unit component number
p0131	Motor component number
p0141	Encoder interface (Sensor Module) component number
p0142	Encoder component number

14.1.3 BICO interconnection

Introduction

Each drive unit contains a large number of interconnectable input and output variables as well as internal control variables. BICO technology (binector connector technology) allows the drive to be adapted to a wide variety of conditions.

Digital and analog signals, which can be interconnected as required by means of BICO parameters, are identified by the prefix BI, BO, CI, or CO in their parameter name. These parameters are identified accordingly in the parameter list or in the function diagrams:

- Binectors (digital): BI: binector input, BO: binector output
- Connectors (analog): CI: connector input, CO: connector output

To interconnect two signals, a BICO input parameter (signal sink) must be assigned to the required BICO output parameter (signal source).

Visualization of the BICO interconnection

Under the following menu you can create a BICO interconnection to the components involved in the SINAMICS drive lineup.

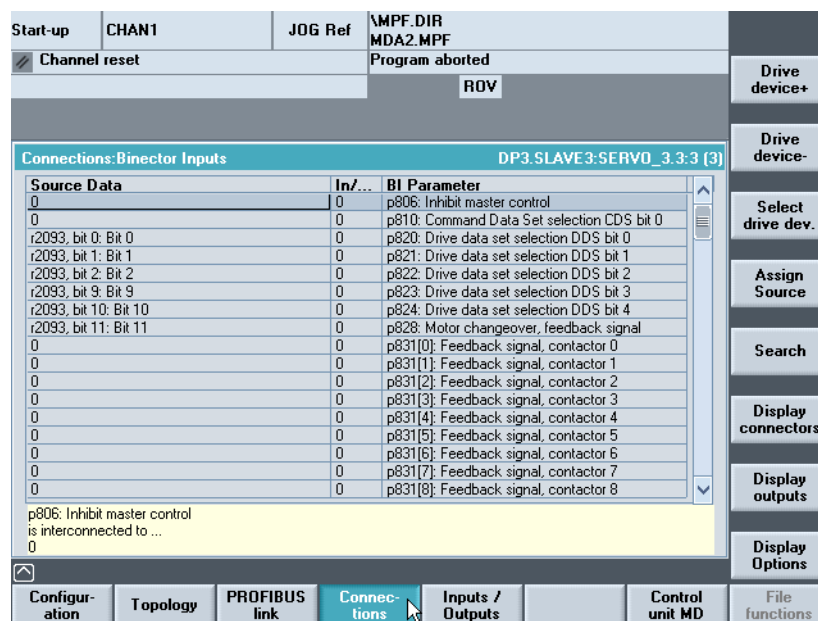


Figure 14-3 Example: "Interconnections"

References

SINAMICS S120/S150 List Manual /LH1/

14.1.4 Transfer telegrams

Introduction

The transfer telegrams from the NC to the drive are transferred via an internal PROFIBUS on the NCU:

- Send telegrams (drive → NC)
- Receive telegrams (NC → drive)

The telegrams are standard telegrams with pre-defined assignment of the process data. These telegrams are interconnected in the drive object using BICO technology.

The following drive objects can exchange process data:

1. Active Line Module (A_INF)
2. Basic Line Module (B_INF)
3. Motor Module (SERVO)
4. Control Unit (CU)

The sequence of the drive objects in the telegram is displayed on the drive page via the parameter list in the "Commissioning" → "Machine data" → "Control Unit MD" operating area in p0978[0...15] and may also be changed through it.

Receive words / send words

Selecting a telegram via p0922 of the related drive object ("Commissioning" → "Machine data" → "Drive MD" operating area) determines the process data to be transferred between the master and slave.

From the perspective of the slave, the received process data comprises the receive words and the process data to be sent the send words.

The receive and send words are comprised of the following elements:

- Receive words: Control words or setpoints
- Send words: Status words or actual values

Telegram types

What telegram types are available?

- Standard telegrams

The standard telegrams are structured in accordance with the PROFIdrive Profile V3.1. The internal process data links are set up automatically in accordance with the telegram number setting.

- Manufacturer-specific telegrams

The manufacturer-specific telegrams are structured in accordance with internal company specifications. The internal process data links are set up automatically in accordance with the telegram number setting.

The telegram length for communication with the drive must be defined in the hardware configuration. The telegram length to be chosen depends on the axis functions required, e.g. the number of encoders or the functions in the drive.

Note

If you change the telegram length of a drive component in HW Config, you also must adjust the selection of the telegram type in the configuration of the interface in the NC.

The following vendor-specific telegrams can be set via p0922:

Telegram number:		
for axes (SERVO)	116:	Speed setpoint, with 2 position encoders, torque reduction and DSC, plus load, torque, power and current actual values
	118:	Speed setpoint, with 2 external position encoders, torque reduction and DSC, plus load, torque, power and current actual values
	136:	DSC with torque pre-control, 2 position encoders (encoder 1 and encoder 2), 4 trace signals
	138:	DSC with torque precontrol, 2 external position encoders (encoder 2 and encoder 3), 4 trace signals
	139:	For Weiss spindle only: Speed/position control with DSC and torque precontrol, 1 position encoder, clamping status, supplementary actual values
for Control Unit	390:	Telegram without measuring probe for NX expansion
	391:	Telegram for up to two probes for NCU
	395:	Control Unit with digital inputs/outputs and 16 probes

References

You can find further details in

- SINAMICS S120 Commissioning Manual (IH1); Section "Preparations for Commissioning"
- SINAMICS S120 Function Manual (FH1); Section "Communication"
- SINAMICS S120/S150 List Manual (LH1); Section "Function block diagrams"

14.2 Axis data

Introduction

The term "axis" is often used either as a single term in conjunction with SINUMERIK 840D sl or in compounded form, e.g. machine axis, channel axis, etc. To provide an overview of the philosophy used as the basis, here is a brief explanation of this term.

Definition

Generally, 4 types of axes are distinguished:

1. Machine axes
2. Channel axes
3. Geometry axes
4. Special axes

Machine axes

Machine axes are the motion units existing on a machine, which can also be designated as linear or rotary axes, depending on their usable movement.

Channel axes

The total of all machine, geometry and special axes assigned to a channel is designated as channel axes.

In this context, the geometry and special axes constitute the program-technological part of the machining process, i.e. they are used for programming in the parts program.

The machine axes constitute the physical part of the machining process, i.e. they carry out the programmed traversing movements on the machine.

Geometry axes

The geometry axes constitute the rectangular Cartesian basic coordinate system of a channel.

Generally, (Cartesian arrangement of the machine axes) direct imaging of the geometry axes to the machine axes is possible. If the arrangement of the machine axes, however, is not Cartesian at right angles, the imaging is performed using a kinematic transformation.

Special axes

Additional axes are all other channel axes that are not geometry axes. Unlike for geometry axes (Cartesian coordinate system), no geometric context is defined for additional axes, neither between additional axes or with respect to geometry axes.

Literature

Function Manual Basic Functions; Axes, Coordinate Systems, Frames, Workpiece numbers
IWS: Axes

14.2.1 Axis assignment

Assigning axes

The assignment of geometry axes to channel axes and channel axes to machine axes, as well as the definition of the names of the different axis types is realized via machine data.

The following diagram illustrates this relationship:

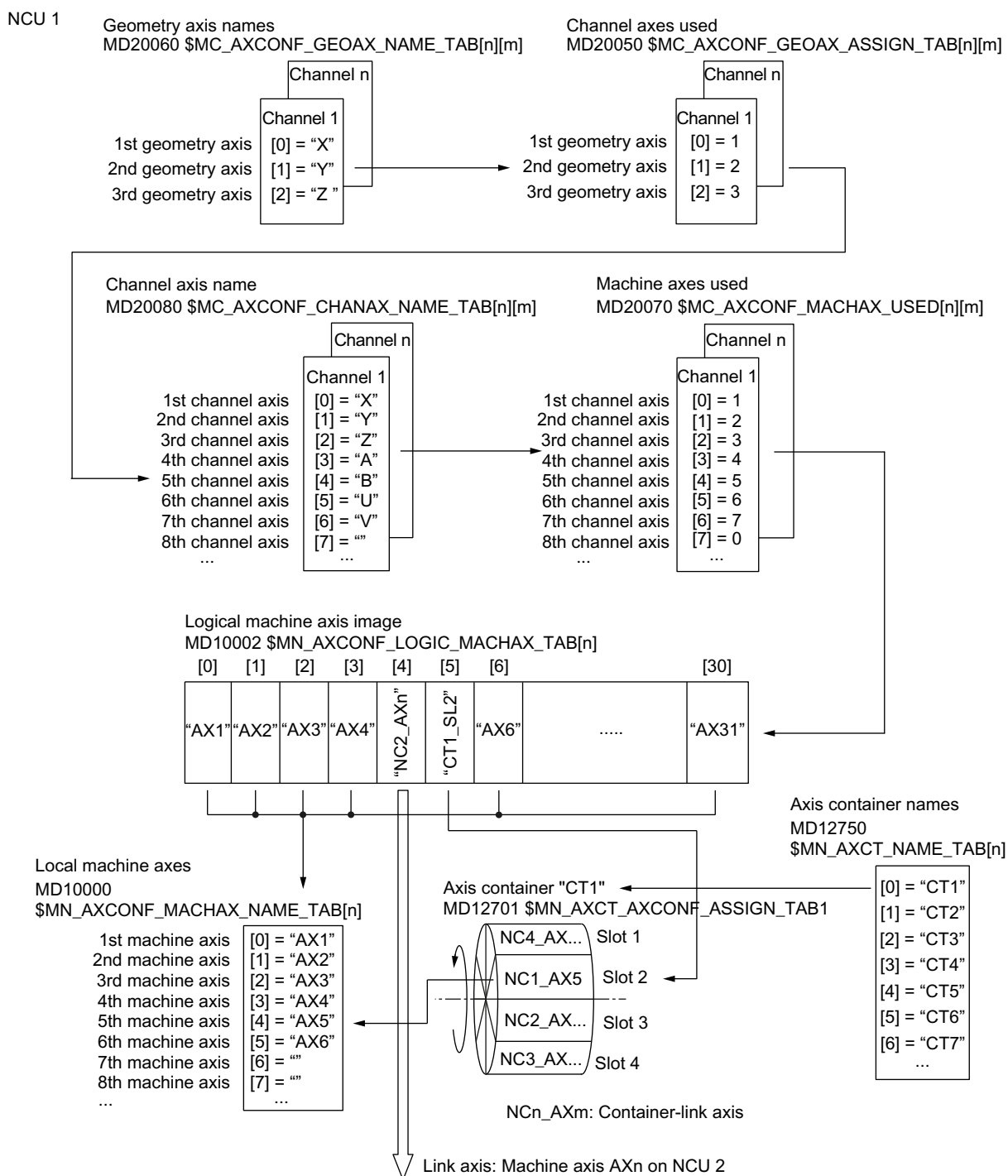


Figure 14-4 Axis assignment

Note

Geometry and special axes

A maximum of three channel axes can be declared as geometry axes. The geometry axes must be assigned to the channel axes in ascending order without any gaps.

All channel axes that are not geometry axes are special axes.

Channel axis gaps

Normally, using MD20070, a channel axis is assigned to one machine axis. Not every channel axis must be assigned to a machine axis. Each channel axis that cannot be assigned to a machine axis (MD20070 [n] = 0), represents a channel axis gap.

Channel axis gaps allow the creation of a uniform configuration of the channel axes over different machine versions of a series. Each channel axis of the series has a defined task or function. If the function and therefore the machine axis does not exist at a specific machine, the corresponding channel axis is not assigned to a machine axis:

MD20070 \$MC_AXCONF_MACHAX_USED[<channel axis>] = 0

Advantages:

- Commissioning archive with uniform basic configuration
- Simple post configuration for the specific machine
- Flexible portability of part programs

Enabling channel axis gaps

The use of channel axis gaps must be enabled using the machine data:

MD11640 \$MN_ENABLE_CHAN_AX_GAP = 1 (channel axis gap allowed).

If the use of channel axis gaps has not been enabled, then the value 0 for channel axis n in the following machine data terminates the allocation of additional machine axes to possible channel axes from channel axis n onwards:

MD20070 \$MC_AXCONF_MACHAX_USED[<channel axis n>]

Boundary conditions:

- Regarding the number of channel axes and the indexing, a channel axis gap counts just the same as axes.
- Ensure that a geometry axis is not assigned to a channel axis, that is not assigned to a machine axis (channel axis gap). **No alarm is displayed!**
- Transformation: When configuring a channel axis in the following machine data, which is not assigned a machine axis (channel axis gap), then Alarm 4346 / 4347 displayed:
 - MD24110 ff. \$MC_TRAFO_AXES_IN1...8
 - MD24120 ff. \$MC_TRAFO_GEOAX_ASSIGN_TAB1...8

Example

The 5th channel axis "B" in MD20070 is not assigned to a machine axis.

If channel axis gaps are enabled, six machine axes (1 - 4, 5, 6) are available.

If channel axis gaps are not enabled, then there are four machine axes (1 - 4) available.

NCU 1

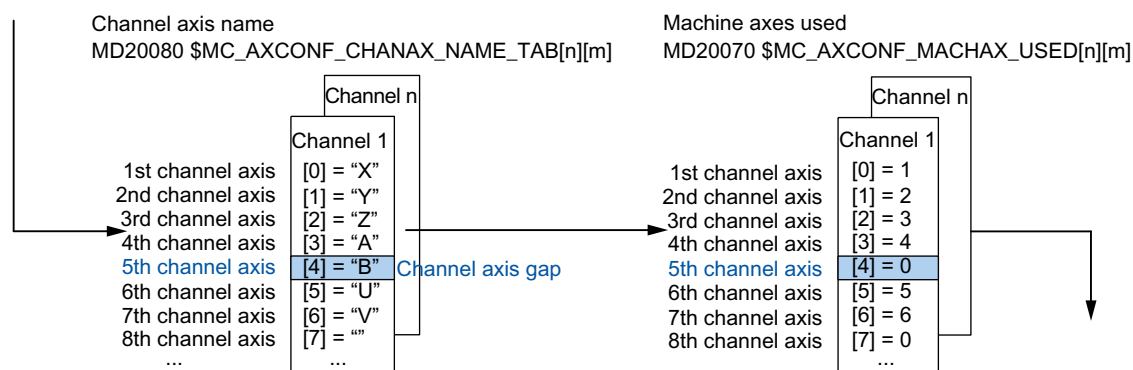


Figure 14-5 Axis configuration with channel axis gap

14.2.2 Drive assignment

Drive assignment

The assignment of machine axes to the drive objects SERVO is realized using machine data. The following diagram illustrates this relationship.

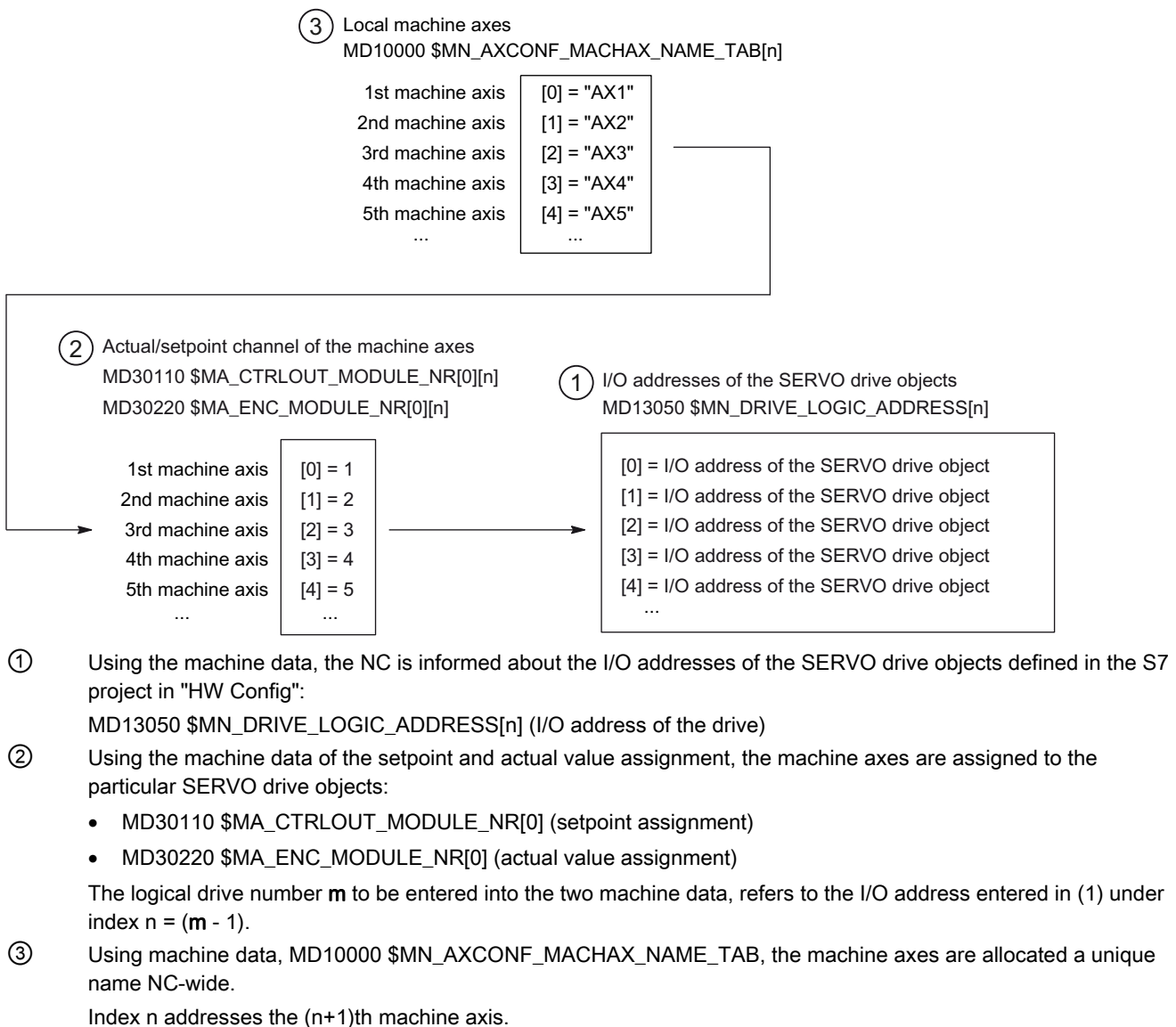


Figure 14-6 Drive assignment

Machine data

The following machine data are relevant for the assignment of channel axes to drives:

MD	Name	Meaning
10000	\$MN_AXCONF_MACHAX_NAME_TAB	Machine axis name
10002	\$MN_AXCONF_LOGIC_MACHAX_TAB	Logical machine axis image
13050	\$MN_DRIVE_LOGIC_ADDRESS	I/O address of drive
20050	\$MC_AXCONF_GEOAX_ASSIGN_TAB	Assignment of geometry axis to channel axis
20060	\$MC_AXCONF_GEOAX_NAME_TAB	Geometry axis name in channel
20070	\$MC_AXCONF_MACHAX_USED	Machine axis number valid in channel
20080	AXCONF_CHANAX_NAME_TAB	Name of channel axis in the channel
30110	\$MA_CTRLOUT_MODULE_NR	Setpoint assignment
30220	\$MA_ENC_MODULE_NR	Actual-value assignment

See also

Axis assignment (Page 376)

14.2.3 Axis names

Machine axes

Each machine, channel and geometry axis can/must be assigned an individual name unambiguously identifying it in its name range. The name of the machine axes are defined via the following machine data:

MD10000 \$MN_AXCONF_MACHAX_NAME_TAB [n] (machine axis name)

Machine axis names must be unambiguous for the entire NC.

The names and the corresponding index defined in the machine data above is used for:

- Accessing axis-specific machine data (loading, saving, displaying)
- Reference point approach from the parts program G74
- Measuring
- Test point traversing from the parts program G75
- Traversing the machine axis from PLC
- Display of axis-specific alarms
- Display in the actual-value system (machine-related)
- DRF handwheel function

Channel axes

The name of the channel axes are defined via the following machine data:

MD20080 \$MC_AXCONF_CHANAX_NAME_TAB[n] (name of the channel axis in the channel)

Channel axis names must be unambiguous for the entire channel.

Geometry axes

The name of the geometry axes are defined via the following machine data:

MD20060 \$MC_AXCONF_GEOAX_NAME_TAB [n] (geometry axis in the channel)

Geometry axis names must be unambiguous for the entire channel.

The axis names for channel and geometry axes are used in the parts program for programming general traversing movements or to describe the workpiece contour. The axis names are used for

- Path axes
- Synchronized axes
- Positioning axes
- Command axes
- Spindles
- Gantry axes
- Coupled axes
- Guide value coupling axes

Machine data

The following machine data are relevant for the axis names:

MD	Name	Designation
10000	\$MN_AXCONF_MACHAX_NAME_TAB	Machine axis name
20060	\$MC_AXCONF_GEOAX_NAME_TAB	Geometry axis name in channel
20080	\$MC_AXCONF_CHANAX_NAME_TAB	Channel axis name/special axis name in channel

14.3 Spindle data

14.3.1 Basic spindle setting

Introduction

The spindle mode of a machine axis is a subset of the general axis functionality. For this reason, the machine data required to start up an axis have also to be set for a spindle.

The machine data to parameterize a rotary axis as spindle are therefore to be found under the axis-specific machine data (from MD 35000 onwards).

Note

After the default machine data have been loaded, no spindle is defined.

Spindle definition

With the following machine data, a machine axis is declared to be an endlessly rotating rotary axis whose programming and display is carried out modulo 360 degrees.

- MD30300 \$MA_IS_ROT_AX (rotary axis/spindle)
- MD30310 \$MA_ROT_IS_MODULO (modulo conversion for rotary axis/spindle)
- MD30320 \$MA_DISPLAY_IS_MODULO (display modulo 360 degrees for rotary axis/spindle)

The machine axis is converted to a spindle by defining the spindle number x (with x = 1, 2, ...max. number of channel axes) in machine data

- MD35000 \$MA_SPIND_ASSIGN_TO_MACHAX (spindle number)

The spindle number must be unique within the channel axes of the channel to which the spindle is assigned.

Spindle modes

The spindle can have the following modes:

- Control mode
- Oscillation mode
- Positioning mode
- Synchronous mode, synchronous spindle

References: Function Manual, Extended Functions; Synchronous Spindle (S3)

- Tapping without compensating chuck

References: Programming Manual, Fundamentals; motion commands

- Axis operation: The spindle can be switched from spindle mode to axis mode (rotary axis) if the same motor is used for spindle and axis operation.

Basic spindle setting

The following machine data is used to specify a spindle mode as basic setting:

MD35020 \$MA_SPIND_DEFAULT_MODE

Value	Spindle basic setting
0	Speed control mode, position control deselected
1	Speed control mode, position control activated
2	Positioning mode
3	Axis mode

Time when the basic position of the spindle becomes effective

The time when the basic setting of the spindle takes effect is set in the machine data:

MD35030 \$MA_SPIND_DEFAULT_ACT_MASK

Value	Effective time
0	POWER ON
1	POWER ON and program start
2	POWER ON and RESET (M2 / M30)

14.3.2 Spindle modes

Functionality

If for certain machining tasks, e.g. on lathes with end-face machining, it is not sufficient to traverse the spindle exclusively under speed control via M3, M4, M5 or to position with SPOS, M19 or SPOSA, the spindle can be switched to position-controlled axis mode and traversed as a rotary axis.

Examples of rotary axis functions:

- Programming with axis name
- Zero offsets (G54, G55, TRANS, etc.)

- G90, G91, IC, AC, DC, ACP, ACN
- Kinematic transformations (e.g. TRANSMIT)
- Path interpolation
- Traversing as positioning axis

References: Function Manual, Extended Functions; Section "Rotary axes (R2)"

Preconditions

- The same spindle motor is used for spindle mode and axis mode.
- The same position measurement system or separate position measurement systems can be used for spindle mode and axis mode.
- An actual position value encoder is a mandatory requirement for axis mode.
- For axis operation, the spindle must be referenced, e.g. with G74.

Example:

Program code	Comment
M70	; Switch spindle over to axis mode
G74 C1=0 Z100	; Reference axis
G0 C180 X50	; Traverse axis position-controlled

Configurable M function

The M function used to switch the spindle to axis mode can be configured channel-specifically via the following machine data:

MD20094 \$MC_SPIND_RIGID_TAPPING_M_NR

Note

The controller detects the transition to axis mode automatically from the program sequence. The explicit programming of the configured M function for switching the spindle to axis mode in the part program is therefore not necessary. However, the M function can continue to be programmed, e.g. to increase the readability of the part program.

Special features

- The feed override switch is active.
- The NC/PLC interface signal does not terminate the axis mode per default:
DB21, ... DBX7.7 (reset).
- The NC/PLC interface signals:
DB31, ... DBB16 to DBB19 and DBB82 to DBB91
are not important if:
DB31, ... DBX60.0 (axis / no spindle) = 0

- Axis mode can be activated in all gear steps.

If the actual position value encoder is installed on the motor (indirect measuring system), the positioning and contouring accuracy can vary for the different gear steps.

- The gear step cannot be changed when the axis mode is active.

The spindle must be switched to control mode.

This is done with M41 ... M45 and M5, SPCOF.

- In the axis mode, the first parameter set is effective (machine data index = zero).

References: Function Manual, Basic Functions; Chapter "Velocities, setpoint / actual value systems, closed-loop control (G2)" > "Closed-loop control" > "Parameter sets of the position controller"

Dynamic response

In axis mode, the dynamic limits of the axis apply, e.g.:

- MD32000 \$MA_MAX_AX_VELO[<axis>] (maximum axis velocity)
- MD32300 \$MA_MAX_AX_ACCEL[<axis>] (maximum axis acceleration)
- MD32431 \$MA_MAX_AX_JERK[<axis>] (maximum axial jerk for path motion)

Feedforward control

The feedforward control mode active for the axis is retained.

A detailed description of the "Dynamic feedforward control" function can be found in:

References: Function Manual, Extended Functions; Chapter "Compensations (K3)" > "Dynamic feedforward control (following error compensation)"

Example: Resolution switchover for analog actuator

Switching to axis mode

Programming	Comment
SPOS=...	
M5	; Controller enable off (by PLC) → is output on PLC
M70	; Switch actuator (by PLC on account of M70) Controller enable on (by PLC)
C=...	; NC traverses with axis parameter set

Switching to spindle mode

Programming	Comment
C=...	
M71	; → is output to PLC Closed-loop controller enable off (by PLC) Switch actuator (by PLC) Switched to spindle parameter set (1-5) internally in the NC, controller enable on (by PLC)
M3/4/5 or SPOS=...	; NC traverses with spindle parameter set

Change to spindle mode

The appropriate parameter set 1...5 is selected for the active gear stage.

The feedforward control is activated, except for tapping with compensating chuck, if the following applies:

MD32620 \$MA_FFW_MODE (feedforward control mode) ≠ 0

Parameter set	Axis mode	Spindle mode
1	Valid	-
2	-	Valid
3	-	Valid
4	-	Valid
5	-	Valid
6	-	Valid

Spindle mode: Parameter set according to the gear stage

Master spindle

In the following machine data, a master spindle has been defined in the relevant channel:

- MD20090 \$MC_SPIND_DEF_MASTER_SPIND (master spindle initial setting in channel)

The spindle number of the channel spindle which is to be the master spindle defined in machine data MD35000 \$MC_SPIND_ASSIGN_TO_MACHAX (spindle number) is entered in this machine data.

Diverse spindle functions can be used in one channel, e.g.:

- Revolutionary feed (G95)
- Tapping with compensation chuck (G63)
- Thread cutting (G33)
- Dwell time in spindle revolutions (G4 S...)

Spindle reset

The following machine data is used to define whether the spindle should remain active after a reset (DB21,... DBX7.7) or end of program (M02/M30):

- MD 35040 \$MC_SPIND_ACTIVE_AFTER_RESET (spindle active after reset)

To cancel spindle movements, an independent spindle reset is required:

- DB31,... DBX2.2 (spindle reset)

References

Function Manual, Basic Functions; Spindles (S1)

14.4 Configure PROFIBUS components

Configuration of the PROFIBUS machine control panel

The following is required in the HW Config for a PROFIBUS machine control panel on the HMI:

- Configuration of the properties of the network interface for PROFIBUS
- Supplementation of the machine control panel and hand wheel in HW Config
- Modification of the machine control panel in OP100

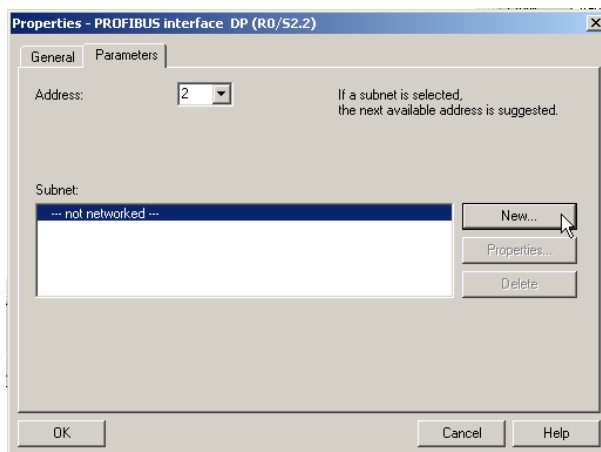
14.4.1 Configure network interface for PROFIBUS

Introduction

In the STEP7 project, you configure the network interfaces PROFIBUS DP, via which you want to reach the machine control panel:

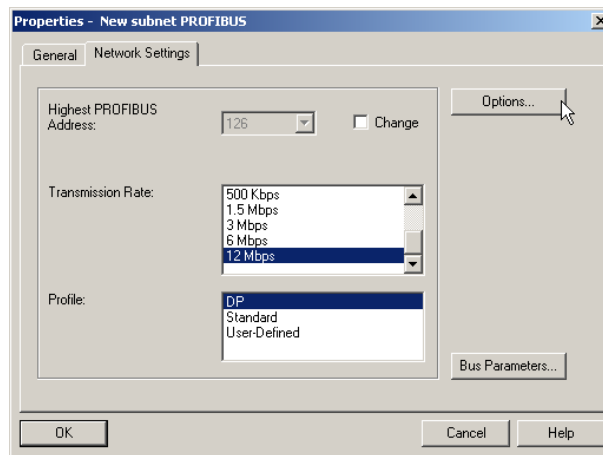
PROFIBUS DP operating sequence

1. Use the left mouse button to select NCU 720.1 and while holding down the mouse button drag it to the "Station design" station window.
2. After you release the mouse button, configure the properties of the PROFIBUS DP interface for socket X126 (machine control panel) in the dialog box.

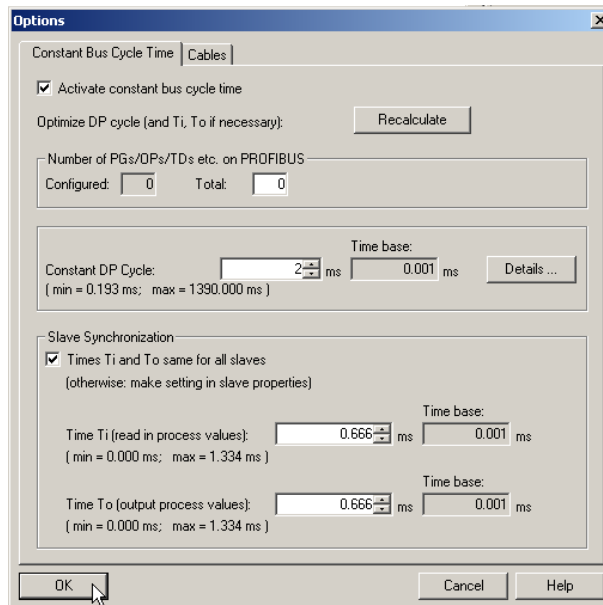


3. Click the following successively:
 - The "New..." button,
 - The "Network settings" tab in the "Properties new subnet PROFIBUS Subnet" dialog box.

4. Select the transmission speed of "12 Mbit/s" for the "DP" profile.



5. Click "Options" and then the "Isochronous mode" tab.

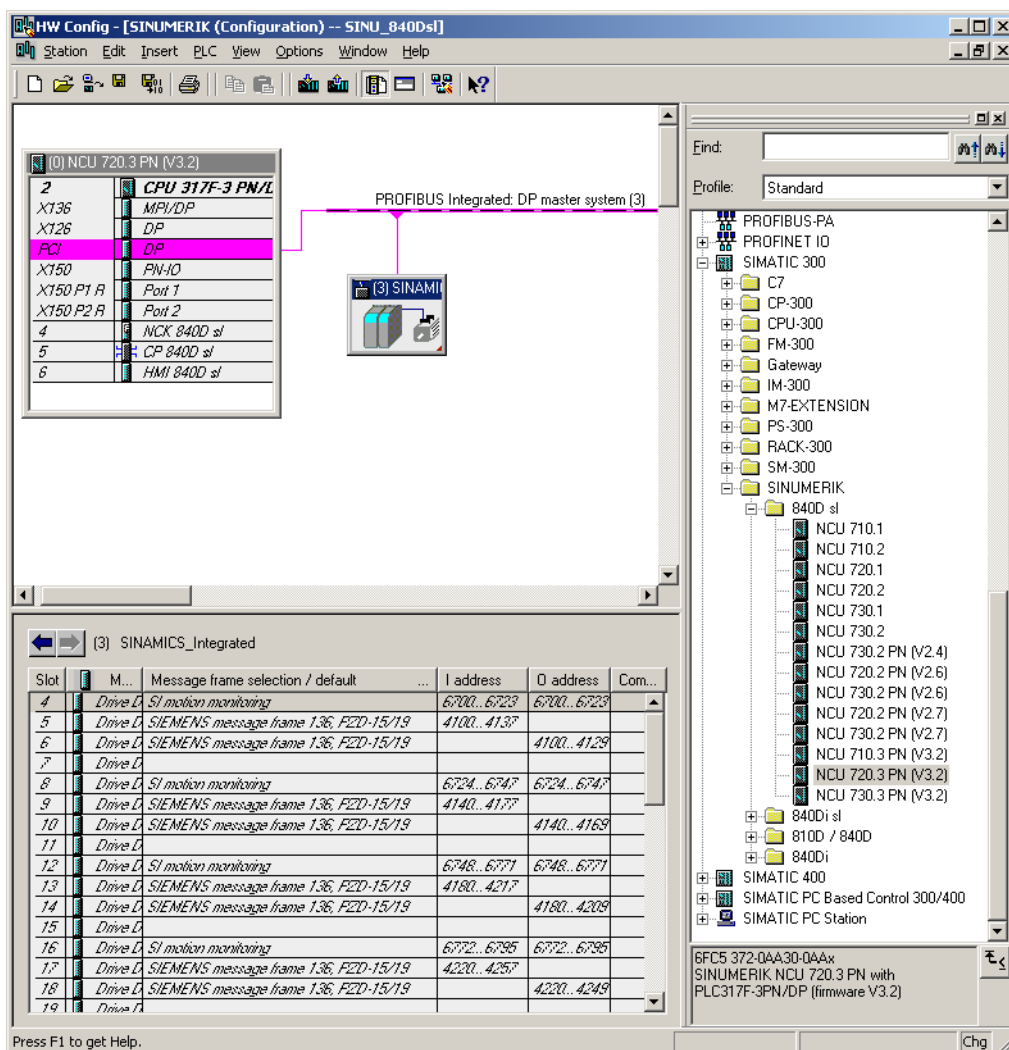


6. To enable reproducible access to peripherals (for handwheel mode), the PROFIBUS DP must have a constant bus cycle time. The following entries are necessary under Equidistance:
 - Click on the "Activate equidistance bus cycle" field.
 - Enter the cycle, e.g. "2 ms" for the "Equidistance DP cycle" (for integrated PROFIBUS) (see MD10050 \$MN_SYSOCK_CYCLE_TIME).
 - Click the "Times Ti and To equal for all slaves" field.
 - The fields "Time Ti" and "Time To" must contain a value "< 2 ms".

7. Click "OK" three times.
8. The NCU module with SINAMICS S120 is inserted in the HW Config.

Note

With the <F4> key and confirmation of the prompt regarding "Reorganize", you can reorganize the display in the station window.



As the next step configure a machine control panel with handwheel.

14.4.2 Load GSD file (contains machine control panel)

Introduction

To expand the machine control panel, you need the device master data (GSD file) with the SINUMERIK MCP. This file contains information that a DP master system requires to link the MCP as DP slave in its PROFIBUS configuration.

Operating sequence

The file is a component of the STEP 7 package for NCU7x0 (Toolbox).

1. Search in the HW config under "Extras" > "Install GSD file..." in the installation directory of the toolbox for the corresponding GSD directory under:
 `..\8x0d\GSD\MCP_310_483`
2. Choose the corresponding language you want to install.
3. Select "Install".
4. Exit with "Close".

14.4.3 Adding a machine control panel and handwheel in HW Config

Introduction

The machine control panel (MCP) can be connected via PROFIBUS to the PLC. In later configurations, this will also be possible over the network.

Operating sequence for adding an MCP in HW Config

You have created a NCU and a NX in the HW Config and installed the GSD file for the MCP.

1. Search under "PROFIBUS DP" > "Further field devices" > "NC/RC" > "MOTION CONTROL" for the "SINUMERIK MCP" module.
2. Click with the left mouse button to select the "SINUMERIK MCP" module and drag it to the chain for the "PROFIBUS DP master system" in the "Station design" station window.
3. After releasing the mouse button, the machine control panel is added (see figure below).
4. Select "MCP" and enter the PROFIBUS address 6 under "Object properties" > button "PROFIBUS..." > tab "Parameter" > input field "Address".

5. Click on "OK" twice.

Now you can assign the slots of the machine control panel, e.g., "Standard + Hand wheel".

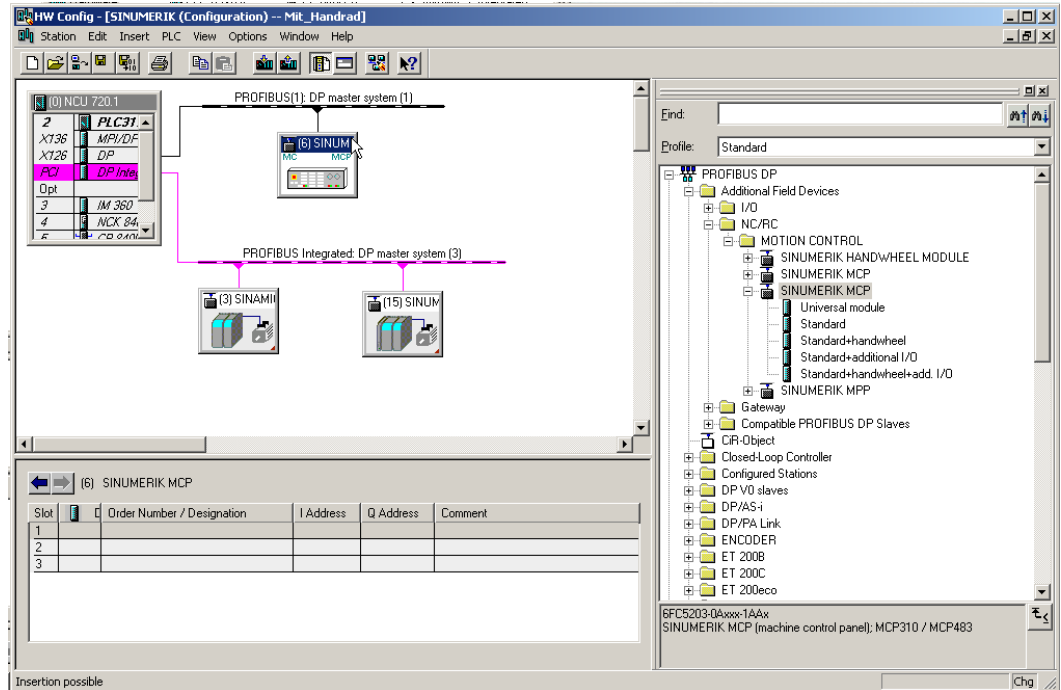


Figure 14-7 Machine control panel in HW Config

14.4 Configure PROFIBUS components

6. In the hardware catalog under "SINUMERIK MCP" click with the left mouse button to select the "Standard+Hand wheel" option and drag it to Slot 1 (see figure below).

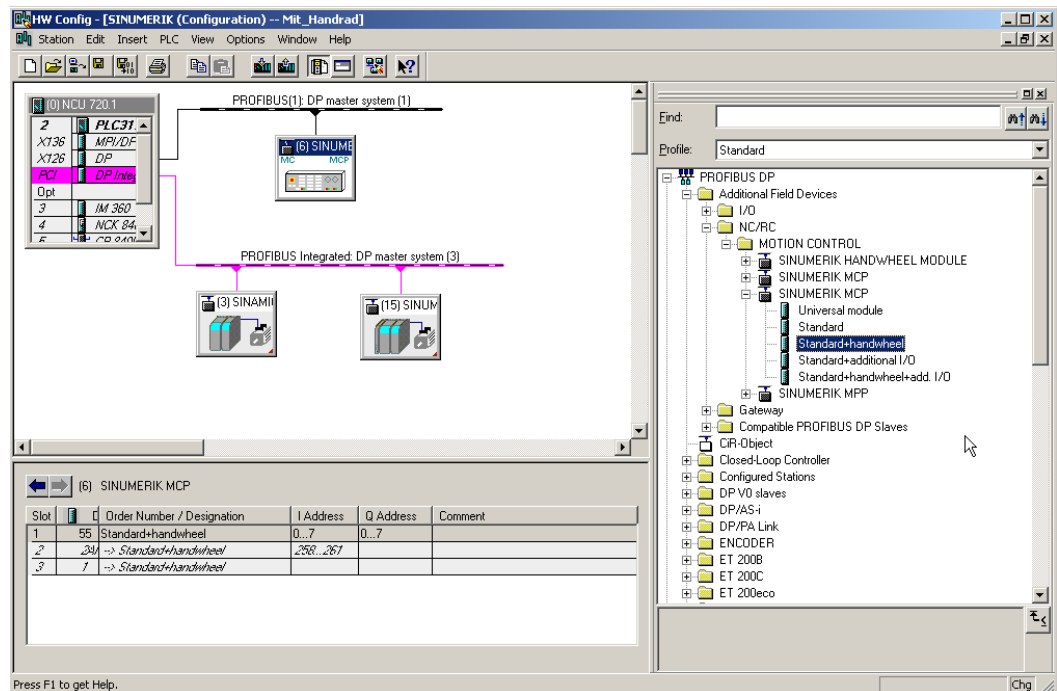


Figure 14-8 Standard+Handwheel for slot

You have configured a machine control panel with handwheel in HW Config.

Note

If a handwheel has been configured, equidistance is required. You set this when you configured the PROFIBUS DP. PROFIBUS address for the machine control panel is "6".

Save, compile and load the configuration to the PLC as the next operating sequence.

14.4.4 Modifying PROFIBUS machine control panel in OB100

Introduction

The PLC base program transfers the signals from the machine control panel. To ensure that the signals are transferred correctly to and from the machine control panel, enter the following parameters in the OB100 on the FB1.

Double-click OB100 the editor to configure the machine control panel below "Blocks".

Example: MCP1 is connected via PROFIBUS DP.

Another example for the connection of the machine control panel via Industrial Ethernet (IE) can be found at:

Modifying machine control panel in OB100 (Page 52)

Configuring the machine control panel

```

OB100
CALL "RUN_UP" , "gp_par"      FB1 / DB7 -- Startup Baseprogram/ Parameters for
Baseprogram

MCPNum :=1                    // An MCP is present

MCP1In :=P#E 0.0
MCP1Out :=P#A 0.0
MCP1StatSend :=P#A 8.0
MCP1StatRec :=
MCP1BusAdr :=6                // PROFIBUS DP address: 6
MCP1Timeout :=
MCP1Cycl :=
MCP2In :=
MCP2Out :=
MCP2StatSend :=
MCP2StatRec :=
MCP2BusAdr :=
MCP2Timeout :=
MCP2Cycl :=
MCPMPFI :=FALSE
MCP1Stop :=FALSE
MCP2Stop :=
MCP1NotSend :=FALSE
MCP2NotSend :=
MCPsDB210 :=
MCPCopyDB77 :=
MCPBusType :=B#16#03          // Parameter [3] := PROFIBUS DP

BHG :=
BHGIN :=

```

14.4 Configure PROFIBUS components

OB100

```
BHGOnt :=  
  
...  
  
UDInt :=  
UDHex :=  
UDReal :=  
IdentMcpType :=  
IdentMcpLengthIn :=  
IdentMcpLengthOut:=  
//Insert User program from here  
...
```

References

You can find additional information about the connection of components:
Function Manual, Basic Functions (P3), Section "Structure and functions of the base program"

Appendix

A.1 Information about third-party software used

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QLocale's data is based on Common Locale Data Repository v1.6.1.

Note

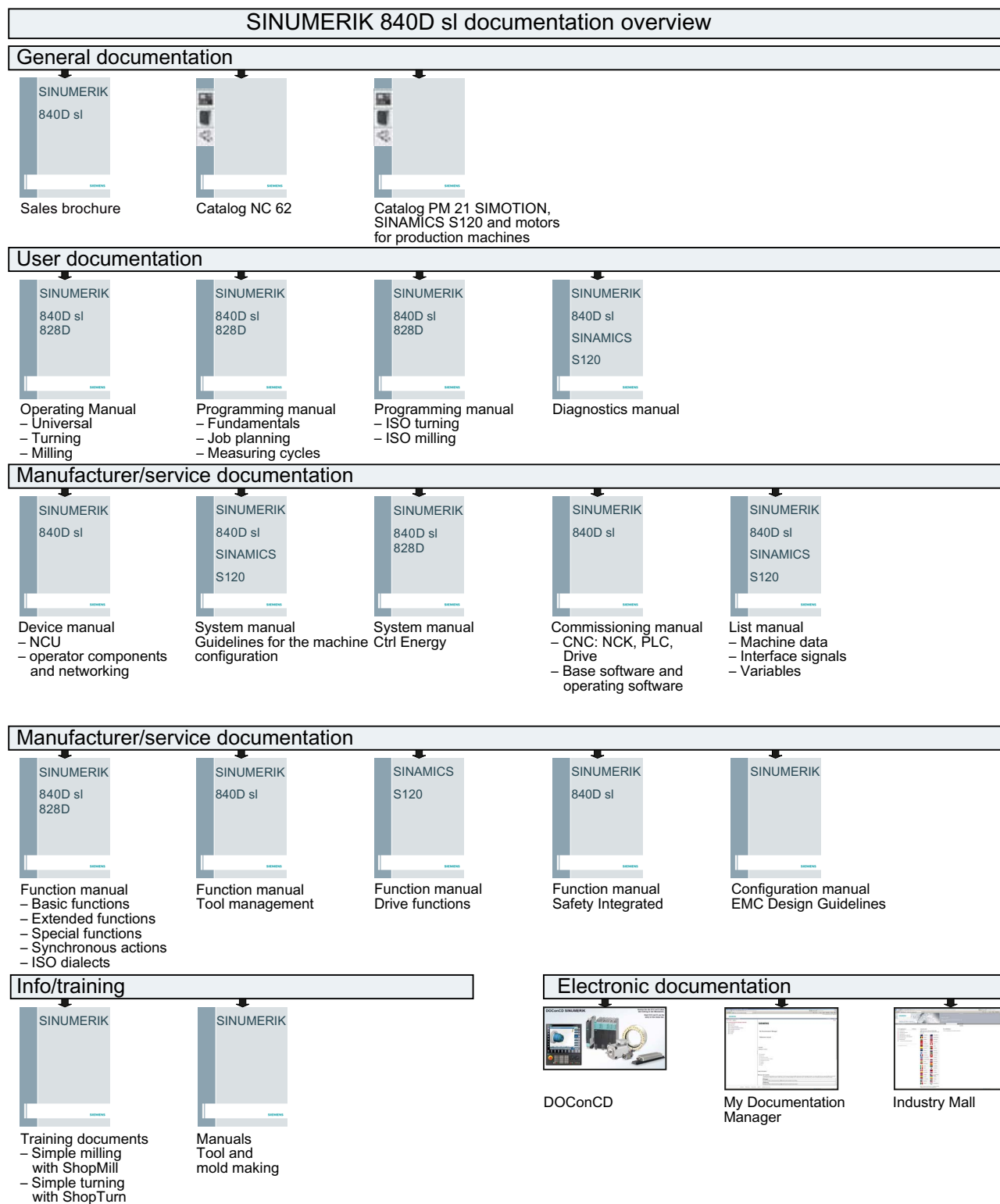
You can find additional information on the product DVD in the Readme_OSS file about the third-party software used.

A.2 Abbreviations

ACX	Compressed format from XML
ALM	Active Line Module
BASP	Command output disable
BERO	Proximity limit switch
BI	Binector Input
BICO	Binector Connector
BO	Binector Output
CF	CompactFlash
CI	Connector Input
CNC	Computerized Numerical Control
CO	Connector Output
CoL	Certificate of License
CP	Communications Processor
CPU	Central Processing Unit
CU	Control Unit
DHCP	Dynamic Host Configuration Protocol: Protocol for automatic assignment of IP addresses from a DHCP server to a client computer
DIP	Dual In-Line Package: dual in-line arrangement
DO	Drive objects
DP	Distributed Peripherals
DRAM	Dynamic Random Access Memory
DRF	Differential resolver function: differential-synchro transmitter function
DRIVE-CLiQ	Drive Component Link with IQ
DSC	Dynamic Servo Control
DWORD	Doubleword
EMC	Electro-Magnetic Compatibility
EN	European standard
EPOS	Basic positioning
ESD	Electrostatic Sensitive Device
GC	Global Control
GSD	Device master file
GUD	Global User Data
GWPS	Grinding wheel peripheral speed
IPO	Interpolator cycle
IS	Interface Signal
JOG	JOG mode: manual mode for setting up the machine
LAN	Local Area Network
LED	Light Emitting Diode
LR	Position controller
LUD	Local User Data
MAC	Media Access Control

MCP	Machine Control Panel
MD	Machine data
MLFB	Machine-readable product designation
MM	Motor Module
MSGW	Message word
NC	Numerical Control: Numerical control with block preparation, traversing range, etc.
NCU	Numerical Control Unit: The NC hardware unit
NX	Numerical Extension (axis extension module)
OB	Organization Block
OLP	Optical Link Plug
PCU	PC Unit: computer unit
PD	Process Data
PELV	Protective Extra-Low Voltage
PG	Programming device
PII	Process Input Image
PIO	Process Output Image
PLC	Programmable Logic Control (component of the CNC controller)
PM	Power Module
PNO	PROFIBUS User Organization
PUD	Global Program User Data
RAM	Random Access Memory (can be read and written)
RDY	Ready
REF	Reference point
RES	Reset
RTCP	Real Time Control Protocol
SBC	Safe brake activation
SD	Setting Data
SH	Safe standstill
SIM	Single Inline Module
SLM	Smart Line Module
SMC	Sensor Module Cabinet-Mounted
SME	Sensor Module Externally Mounted
SMI	Sensor Module Integrated
STW	Status Word
TCU	Thin Client Unit
USB	Universal Serial Bus

A.3 Overview



Glossary

Active Line Module

Controlled, self-commutating feed/feedback unit (with -> "IGBTs" in feed/feedback direction), which supplies the DC-link voltage for the -> "Motor Module".

Certificate of License (CoL)

The CoL is the proof of the → license. The product may only be used by the holder of the → license or authorized persons. The CoL includes the following data relevant for the license management:

- Product name
- → License number
- Delivery note number
- → Hardware serial number

CompactFlash card

As the carrier of all non-volatile data in a SINUMERIK solution line control system, the CompactFlash card represents the identity of this control system. The CompactFlash card is a memory card that can be plugged into the → control unit from outside. The CompactFlash card also contains the following data relevant for the license management:

- → Hardware serial number
- License information including the → license key

Control Unit

Central control module in which the closed-loop and open-loop control functions for one or more -> "SINAMICS" -> "Line Modules" and/or -> "Motor Modules" are implemented.

There are three types of Control Unit:

- SINAMICS Control Units, e.g. -> "CU320"
- SIMOTION Control Units, e.g. -> "D425" and -> "D435"
- SINUMERIK solution line Control Units, e.g. NCU710, NCU720 and NCU730

Control Word

Bit-coded ->"Process data" word, transmitted by -> "PROFIdrive" at cyclic intervals to control the drive states.

Double Motor Module

Two motors can be connected to and operated with a Double Motor Module.
See → "Motor Module" → "Single Motor Module"
Former term: → "Double-Axis Module"

Drive

The drive includes the motor (electric or hydraulic), the actuator (converter, valve), the control unit, the measuring system, and supply components (line infeed module, pressure reservoir).

For electric drives, a distinction is made between a converter system and an inverter system. With a converter system (e.g. → "MICROMASTER 4"), from the user's point of view the line infeed, the actuator, and the control component form a single device; with an inverter system (e.g. → "SINAMICS S"), the supply is ensured by means of → "Line Module", thereby realizing a DC line to which the → "Invertors" (→ "Motor Modules") are connected. The (→ "Control Unit") is implemented as a separate device and connected to the other components by means of → "DRIVE-CLiQ".

Drive Component

Hardware component connected to a → "Control Unit" via → "DRIVE-CLiQ", for example. Drive units are for instance: → "Motor Modules", → "Line Modules", → "Motors", → "Sensor Modules" and → "Terminal Modules".
The overall layout of a Control Unit together with the connected drive components is called → "Drive unit".

Drive Group

A drive group comprises a → "Control Unit" and the → "Motor Modules" and → "Line Modules" connected via → "DRIVE-CLiQ".

Drive Object

A drive object is an autonomous, individual software function with its own → "Parameters" and may also have its own → "Faults" and → "Alarms". Drive objects may exist by default (e.g. On-board I/O), can be created individually (e.g. → "Terminal Board" 30, TB30) or also as multiples (e.g. → "Servo Control"). As a rule, each drive object has its own window for parameterization and diagnostic purposes.

Drive Parameters

Parameters of a drive axis that include, for example, the parameters of the corresponding controllers, as well as the motor and encoder data. The parameters of the higher-level technology functions (positioning, ramp-function generator), however, are called → "Application Parameters".
See → "Basic Unit System".

Drive System

A drive system includes all the components in a product family, e.g. SINAMICS. A drive system comprises, e.g. -> "Line Modules", -> "Motor Modules", -> "Sensors", -> "Motors", -> "Terminal Modules" and -> "Sensor Modules" as well as additional components (reactors, filters, cables, etc.).
See -> "Drive Unit"

Drive Unit

The drive unit includes all the components connected via -> "DRIVE-CLiQ" that are required for carrying out a drive task: -> "Motor Module" -> "Control Unit" -> "Line Module" and the required -> "Firmware" and -> "Motor"s, but not additional components, such as filters or reactors.
Several -> "Drives" can be implemented in a drive unit.
See -> "Drive System".

DRIVE-CLiQ

Abbreviation of "Drive Component Link with IQ".
Communication system for connecting the different components of a SINAMICS drive system, e.g. -> "Control Unit", -> "Line Modules", -> "Motor Modules", -> "Motors", and speed/position sensors.
The DRIVE-CLiQ hardware is based on the Industrial Ethernet standard with twisted-pair lines. The DRIVE-CLiQ line provides the send and receive signals, as well as the +24 V power supply.

DRIVE-CLiQ Hub Module Cabinet

The DRIVE-CLiQ Hub Module Cabinet (DMC) is a star coupler for multiplying -> "DRIVE-CLiQ sockets. The DMC can be clipped onto a rail. The DMC20 is available, for example.
See -> "Hub"

Encoders

An encoder is a measuring system that captures actual values for the speed and/or angular/position values and makes them available for electronic processing. Depending on the mechanical construction, encoders can be integrated in the -> "Motor" (-> "Motor Encoder") or mounted on the external mechanics (-> "External Encoder"). Depending on the type of motion, a distinction is made between rotary encoders ("Rotary Transducers") and translatable encoders (e.g. -> Linear Encoders). In terms of measured value provision, a distinction is made between -> "Absolute Encoders" (Code Encoders) and -> "Incremental Encoders".
See -> "Incremental Encoder TTL/HTL" -> "Incremental Encoder sin/cos 1 Vpp" -> "Resolver".

External Encoder

Position encoder that is not built in or mounted on the → "Motor", but fitted instead via a mechanical transmission element or mechanical intermediate element.
The external encoder (see → "Externally-Mounted Sensor") is used for → "Direct Position Detection".

Hardware

In the context of license management of SINUMERIK → software products, hardware refers to the component of a SINUMERIK control system to which → licenses are assigned on the basis of its unique identifier. The license information is also saved to non-volatile memory on this component, e.g. on a → CompactFlash card.

Hardware serial number

The hardware serial number is a permanent part of the → CompactFlash card. It is used to identify a control system uniquely. The hardware serial number can be determined by:

- → Certificate of License
- User interface
- Label on the CompactFlash card

Hub

A central connection device in a network with star-shaped topology. A hub distributes incoming data packages to all connected end devices.

See → "DRIVE-CLiQ Hub Module Cabinet" (DMCxx)

Infeed

Input component of a converter system for generating a DC-link voltage to supply one or more → "Motor Modules", including all the required components, e.g. → "Line Modules", fuses, reactors, line filters, and firmware, as well as proportional computing power (if required) in a → "Control Unit".

License

A license gives the user the legal right to use a → software product. Evidence of this right is provided by the following:

- → Certificate of License (CoL)
- → License key

License key

The License Key is the "technical representative" of the sum of all the → licenses that are assigned to one particular piece of → hardware, which is uniquely marked by its → hardware serial number.

License number

The license number is the feature of a → license used for its unique identification.

Line Module

A Line Module is a power component that generates the DC-link voltage for one or more → "Motor Modules" from a 3-phase mains voltage.

In SINAMICS, the following three types of Line Module are available:

→ "Basic Line Module", → "Smart Line Module" and → "Active Line Module".

The overall function of an infeed, including the required additional components like → "Line Reactor", proportional computing power in a → "Control Unit", switching devices, etc., is called → "Basic Infeed", → "Smart Infeed", and → "Active Infeed".

Modular machine

The modular machine concept is based on a maximum target topology created offline. The maximum design of a particular machine type is referred to as the maximum configuration in which all the machine components that may be used are pre-configured in the target topology. By deactivating/deleting drive objects (p0105 = 2), sections of the maximum configuration can be removed.

If a component fails, the sub-topology can also be used to allow a machine to continue running until the spare part is available. In this case, however, no BICO source must be interconnected from this drive object to other drive objects.

NOTICE
Data backup
To prevent data loss, save the drive data in a commissioning archive, before you make any changes!

Motor

For the electric motors that can be driven by → "SINAMICS", a basic distinction is made between rotary and linear motors with regard to their direction of motion, and between synchronous and induction motors with regard to their electromagnetic operating principle. In SINAMICS, the motors are connected to a → "Motor Module".

See → "Synchronous Motor" → "Induction Motor" → "Built-In Motor" → "Motor Encoder" → "External Encoder" → "Third-Party Motor".

Motor Encoder

An → "Encoder" (e.g. → "Resolver", → "Incremental Encoder TTL/HTL", or → "Incremental Encoder sin/cos 1 Vpp" that is integrated in or attached to the motor.

The encoder detects the motor speed. In the case of synchronous motors, it can also detect the rotor position angle (the commutation angle for the motor currents).

For drives without an additional → "Direct Position Measuring System", it is also used as a → "Position Encoder" for position control.

In addition to the motor encoders, → "External Encoders" for → "Direct Position Sensing" are available.

Motor module

A Motor Module is a power component (DC-AC inverter) that supplies the power for the connected motor(s).

Power is supplied through the → "DC Link" of the → "Drive Unit".

A Motor Module must be connected to a → "Control Unit" via → "DRIVE-CLiQ". The open-loop and closed-loop control functions for the Motor Module are stored in the Control Unit.

→ "Single Motor Modules" and → "Double Motor Modules" are available.

Option

One option is a SINUMERIK → software product that is not contained in the basic version and which requires the purchase of a → license for its use.

Option Slot

Slot for an optional module (e.g. in the → "Control Unit").

Parameters

Variable quantity within the drive system that the user can read and, in some cases, write.

For → "SINAMICS", all specifications defined in the → "PROFIdrive" profile are defined by a parameter.

See → "Visualization Parameters" and → "Adjustable Parameters".

Product

A product is marked by the data below within the license management of SINUMERIK

→ software products:

- Product designation
- Order number:
- → License number

PROFIBUS

Field bus according to IEC 61158, Sections 2 to 6.

The abbreviation "DP" is no longer included because PROFIBUS FMS is not standardized and PROFIBUS PA (for Process Automation) is now part of the "general" → "PROFIBUS".

Sensor Module

Hardware module for evaluating speed/position encoder signals and providing detected actual values as numerical values at a → DRIVE-CLiQ Socket".

Three mechanical Sensor Module variants are available:

- SMCxx = Sensor Module Cabinet Mounted
- SME = Sensor Module Externally Mounted (with a high degree of protection)

Servo Control

For → Motors equipped with a → "Motor encoder", this control type allows operation with a high level of → "Accuracy" and → "Dynamic response". In addition to speed control, position control can be included.

Servo Drive

An electric servo drive comprises a motor, a → "Motor Module", a → "Servo Control" and, in most cases, a speed and position → "Encoder".

Electric servo drives are normally extremely precise and have a high dynamic response. They are designed for cycle times less than 100 ms, and often have a short-time overload capacity which enables quick acceleration. Servo drives are available as rotary and linear drives and are used for machine tools, handling robots, and packaging machines.

SITOP power

Component for the → "Electronic power supply". Example: 24 VDC

Smart Line Module

Unregulated line infeed / feedback unit with a diode bridge for the infeed and stall-protected, line-commutated feedback via → "IGBTs".

The Smart Line Module supplies the DC-link voltage for the → "Motor Modules".

Software product

The term software product is generally used to describe a product that is installed on a piece of → hardware to process data. Within the license management of SINUMERIK software products, a corresponding → license is required to use each software product.

Status Word

Bit-coded -> "Process data" word, transmitted by -> "PROFIdrive" at cyclic intervals to control the drive states.

Vector Control

Vector control (field-oriented control) is a high-performance control type for induction machines. It is based on an exact model calculation of the motor and two current components that simulate and accurately control the flux and torque by means of software algorithms. As a consequence, the entered speeds and torques can be precisely maintained and limited with a good dynamic performance.

The vector control is available in two variants:

The frequency control (-> "Sensorless vector control") and the speed-torque control with speed feedback (-> "Encoder").

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