SIEMENS

SIMOTION

SIMOTION D4x5

Commissioning and Hardware Installation Manual

Preface

Description	1
Use planning	2
Installing	3
Connection	4
Commissioning (hardware)	5
Parameter assignment / addressing	6
Commissioning (software)	7
Service and maintenance	8
Diagnostics	9
Configuration of drive-related I/Os (without symbolic assignment)	A
Standards and approvals	В
ESD guidelines	С

Valid for SIMOTION D425, D435 and D445/D445-1 as well as the CX32, CBE30 and TB30 supplementary system components

Legal information

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.

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.

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

CAUTION

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

NOTICE

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

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

Qualified Personnel

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

Proper use of Siemens products

Note the following:

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 adhered to. The information in the relevant documentation must be observed.

Trademarks

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

Disclaimer of Liability

We have 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.

Siemens AG Industry Sector Postfach 48 48 90026 NÜRNBERG GERMANY Copyright © Siemens AG 2010. Technical data subject to change

Preface

Contents of this commissioning and hardware installation Manual

This document is part of the SIMOTION D documentation package.

Scope

The SIMOTION D4x5 Commissioning and Hardware Installation Manual is valid for the SIMOTION D425, SIMOTION D435, SIMOTION D445/D445-1, and CX32 devices. A separate SIMOTION D4x5-2 Commissioning and Hardware Installation Manual is available for the SIMOTION D4x5-2 devices including the CX32-2 and TB30 system components.

Standards

The SIMOTION system was developed in accordance with ISO 9001 quality guidelines.

Information in this manual

The following is a description of the purpose and use of this Commissioning and Hardware Installation Manual:

Description

Provides information about the SIMOTION system and its integration in the automation environment.

Use planning

Provides information on the transport, storage, and environmental conditions.

Installation

Provides information on the various installation options for the device.

Connection

Provides information about connecting and cabling the various devices, and about communications interfaces.

Commissioning (hardware)

Provides information on commissioning the device.

Parameter assignment / addressing

Provides information on configuring and parameterizing the various bus systems.

• Commissioning (software)

Provides information on configuring and commissioning the system.

• Maintenance and servicing

Provides information about service and maintenance procedures that must be performed on the device.

Diagnostics

Provides information about the available diagnostic information, how to interpret it, and its meaning.

Appendices with factual information for reference (e.g. standards, approvals and ESD guidelines).

SIMOTION Documentation

An overview of the SIMOTION documentation can be found in a separate list of references.

This documentation is included as electronic documentation in the scope of delivery of SIMOTION SCOUT. It comprises 10 documentation packages.

The following documentation packages are available for SIMOTION V4.2:

- SIMOTION Engineering System
- SIMOTION System and Function Descriptions
- SIMOTION Service and Diagnostics
- SIMOTION IT
- SIMOTION Programming
- SIMOTION Programming References
- SIMOTION C
- SIMOTION P
- SIMOTION D
- SIMOTION Supplementary Documentation

Hotline and Internet addresses

Additional information

Click the following link to find information on the the following topics:

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

http://www.siemens.com/motioncontrol/docu

Please send any questions about the technical documentation (e.g. suggestions for improvement, corrections) to the following e-mail address: docu.motioncontrol@siemens.com

My Documentation Manager

Click the following link for information on how to compile documentation individually on the basis of Siemens content and how to adapt this for the purpose of your own machine documentation:

http://www.siemens.com/mdm

Training

Click the following link for information on SITRAIN - Siemens training courses for automation products, systems and solutions:

http://www.siemens.com/sitrain

FAQs

You can find Frequently Asked Questions on the Service&Support pages under **Product Support**:

http://support.automation.siemens.com

Technical support

Country-specific telephone numbers for technical support are provided on the Internet under **Contact**:

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

Disposal and recycling of the device

SIMOTION D is an environmentally friendly product. It includes the following features:

- In spite of its excellent resistance to fire, the flame-resistant agent in the plastic used for the housing does not contain halogens.
- Identification of plastic materials in accordance with DIN 54840.
- Less material used because the unit is smaller and with fewer components thanks to integration in ASICs.

The disposal of the products described in this manual should be performed in compliance with the valid national regulations.

The products can be largely recycled owing to their low pollutant content. To recycle and dispose of your old device in an environmentally friendly way, please contact a recycling company certified for electronic waste.

If you have any further questions about disposal and recycling, please contact your local Siemens representative. Contact details can be found in our contacts database on the Internet at:

http://www.automation.siemens.com/partner/index.asp

Further information / FAQs

You can find further information on this manual under the following FAQs:

http://support.automation.siemens.com/WW/view/de/27585482

You can also find additional information under:

- SIMOTION Utilities & Applications: SIMOTION Utilities & Applications will be included in the SIMOTION SCOUT scope of delivery and, along with FAQs, also contain free utilities (e.g. calculation tools, optimization tools, etc.) as well as application examples (ready-toapply solutions such as winders, cross cutters or handling).
- The latest SIMOTION FAQs at http://support.automation.siemens.com/WW/view/en/10805436/133000
- SIMOTION SCOUT online help
- Refer to the list of references (separate document) for additional documentation

Table of contents

	Prefac	e	3
1	Descri	ption	13
	1.1	System overview	13
	1.2	System components	17
	1.3	I/O integration	
	1.4	Commissioning software	23
	1.5	Safety notes	24
2	Use pl	anning	
	2.1	Shipping and storage conditions	
	2.2	Mechanical and climatic ambient conditions	
	23	Information on insulation tests, safety class, and degree of protection	29
3	Installi	na	
Ŭ	3 1	Installation notes	31
	3.2		
	2.2	Side mounting of SIMOTION D4x5 on SIMAMICS accomply	
	5.5	Mounting of Simo Fion D4x5 of SinAmics assembly	
	3.4 3.4.1	Mounting SIMOTION D4x5 on the wall of the control cabinet	35 35
	3.4.2	Mounting SIMOTION D425, D435, and D445-1 without spacers	
	3.5	Installing supplementary system components	
	3.5.1	Installing the TB30	38
	3.5.2	Installing the CBE30	
	3.5.3	Installing the CX32	40
	3.5.4	Removing the cover of the CX32	45
4	Conne		
	4.1	Complete overview (example)	47
	4.2	Safety information for wiring	49
	4.3	Opening the front cover	50
	4.4	Power supply	51
	4.4.1	Safety rules	51
	4.4.2	Standards and Regulations	
	4.4.3 4 4 4	Connecting the power supply	52 53
	 Л Б	Connecting DRIVE-CLiO components	
	4.5.1	DRIVE-CLiQ wiring	
	4.5.2	Connectable DRIVE-CLiQ components	

	4.5.3	Connecting CX32	. 58
	4.6	Connecting inputs/outputs.	62
	4.6.1	Creating a shield connection	63
	4.6.2	Connecting inputs/outputs of the TB30	64
	4.7	Connecting PROFIBUS/MPI	66
	4.7.1	PROFIBUS connection components	66
	4.7.2	PROFIBUS cables and connectors	67
	4.7.3	PROFIBUS cable lengths	67
	4.7.4	Rules for the laying of PROFIBUS cables	68
	4.7.5	Connecting PROFIBUS DP (interfaces X126 and X136)	68
	4.7.6	Connection rules in the PROFIBUS subnet	69
	4.7.7	Operating the X136 interface as MPI	71
	4.8	Connecting PROFINET IO components	73
	4.8.1	Wiring PROFINET	73
	4.8.2	PROFINET cable	74
	4.9	Routing	76
	4.9.1	Routing on SIMOTION D	76
	4.9.2	Routing on SIMOTION D (SINAMICS integrated)	79
	4.10	Connecting Ethernet	80
	4.10.1	Wiring Ethernet	80
	4.10.2	Ethernet cables and connectors	80
5	Commis	sioning (hardware)	. 83
	5.1	Requirements for commissioning	83
	5.1.1	Inserting the CompactFlash card	83
	5.1.2	Checking the system	85
	5.1.3	Switching on the power supply	85
	5.2	RESET button	87
	5.3	User memory concept	88
	5.3.1	SIMOTION D4x5 memory model	88
	5.3.2	Properties of the user memory	89
	5.3.3	Operations and their effect on the user memory	93
	5.4	Fan	100
	5.4.1	Cooling the SIMOTION D4x5	100
	5.4.2	Fan/battery module on the D425/D435	101
	5.4.3	Fan/battery module on the D445/D445-1	101
	5.4.4	Overview of states, fan/battery module	103
	5.4.5	Response to overtemperature	105
6	Parameter assignment / addressing		107
	6.1	Software requirements	107
	6.2	Creating a project and configuring communication	107
	6.2.1	Creating a SIMOTION project and inserting a D4x5	107
	6.2.2	Configuring the PROFIBUS PG/PC interface	110
	6.2.3	Configuring the Ethernet PG/PC interface	111
	6.2.4	Representation of SIMOTION D4x5 in HW Config	113
	6.3	Configuring PROFIBUS DP	114

6.3.1	General information about communication via PROFIBUS DP	
6.3.2	Operating SIMUTION D4x5 on PROFIBUS DP.	115
634	Setting the DP cycle and system cycle clocks	/۱۱ 118
635	Cycle clock scaling of external PROFIBUS interface to internal PROFIBUS interface	110
636	Creating a new PROFIBUS subnet	113
637	Modifying the data transmission rate	
6.3.8	Establishing a PG/PC assignment	
0.0.0		
6.4	Configuring an Ethernet subnet	
6.4.1	Configuring an MPI bus	124
0.4.1.1	MPL parameters	124
642	Properties of the Ethernet interfaces	124 125
643	Configuring Ethernet addresses in HW Config	123 127
644	Reading out IP and MAC address	127 128
6.5		
6.5.1	General information about communication via PROFINET IO	
6.5.2	Setting a send cycle clock and a system cycle clock	
0.0.3		133
0.5.4	Configuration tasks	134
Commis	sioning (software)	135
7.1	Overview of commissioning	
7.1.1	Symbolic assignment / adaptation	
7.1.2	Procedure when commissioning	139
7.1.3	Important functions for the project handling during commissioning	140
7 2	Performing offline configuration for the D4x5	1/1
7.2		141
722	Accessing the drive wizard	
7.2.3	Configuring components	
7.2.4	Downloading a project into the target system	
7.2.5	Downloading a project to the CF card	
7.2.6	Loading a project, including sources and additional data	164
7.2.7	Archiving a project to the CompactFlash Card (zip file)	165
73	Performing online configuration for D4x5	166
7.3.1	Overview	
7.3.2	Establish an online connection	
7.3.3	Starting the automatic configuration	
7.3.4	Editing SINAMICS components	172
7.3.5	Downloading a project to SIMOTION D4x5	172
74	Configuring a CX32	174
7.4.1	Overview	
7.4.2	Basic principles of the CX32	
7.4.3	Preparing for configuration	176
7.4.4	Displaying the topology	179
7.4.5	Performing CX32 configuration offline	180
7.4.5.1	Loading a project created offline to the target system	181
7.4.5.2	Loading a project created offline to the CF card	182
7.4.6	Performing CX32 configuration online	183
7.4.7	CX32 contiguration instructions	184

7

7.4.7.1	CX32 power-up	184
7.4.7.2	Interconnecting the infeed "Operation" signal on the CX32	185
7.4.7.3	CX32 diagnostics	187
7.4.7.4	Upgrading D4x5/CX32	188
7.4.7.5	Replacing D4x5/CX32.	189
7.5	Additional information on configuring the SINAMICS Integrated	190
7.5.1	Settings for DP slave properties	190
7.5.2	Using vector drives	191
7.5.3	Setting the time of day	194
7.5.4	SINAMICS diagnostic buffer	197
7.5.5	Acyclic communication with the drive	197
7.5.6	Control properties and performance features	198
7.5.7	Current controller cycle clocks <> 125 µs / use of output cams and measuring inputs	199
7.6	Testing a drive with the drive control panel	200
7.7	Creating and testing axes	203
7.7.1	Overview of SIMOTION engineering	203
7.7.2	Creating an axis with the axis wizard	204
7.7.3	Testing the axis with the axis control panel	211
7.8	Activating the infeed (line module)	213
7.8.1	Infeed without DRIVE-CLiQ connection	214
7.8.2	Infeeds with DRIVE-CLiQ connection	214
7.9	Setting up addresses and message frames	216
7.9.1	Setting up communication for symbolic assignment	216
7.9.2	Message frame configuration	216
7.10	Linking an additional encoder (optional)	219
7.10.1	Fundamentals	219
7.10.2	Additional encoders on the drive	220
7.10.3	Additional encoders via PROFIBUS/PROFINET	221
7.11	Symbolic assignment of I/O variables (PROFIdrive message frame / drive parameters)	222
7.11.1	Symbolic assignment of I/O variables to the PROFIdrive message frame of the TO axis	222
7.11.2	Symbolic assignment of I/O variables to drive parameters	222
7.12	Configuration of drive-related I/Os (with symbolic assignment)	226
7.12.1	Configuration of the I/O terminals	227
7.12.1.1	Configuration of the D4x5 I/Os (terminal X122/X132)	228
7.12.1.2	Configuration of the CX32/CU3xx/TB30/TMxx I/O terminals	229
7.13	Configuration of the technology objects and I/O variables	230
7.13.1	Configuration of global measuring inputs	230
7.13.2	Configuration of local measuring inputs	231
7.13.3	Configuration of output cams / cam tracks	231
7.13.4	Configuration of the I/Os (variables / TO axis)	234
7.14	DMC20/DME20 DRIVE-CLiQ hub	235
7.14.1	Hub properties	235
7.14.2	Creating a DMC20/DME20 DRIVE-CLiQ hub	236
7.15	TM41 Terminal Module	236
7.15.1	Overview	236
7.15.2	Configuring TM41 at SINAMICS Integrated	237
7.15.3	Configuring TM41 using the Axis Wizard	238

	7.16 7.16.1	Optimizing drive and closed-loop controller	238
	7.10.1	Automatic speed controller setting	230
	7.16.3	Automatic position controller setting	200
	7 16 4	Measuring functions trace and function generator	242
	7.16.5	Manual speed controller optimization	
	7.17	Downloading and storing user data	247
	7.18	Deleting data	249
	7.18.1	Overview of data deletion	249
	7.18.2	Overall reset of SIMOTION D4x5	249
	7.18.3	Deleting user data from CF card	252
	7.18.4	Restoring the default settings of SINAMICS Integrated	253
	7.18.5	Setting SIMOTION D4x5 to the default settings	253
	7.19	Powering down the system	254
	7.20	Configuring Safety Integrated functions	254
	7.21	Migration D445 to D445-1	259
	7.21.1	Overview	259
	7.21.2	Configuration	260
	7.21.3	Compatibility	260
8	Service	and maintenance	263
	8.1	Overview	263
	8.2	Replacing modules (spare part scenario)	
	8.2.1	Parts replacement for SIMOTION D4x5	
	8.2.2	Removal and replacement of the SIMOTION D4x5	268
	8.2.3	Replacing DRIVE-CLiQ components	269
	8.2.4	Replacing the CompactFlash Card	272
	8.3	Adapting a project (Updating the project / Replacing the SIMOTION controller)	272
	8.3.1	Overview	272
	8.3.2	Creating backup copies (project/CF)	273
	8.3.3	Backing up user data (backup variables)	273
	8.3.4	Upgrading a user project to the new SCOUT version	275
	8.3.5	Platform replacement via XML export/import	
	8.3.6	Preparing the device replacement	
	8.3.7	Device replacement in HW Config	
	8.3.8	Upgrading technology packages.	
	8.3.9	Upgrading the device version of SINAMICS S120 control units	
	8.3.10 8.3.11	Opgrading a library	283 284
	0.4		004
	0.4 0.4 1	Performing a firmware and project update	284 204
	0.4.1 010	Upgrauling the Compactriash Card's boot loader	2ŏ4 ⊃o⊑
	0.4.Z Q / 2	Update via IT DIAG	ססכ ססב
	0.4.J 8 / /	Ungrade via H DIAG	00∠ אפר
	0.4.4 8 / 5	Ungrade via CE card	00∠ 201
	8451	Backup of the CF card data	201 201
	8452	Firmware upgrade via CF card	292
	8.4.5.3	Upgrading SINAMICS	

	8.4.5.4	Loading a project to the target system	294
	8.5	SIMOTION Compact Flash card	295
	8.5.1	Changing the CompactFlash Card	295
	8.5.2	Writing to the the CompactFlash card	296
	8.5.3	Formatting the CompactFlash card	
	8.5.4	Bootloader on the CompactFlash card	
	8.5.5 8.5.6	Card reader for CF cards	
9	Diagnost	tics	299
	9.1	Diagnostics via LED displays	299
	9.1.1	SIMOTION D4x5 and SINAMICS Integrated displays	
	9.1.2	LED displays of the PROFINET interface	306
	9.1.3	LED displays of the Ethernet interface	307
	9.1.4	LED displays of the CX32 controller extension	308
	9.1.4.1	Behavior of the LEDs during booting of the CX32	308
	9.1.4.2	Behavior of the LEDs after booting of the CX32	309
	9.2	Diagnostic data and non-volatile data	310
	9.2.1	Overview	
	9.2.2	Backing up diagnostic data and non-volatile data	
	9.2.2.1	Diagnostic data	
	9.2.2.2	Procedure for backing up during operation	
	9.2.2.3	Procedure for backing up during startup	
	9.2.2.5	Storing data	
	9.2.3	Diagnostics via websites	
	9.2.4	Deleting/restoring non-volatile data	317
	9.2.5	Backing up diagnostic data and non-volatile data using IT DIAG	318
	9.3	Additional service and diagnostics options	320
	9.3.1	SIMOTION Task Profiler application	320
	9.3.2	Diagnostics using IT DIAG	321
Α	Configur	ation of drive-related I/Os (without symbolic assignment)	323
	A.1	Local and global measuring inputs	323
	A.2	Configuring local measuring inputs	325
В	Standard	ds and approvals	327
	B.1	General rules	327
	B.2	Safety of electronic controllers	329
С	ESD gui	delines	331
	C.1	ESD definition	331
	C.2	Electrostatic charging of individuals	332
	C.3	Basic measures for protection against discharge of static electricity	333
	Index		335

Description

1

1.1 System overview

Overview

SIMOTION D is a drive-based version of SIMOTION based on the SINAMICS S120 drive family.

With SIMOTION D, the SIMOTION PLC and motion control functionalities as well as the SINAMICS S120 drive software run on shared control hardware.

SIMOTION D is available in two versions:

- SIMOTION D410 is a compact control unit for single-axis applications and is snapped on to the SINAMICS S120 PM340 power module in blocksize format.
- SIMOTION D4x5 is a control unit for multi-axis applications in SINAMICS S120 booksize format and is offered in several performance variants:
 - SIMOTION D425 (BASIC performance) for up to 16 axes
 - SIMOTION D435 (STANDARD performance) for up to 32 axes
 - SIMOTION D445/D445-1 (HIGH Performance) for up to 64 axes Compared with SIMOTION D445, SIMOTION D445-1 offers an improvement in PLC and motion control performance of approximately 30%, depending on the application. Consequently, SIMOTION D445-1 is the preferred solution for new applications as of V4.1 SP2.

This manual describes the SIMOTION D4x5 for multi-axis applications. Separate manuals are available for the SIMOTION D410 single-axis module as well as for the SIMOTION D4x5-2 multi-axis modules.

Like SINAMICS S120, SIMOTION D also follows the Totally Integrated Automation (TIA) concept. TIA is characterized by integrated data management, configuration, and communication for all products and systems. Thus, an extensive toolbox of automation modules is also available for SIMOTION D.

Note

In order to cover all versions of SIMOTION D for multi-axis applications, the product will be referred to as "D4x5". Specific product designations will be used for information that applies only to one product version, e.g. D435.

Description

1.1 System overview

Application

SIMOTION D4x5 is ideally suited to applications with many coordinated axes with high clockpulse rates.

Typical applications include:

- Compact multiple-axis machines
- · High-performance applications with short machine cycles
- Compact machines
 - Including the complete machine control in the drive
 - With extensive connection possibilities for communication, HMI and I/O
- Distributed drive concepts
 - Applications with many axes
 - Synchronization of several SIMOTION D control units using distributed synchronous operation

Versions

The individual versions - SIMOTION D425 (BASIC Performance), SIMOTION D435 (STANDARD Performance) and SIMOTION D445/D445-1 (HIGH Performance) - differ in terms of their PLC performance and motion control performance. The main distinguishing features are:

	SIMOTION D425	SIMOTION D435	SIMOTION D445/D445-1
Maximum number of axes	16	32	64
Minimum servo/interpolator cycle clock	2.0 ms	1.0 ms	0.5 ms
DRIVE-CLiQ interfaces	4	4	6

SIMOTION D4x5 features PLC and motion control performance (open-loop control and motion control) for up to 16, 32 or 64 axes, as required.

Due to the following functional improvements, we recommend using a SIMOTION D445-1 instead of a SIMOTION D445 for new applications as of V4.1 SP2:

- An increase of around 30% in PLC and motion control performance, depending on the application
- Less mounting depth (mounting is possible even without spacers)
- Double-fan/battery module for higher availability
- Further information (http://support.automation.siemens.com/WW/view/en/31507782)

The computing functions integrated into the drive allow the D4x5 control unit to operate up to six servo, four vector or eight V/f axes.

The drive control supports servo control (for a highly dynamic response), vector control (for maximum torque accuracy) and V/f control.

Note

With the SIZER configuration tool, you can easily configure the SINAMICS S120 drive family including SIMOTION.

It provides you with support for selecting and dimensioning the components required for a motion control task.

You can also determine the possible number of axes and the resulting load with SIZER in accordance with your performance requirements.

Hardware components

As the central hardware, SIMOTION D uses the SIMOTION D4x5 as a control unit consisting of the SIMOTION runtime system and the SINAMICS drive control. The control unit uses the SINAMICS Integrated drive with various SINAMICS S120 drive modules (line and motor modules) to perform open-loop and closed-loop control of the axis grouping. A range of additional SINAMICS S120 components, such as SMx encoder systems or terminal modules can be connected via DRIVE-CLiQ. With a few exceptions (e.g. no basic positioner EPOS, no basic operator panel BOP20, etc.), the drive control integrated in SIMOTION D has the same control characteristics and performance features as the SINAMICS S120 CU320 control unit. The EPOS functionality is provided by the SIMOTION technology functions. The functionality of SIMOTION D can be expanded with the distributed I/O via PROFIBUS or with the CBE30 Ethernet communication board via PROFINET IO. The following figure shows a typical SIMOTION D axis grouping.



Figure 1-1 Example of a SIMOTION D4x5 axis assembly

1.1 System overview

A SIMOTION D axis grouping generally consists of the following elements:

• SIMOTION D (control unit) (1)

This unit contains the programmable runtime system of SIMOTION and the drive software of SINAMICS S120. In principle, SIMOTION D is capable of controlling multiple axes/drives.

• One SINAMICS infeed (line module) (2)

This module generates a DC link from the supply system.

• SINAMICS power units (motor modules) (3)

These modules are used to control motors.

It is also possible to operate SINAMICS PM340 power modules with the SINAMICS control unit adapter (CUA). A separate infeed is then unnecessary.

• DRIVE-CLiQ components (4)

In SINAMICS S120 / SIMOTION D, the individual components of the drive system communicate with each other via DRIVE-CLiQ. In addition to power components, encoder systems and special DRIVE-CLiQ I/O devices can also be linked via DRIVE-CLiQ.

Extension of the drive computing performance

The motion control performance of a SIMOTION D4x5 can be utilized in full by expanding the computing performance at the drive in two different ways:

- SINAMICS S110/S120 control units complete with further SINAMICS S110/120 drive modules can be connected via PROFIBUS or PROFINET.
- With SIMOTION D435 and D445/D445-1, the CX32 controller extension can be connected via DRIVE-CLiQ. This module is extremely compact and can control up to six servo, four vector or eight *V*/f axes.

Software components

The basic functionality of SIMOTION D is supplied on a CompactFlash card containing the following:

The SIMOTION runtime system with the following functions:

- Freely programmable runtime system (IEC 61131)
- Various runtime levels (tasks)
- PLC and arithmetic functionality
- Motion control functions
- Communication functions

The SINAMICS S120 drive control with the following functions:

- Closed-loop current and torque control
- Closed-loop speed control
- Regulated infeed

1.2 System components

Central components

SIMOTION D4x5 communicates with automation components via the following interfaces:

- PROFIBUS DP
- Ethernet
- PROFINET IO (when using a CBE30)
- DRIVE-CLiQ (DRIVE Component Link with IQ).

SIMOTION D features a SINAMICS Integrated drive element. Communication with the SINAMICS Integrated is via PROFIBUS mechanisms (DP Integrated).

The most important components of the system and their functions are shown below.

Component	Function	
SIMOTION D4x5 controller	is the central motion control module. This module contains the programmable SIMOTION runtime for the SIMOTION D4x5 and the SINAMICS S120 drive software. You can use the integrated high-speed digital I/Os as:	
	Homing inputs	
	Inputs for measuring inputs	
	User-addressable process inputs/outputs	
	Outputs for fast output cams	
	The measuring sockets can output any analog signals.	
System software	The basic functionality of SIMOTION D is supplied on a CompactFlash card containing the following:	
	SIMOTION runtime (kernel)	
	Drive software of SINAMICS S120 - implements all drive functions	
Power supply	provides the electronic power supply for SIMOTION D, e.g. via the SITOP power supply.	

1.2 System components

PROFIBUS DP

The control unit can communicate with the following components via the PROFIBUS DP interfaces:

Component	Function	
Programming device (PG/PC)	configures, parameterizes, programs, and tests with the "SIMOTION SCOUT" engineering system (ES)	
SIMATIC HMI device	is used for operating and monitoring functions. This is not an essential requirement for the operation of a control unit.	
Other controllers (e.g. SIMOTION or SIMATIC)	e.g. higher-level controller (plant controller); modular machine concepts with multiple controls, distributed across individual machine modules	
Distributed I/O systems		
SIMATIC ET 200M	Modular I/O system for control cabinet installation and high channel density	
SIMATIC ET 200S	Finely scalable I/O system for control cabinet configuration and particularly time-critical applications; including motor starters, safety technology and individual grouping of load groups	
SIMATIC ET 200pro	Modular I/O system with IP65/67 degree of protection for machine- related applications with no control cabinet; with features such as compact designs, integrated PROFIsafe safety technology, PROFINET connection and live module replacement.	
SIMATIC ET 200eco	I/O system with IP65/67 degree of protection for cabinet-free use close to the machine with flexible and fast ECOFAST or M12 connection methods	
Other PROFIBUS I/O		
Gateways	DP/AS-Interface link 20E and DP/AS-Interface link Advanced for the PROFIBUS DP gateway to AS-Interface	
	DP/DP coupler for connecting two PROFIBUS DP networks	
Drive interfaces	 ADI4 (Analog Drive Interface for 4 axes) for connection of drives with analog ± 10 V setpoint interface or for external encoders IM174 (Interface Module for 4 axes) for connection of drives with analog ± 10 V setpoint interface, for external sensors, or for connection of stepper drives with pulse-direction interface 	
Drive units with PROFIBUS DP interface (e.g. SINAMICS S120)	convert speed setpoints into signals for controlling the motor and supply the power required to operate the motors. Also can be operated as an isochronous slave on PROFIBUS DP.	
Teleservice adapter	Remote diagnostics	

Table 1-2 Components on PROFIBUS DP

Ethernet

The control unit can communicate with the following components via the Ethernet interfaces or be embedded in an automation environment:

Table 1- 3	Components on	the Ethernet

Component	Function configures, parameterizes, programs, and tests with the "SIMOTION SCOUT" engineering system (ES)	
Programming device (PG/PC)		
Master computer	communicates with other devices via UDP, TCP/IP	
SIMATIC HMI device	is used for operating and monitoring functions. This is not an essential requirement for the operation of a control unit.	

PROFINET IO

The use of a Communication Board Ethernet (CBE30) enables SIMOTION D4x5 to communicate with the following components via PROFINET IO:

Component	Function	
Programming device (PG/PC)	configures, sets parameters, programs and tests using the "SIMOTION SCOUT" Engineering System (ES).	
SIMATIC HMI device	is used for operating and monitoring functions. This is not an essential requirement for the operation of a control unit.	
Other controllers (e.g. SIMOTION or SIMATIC)	e.g. higher-level controller (plant controller); modular machine concepts with multiple controls, distributed across individual machine modules	
Master computer	communicates with other devices via UDP, TCP/IP.	
Distributed I/O systems		
SIMATIC ET 200M	Modular I/O system for control cabinet installation and high channel densities.	
SIMATIC ET 200S	Finely scalable I/O system for control cabinet installation and particularly time-critical applications; including motor starters, safety technology and individual grouping of load groups.	
SIMATIC ET 200pro	Modular I/O system with IP65/67 degree of protection for machine- related applications with no control cabinet; with features such as compact designs, integrated PROFIsafe safety technology, PROFINET IO connection and live module replacement.	
SIMATIC ET 200eco PN	Compact block I/O with IP65/66/67 degree of protection for cabinet-free usage in machines with M12 connection method. Very rugged and resistant encapsulated metal enclosure.	
Other PROFINET IO I/O devices		
Drive units with PROFINET IO interface	convert speed setpoints into signals for controlling the motor and supply the power required to operate the motors.	
Gateways	IE/AS-Interface link PN IO for the PROFINET IO gateway to AS-Interface	
	PN/PN coupler for connecting two PROFINET IO networks	

Table 1-4 Components on the PROFINET IO

Description

1.2 System components

DRIVE-CLiQ

The DRIVE-CLiQ interfaces permit a fast connection to the SINAMICS drive components.

DRIVE-CLiQ offers the following advantages within the DRIVE-CLiQ topology rules:

- Expandability of components
- Automatic detection of components by the control unit
- Standardized interfaces to all components
- Uniform diagnostics down to the components
- Complete service down to the components
- Simple mechanical handling

The controller can communicate with the following components via DRIVE-CLiQ:

Component	Function	
Control unit (SINAMICS S110/S120)	Central control module in which the open- and closed-loop control functions for the drive are implemented.	
Line module (SINAMICS S120)	generates a DC link from the supply system.	
Motor module (SINAMICS S120)	used to control motors (DC/AC inverters, booksize).	
Power module (SINAMICS S110/S120)	used to control motors (AC/DC converters, blocksize).	
CX32 controller extension	enables additional axes to be connected for SIMOTION D435 and D445/D445-1.	
CUA31/CUA32 control unit adapter	enables a blocksize power module (PM340) to be connected to a booksize control unit D4x5, CX32 or CU320.	
TM31 terminal module	enables a terminal expansion via DRIVE-CLiQ (additional analog and digital I/Os).	
TM41 terminal module	enables a terminal expansion (analog and digital I/Os) and encoder simulation.	
TM54F terminal module	enables terminal expansion (secure digital inputs/outputs) for controlling the secure motion monitoring functions of the integrated drives.	
TM15, TM17 High Feature terminal module	The terminal modules TM15 and TM17 High Feature are used to implement inputs of measuring inputs and outputs of cam outputs. In addition, these terminal modules provide drive-related digital inputs and outputs with short signal delay times.	
SMx sensor modules	enable acquisition of encoder data from connected motors via DRIVE-CLiQ.	
Motors with DRIVE-CLiQ interface	allow simplified commissioning and diagnostics, as the motor and encoder type are identified automatically.	
DMC20/DME20 DRIVE-CLiQ hub	enables the number of DRIVE-CLiQ interfaces to be increased and the creation of a star-shaped topology.	

Table 1-5 Components connected to DRIVE-CLiQ

Note

You can find detailed information about components in the SINAMICS S110/S120 family of products in the SINAMICS S110/S120 manuals.

Optional components

The functionality of the D4x5 control unit can be expanded by using one of the components listed below.

Table 1-6 Optional components

Component	Function
Communication Board Ethernet CBE30	Communication via PROFINET IO with IRT and PROFINET IO with RT
Terminal Board TB30	Terminal expansion, i.e. additional analog and digital I/Os

The selected component is plugged into the option slot of the control unit.

1.3 I/O integration

1.3 I/O integration

Note

Note that not all modules in the ET 200 I/O family are approved for SIMOTION. Moreover, system-related functional differences can come into play when these I/O or I/O systems are used on SIMOTION vs. on SIMATIC. For example, special process-control functions (e.g., HART modules, etc.) are not supported by SIMOTION for the ET 200M distributed I/O system.

A detailed, regularly updated list of the I/O modules approved for use with SIMOTION, as well as notes on their use, can be found on the Internet at (http://support.automation.siemens.com/WW/view/en/11886029):

In addition to the I/O modules enabled for SIMOTION, in principle all certified standard PROFIBUS slaves (DP-V0/DP-V1/DP-V2) and PROFINET IO devices with RT and IRT realtime classes may be connected to SIMOTION D4x5. These modules are integrated using the GSD file (PROFIBUS) or GSDML file (PROFINET) provided by the relevant device manufacturer.

Note

Please note that in individual cases further boundary conditions must be fulfilled in order to integrate a standard slave/standard device into SIMOTION. Thus, a few modules require "driver blocks", e.g., in the form of function blocks, that permit (or simplify) integration.

For modules enabled for SIMOTION (e.g. SIMATIC S7-300 module FM 350-1, etc.), these driver modules are part of the SIMOTION SCOUT Engineering System command library.

1.4 Commissioning software

Requirement

To create and edit projects on your PG/PC, you need the SIMOTION SCOUT commissioning and configuration tool. For information on how to install SIMOTION SCOUT, refer to the *SIMOTION SCOUT* Configuration Manual.

Note

SIMOTION SCOUT contains the functionality of STARTER and SIMATIC S7-Technology.

Simultaneous operation of SIMOTION SCOUT, STARTER and SIMATIC S7-Technology as a single installation on one PC/PG is not possible.

Integrated starter

You can insert a standalone drive (e.g. SINAMICS S120) with the "Insert single drive unit" element in the project navigator. It is commissioned using wizards in the working area of the workbench that contains the STARTER functionality.

SINAMICS Support Package (SSP)

You can use a SINAMICS Support Package (SSP) to upgrade the version of the drive units on a STARTER integrated into SIMOTION SCOUT.

This permits the use of new functions which only become available with new drive unit FW versions.

In this regard, the following SSPs are relevant for SIMOTION SCOUT:

- "SINAMICS" SSP for upgrading single drive units (e.g. CU3xx)
- "SIMOTION SINAMICS Integrated" SSP for upgrading the SINAMICS drives integrated into SIMOTION D.

Detailed installation instructions appear in the Readme files supplied with each each SSP.

Upgrade SIMOTION D4x5 projects and hardware

Projects that you have created for one SIMOTION D4x5 firmware version can also be converted for other firmware versions. Furthermore, you can amend the version of SIMOTION D4x5. For example, a D425 can be converted to a D435 (and vice versa, insofar as the performance and quantity structure allow this). For further information, see Section Adapting a project (Updating the project / Replacing the SIMOTION controller) (Page 272). 1.5 Safety notes

IT DIAG

The SIMOTION D4x5 features an integrated web server.

The web server supports the display of diagnostics and system data in standard Internet browsers, even in the absence of an engineering system, and the carrying out of project/firmware updates.

As of firmware version V4.2, it is no longer necessary to purchase licenses for SIMOTION IT DIAG and SIMOTION IT OPC XML-DA.

Additional references

For detailed information on working with projects, refer to the *SIMOTION SCOUT* Configuration Manual.

For detailed information about IT DIAG, see the *SIMOTION IT Ethernet-based HMI and Diagnostic Functions* Diagnostics Manual.

1.5 Safety notes

Note the following safety information when working with the control unit and its components.

NOTICE

The 80 mm clearances above and below the components must be observed. The unit protects itself from overheating by shutting down.

An option board may only be inserted and removed when the control unit and option board are disconnected from the power supply.

The Compact Flash card may only be inserted or removed when the control unit is disconnected from the power supply.

The SIMOTION D4x5 is in a de-energized state when all the LEDs are OFF.

Use planning

2.1 Shipping and storage conditions

Shipping and storage conditions

With regard to transportation and storage conditions, SIMOTION D4x5 surpasses the requirements specified in IEC 1131, Part 2. The following conditions apply to modules that are transported and stored in the original packaging.

Conditions

Type of condition	Permissible range	
Free fall	≤ 1 m	
Temperature	From -40° C to +70° C	
Atmospheric pressure Air pressure in mbar (kPa):		
	> 700 mbar (70 kPa)	
	< 1060 mbar (106 kPa)	
	The specified values correspond to a transport or storage altitude of up to 3,000 m.	
Relative humidity	5% to 95%, without condensation	

Table 2- 1	Shipping and storage conditions

Shipping backup batteries

If possible, ship the backup batteries in the original packaging. No special measures are required to ship backup batteries used for SIMOTION D. The lithium content of the backup battery is less than 0.5 g.

2.2 Mechanical and climatic ambient conditions

Storage of backup batteries

Always store backup batteries in a cool and dry place. The batteries have a maximum shelf life of 10 years.

∕!∖warning

Risk of injury, material damage, release of hazardous substances.

Do not throw new or discharged batteries into a fire and do not solder the cell body (max. temperature 100° C) and also do not recharge the batteries - there is an explosion hazard!

Do not open a battery. Replace a faulty battery only with the same type.

Only use a replacement from Siemens (for order number, see manual).

Always try to return old batteries to the manufacturer or deliver these to a registered recycling company.

Note

If you have a spare parts inventory, you must not store a SIMOTION D4x5 with the fan/battery module mounted. Only connect the fan/battery module if the fan or battery backup voltage is required.

2.2 Mechanical and climatic ambient conditions

Conditions of use

SIMOTION D4x5 is designed for use in stationary, weather-protected locations. The operating conditions surpass the IEC 1131-2 requirements.

SIMOTION D4x5 satisfies the operating conditions for Class 3C3 in accordance with DIN EN 607213-3 (operating locations with high traffic densities and in the immediate vicinity of industrial equipment with chemical emissions).

Use prohibition

Without additional measures, SIMOTION D4x5 may not be used in

- Locations with a high percentage of ionizing radiation
- Locations with extreme operating conditions, e.g.
 - Dust accumulation
 - Corrosive vapors or gases
- In systems, which require special monitoring, e.g.
 - Elevator installations
 - Electrical installations in highly sensitive areas

2.2 Mechanical and climatic ambient conditions

An additional measure for using SIMOTION D4x5 can, for example, be installation in cabinets.

Mechanical ambient conditions

SIMOTION D4x5 meets the following standards for mechanical stress:

- Vibrational load: DIN EN 60721-3-3, Class 3M4
- Shock load: DIN EN 60721-3-3, Class 3M4
- Free fall: DIN EN 60721-3-2, Class 2M1 and Class 2M2
- Toppling: DIN EN 60721-3-2, Class 2M1

The mechanical ambient conditions for SIMOTION D4x5 are listed in the following table in the form of sinusoidal vibrations.

Table 2- 2Mechanical ambient conditions

Frequency range (Hz)	continuous	infrequent
10 ≤ f ≤ 58	0.0375 mm amplitude	0.075 mm amplitude
58 ≤ f ≤ 150	0.5 g constant acceleration	1 g constant acceleration

Vibration reduction

If SIMOTION D4x5 is subjected to larger shocks or vibrations, you must use suitable measures to reduce the acceleration or the amplitude.

We recommend installation on shock-absorbing material (e.g. rubber-metal vibration dampers).

Testing mechanical environmental conditions

Table 2- 3Mechanical ambient conditions

Testing	Test standard	Comments
Vibrations	Vibration testing in accordance with IEC 68 Part 2-6 (sine) severity	Type of vibration: Frequency sweeps at a rate of change of 1 octave per minute.
		10 Hz ≤ f ≤ 58 Hz, const. Amplitude 0.075 mm
	level 12	58 Hz ≤ f ≤ 500 Hz, const. acceleration 1 g
		Duration of vibration: 10 frequency cycles per axis in each of the 3 perpendicular axes
Shock	Shock testing in	Type of shock: half sine
	accordance with	Severity of shock: 15 g peak value, duration = 11 ms
	IEC 68 Part 2-27	Direction of shock: 3 shocks each in +/- direction in each of the 3 perpendicular axes

2.2 Mechanical and climatic ambient conditions

Climatic ambient conditions

SIMOTION D4x5 satisfies the climatic environmental conditions for Class 3K5 in accordance with DIN EN 60721-3-3.

SIMOTION D4X5 may not be used under the following climatic ambient conditions:

Ambient conditions	Application range	Comments
Temperature: Vertical mounting position:	From 0° C to 55° C	The fan/battery module is optional for SIMOTION D425 and D435 (Type 6AU1 435-0AA00-0AA1).
		The fan/battery module is required at supply air temperatures of 43° C and above for SIMOTION D435 (Type 6AU1 435-0AA00-0AA0, previous version).
		A fan/battery module is always required for SIMOTION D445/D445-1.
		The maximum supply air temperature for all modules is 55 °C.
Relative humidity	5% to 95%	Without condensation, corresponds to relative humidity (RH) severity level 2 in accordance with IEC 1131-2
Atmospheric pressure	700 hPa to 1060 hPa	3000 m - 0 m above mean sea level
Pollutant concentration		Test:
	SO ₂ : < 0.5 ppm; Relative humidity < 60%, no condensation	10 ppm; 4 days 1 ppm; 4 days
	H ₂ S: < 0.1 ppm; Relative humidity < 60%, no condensation	

2.3 Information on insulation tests, safety class, and degree of protection

2.3 Information on insulation tests, safety class, and degree of protection

Test voltages

During the routine test, the insulation resistance is tested at the following test voltage in accordance with IEC 1131 Part 2:

Table 2-4 Test voltages

Circuits with rated voltage Ue relative to other circuits or ground	Test voltage
0 V < Ue ≤ 50 V	500 VDC

Class of protection

Safety class I in accordance with VDE 0106, Part 1 (IEC 536), i.e. a protective-conductor terminal is required on the mounting rail.

Protection against ingress of solid foreign bodies and water

Degree of protection IP 20 in accordance with IEC 529, i.e., protection against contact with standard probes.

Also: Protection against ingress of solid foreign bodies with diameters greater than 12.5 mm.

No special protection against ingress of water.

Use planning

2.3 Information on insulation tests, safety class, and degree of protection

Installing

3.1 Installation notes

Open equipment

These modules are open equipment. This means they may only be installed in housings, cabinets, or in electrical equipment rooms that can only be entered or accessed with a key or tool. Housings, cabinets, or electrical equipment rooms may only be accessed by trained or authorized personnel. An external fire-protection housing is required.

The equipment must be deenergized when you install the control unit.

3.2 Installing the SIMOTION D4x5

Requirement

The control unit is installed in a control cabinet along with the SINAMICS components.

The following requirements must be met for installing a control unit:

- The control cabinet has been installed and wired.
- SINAMICS components should already have been installed and wired (for side mounting).
- · Components and tools are available.

Designs

The control unit is compatible with the SINAMICS S120 in booksize format. There are two possible mounting methods:

- Side mounting on the SINAMICS S120 line module
 - In this type of installation, the control unit is attached to the side panel of the line module in the control cabinet.
- Direct installation on the wall of the control cabinet

In the case of both designs, the CompactFlash Card and the option slot can be accessed from the outside. The fan/battery module can be mounted later.

Because the Control Unit is similar to the SINAMICS S120 family with regard to installation, please follow the instructions in the SINAMICS manuals.

3.2 Installing the SIMOTION D4x5

Mounting and installation aids

The Control Unit is designed for mounting in a control cabinet (IP20 degree of protection). All versions of SIMOTION D4x5 are supplied with pre-assembled spacers for installation on the wall of the control cabinet. The spacers can be removed from the SIMOTION D425, D435, and D445-1 if necessary.



Figure 3-1 Mounting aids based on the example of SIMOTION D425 and D435

3.2 Installing the SIMOTION D4x5

Mounting a SIMOTION D445

Because a SIMOTION D445 has cooling ribs for heat dissipation on its rear, the spacers provided as standard cannot be disassembled. The D445 can be mounted on the control cabinet wall using spacers or on the side of the SINAMICS assembly using mounting fixtures.

Note

SIMOTION D445 can only be operated with a fan/battery module. This module is supplied with SIMOTION D445 and has to be mounted first. A description of how to install the fan/battery module can be found in the *SIMOTION D4x5* Manual (Chapter "Spare parts/Accessories", Section "Installing the fan/battery module").

See also

Side-mounting of SIMOTION D4x5 on SINAMICS assembly (Page 34) Mounting the SIMOTION D4x5 with spacers (Page 35) Mounting SIMOTION D425, D435, and D445-1 without spacers (Page 37) 3.3 Side-mounting of SIMOTION D4x5 on SINAMICS assembly

3.3 Side-mounting of SIMOTION D4x5 on SINAMICS assembly

The SIMOTION D425, D435, and D445 Control Units can be mounted on the side wall of a SINAMICS S120 Line Module. The mounting fixtures required for this are supplied with the SINAMICS S120 Line Module.

Note

Assembly on the side of the SINAMICS S120 Line Module using 5 mounting fixtures is not possible with SIMOTION D445-1.

SIMOTION D445-1 must always be screwed to the control cabinet wall.

The SINAMICS S120 Line Module has five mounting fixtures on the left side. To mount the control unit, proceed as follows:

- 1. Attach the Control Unit to the left side of the SINAMICS S120 Line Module. The mounting fixtures fit exactly in the five cutouts on the module.
- 2. Push the two units together.
- 3. Press down on the module until the unit engages and is securely connected to the SINAMICS S120 Line Module.



The module is connected flush with the SINAMICS assembly on top and in front.

Figure 3-2 SINAMICS assembly with SIMOTION D4x5

3.4 Mounting SIMOTION D4x5 on the wall of the control cabinet

3.4 Mounting SIMOTION D4x5 on the wall of the control cabinet

Overview

If you need to or wish to remove the Line Module, the Control Unit can also be mounted on the wall of the control cabinet. Two mounting options are provided for mounting on the wall of the control cabinet:

- Mounting with spacers on the wall of the control cabinet (all D4x5)
- Mounting without spacers on the wall of the control cabinet (D425/D435/D445-1 only)

D445-1 next to Line Module

If you wish to install a SIMOTION D445-1 directly to the left of a Line Module, you will need to remove the plastic mounting fixtures from the side wall of the Line Module.

These mounting fixtures stick out over the side wall of the Line Module. SIMOTION D445-1 has a smooth wall (i.e. there are no cut-outs on the side). so can only be installed flush next to the Line Module if the mounting fixtures on the Line Module are removed.

Proceed as follows to do this:



device and push up the holder.

been removed

3.4.1 Mounting the SIMOTION D4x5 with spacers

Spacers enable you to attach the Control Unit to a bare, conductive metallic wall of a control cabinet with two M5 or M6 screws.

Purpose of this type of installation

This type of mounting is needed if:

- Multiple Control Units are to be used and, therefore, all Control Units cannot be mounted on the side
- The mounting depth of the SINAMICS S120 booksize assembly is to be achieved

Installing

3.4 Mounting SIMOTION D4x5 on the wall of the control cabinet

The spacers are included in the scope of delivery of a Control Unit and are readyassembled.

Procedure

- 1. Mount the spacers on the D425/D435/D445-1 Control Unit, if they have previously been removed.
- 2. Use two M5 or M6 screws to mount the Control Unit on the wall of the control cabinet.



Figure 3-3 Mounting the control unit with spacers

Result

The Control Unit is mounted separately from the SINAMICS booksize components and flush with the assembly on the wall of the control cabinet.
3.4.2 Mounting SIMOTION D425, D435, and D445-1 without spacers

The control unit has a metal clip at the top of the rear panel; when shipped, the clip is pushed in and secured with three M3 screws (0.8 Nm).

- 1. Loosen the screws and push the clip up until the upper hole extends beyond the housing.
- 2. Tighten up the three screws on the clip again.
- 3. Mount the Control Unit directly on the wall of the control cabinet at the top and bottom using two M5 or two M6 screws (6 Nm tightening torque).



Figure 3-4 Mounting the Control Unit on the wall of the control cabinet

The Control Unit is mounted separately from the SINAMICS booksize components on the wall of the control cabinet.

3.5 Installing supplementary system components

3.5.1 Installing the TB30

Requirement

Note

The TB30 terminal board may only be inserted and removed when the D4x5 control unit and the terminal board are de-energized.

Procedure

The TB30 is installed in the option slot of the control unit.



Figure 3-5 TB30 terminal board installation

3.5.2 Installing the CBE30

Requirement

Note

The CBE30 communication board Ethernet may only be inserted and removed when the D4x5 control unit and the CBE30 are de-energized.

Procedure

A CBE30 is installed in the option slot of the control unit.



Figure 3-6 Installing the CBE30

3.5.3 Installing the CX32

Overview

The CX32 can be installed in several ways.

Mounting the CX32 directly on a line module in booksize format



Figure 3-7 Mounting the CX32 directly on a line module booksize

Installing

3.5 Installing supplementary system components

Mounting the CX32 on another CX32

A description with photos of opening the cover can be found in Section Removing the cover of the CX32 (Page 45).



Table 3-1 Mounting a CX32 on another CX32



CX32 directly on a mounting surface

There are two mounting points on the rear side of the CX32. These can be screwed directly to a wall, e.g a control cabinet wall.



Figure 3-8 Mounting the CX32 directly on a mounting surface

CX32 with spacers on a mounting surface

To provide the correct mounting depth for a booksize line-up with internal air cooling, a spacer element is pre-assembled on the CX32. The spacer must then be fixed to the mounting surface.



Figure 3-9 Mounting a CX32 with spacers

3.5.4 Removing the cover of the CX32

Actions to remove the cover of the CX32

The following steps are required to remove the cover - see the following photos:

- Release
- Swing open through approx. 45°
- Remove

Note that the cover can only be removed when it has been swung open through approx. 45°.



Figure 3-10 Opening/removing the protective cover

Connection

4.1 Complete overview (example)

Overview

The SIMOTION D4x5 has a number of interfaces that can be used for connecting the power supply and for communication with the other components of the system. To make these connections, the front cover of the SIMOTION D4x5 must be opened.

- The different SINAMICS components are interconnected via DRIVE-CLiQ.
- Actuators and sensors can be connected to the digital inputs/outputs.
- For communication purposes, the SIMOTION D4x5 can be connected to PROFIBUS DP, PROFINET IO with IRT/RT, MPI, and Ethernet.

4.1 Complete overview (example)

Overview of connections

The following overview shows examples of the various interfaces and their connection possibilities.



Figure 4-1 Connection possibilities for SIMOTION D4x5

4.2 Safety information for wiring

4.2 Safety information for wiring

Requirement

Once you have mounted the control unit in the control cabinet, you can begin wiring the assembly.

Note

Safety functions, reliability, and EMC are guaranteed only with original SIEMENS cables.

Note the following safety information:

/!\DANGER

The equipment must be deenergized when you wire the control unit.

Equipotential bonding

The SIMOTION D4x5 is designed for use in cabinets with a PE conductor connection.

If the drive line-up is arranged on a common, bare metallic mounting plate (e.g. with a galvanized surface), no additional equipotential bonding is needed within the drive line-up.

If the drive components are located in different cabinets, you have to ensure equipotential bonding.

If, for example, data cables (PROFIBUS, PROFINET, Ethernet or DRIVE-CLiQ) are routed through several control cabinets, the "potential connection" of the SIMOTION D4x5 should be connected to the equipotential bonding conductor.

Use a finely stranded copper conductor with 4 mm² cross section and lay it together with the PROFIBUS/PROFINET/Ethernet or DRIVE-CLiQ connecting cable.

The "potential connection" is located below the mode switch on the front of the SIMOTION D4x5. See also the *SIMOTION D4x5* Manual.

4.3 Opening the front cover

4.3 Opening the front cover

Introduction

The interfaces on the front side of the D4x5 and the CX32 have a cover. This is opened by swinging the front cover down; the interface connections are then accessible and can be wired. For the opening procedure, see also the photos in Section Removing the cover of the CX32 (Page 45).

A hinge connects the front cover to the front of the housing. Once opened, the cover can be removed. The front cover is closed by swinging it up; it automatically locks by means of a hook at the top of the device housing.

Procedure for D4x5 and CX32

- 1. Unlatch the release hook on the inside of the front cover (see the following figure).
- 2. Remove the front cover with a forward motion.



Figure 4-2 D4x5 with cover, figure similar for CX32

Note

All cables must be routed vertically upwards to the fullest extent possible so that the front cover can be closed. The front cover has an outlet for the upward routing of these cables.

4.4 Power supply

4.4.1 Safety rules

Basic rules

Because of the wide range of possible applications, only the basic rules for electrical installation can be included in this section. At a minimum, you must comply with these basic rules to ensure problem-free operation.

Rules for safe operation

In order to ensure safe operation of your equipment, implement the following measures, adapting them to suit your conditions:

- An EMERGENCY STOP strategy in accordance with the generally accepted rules of current engineering practice (e.g. European Standards EN 60204, EN 418 and similar).
- Additional measures for end position limiting of axes (e.g. hardware limit switches).
- Equipment and measures for protection of motors and power electronics in accordance with the SINAMICS installation guidelines.

In order to identify hazards, we also recommend that a risk analysis be conducted on the entire system in accordance with the basic safety requirements set out in Appendix 1 of the EU machinery directive.

Additional references

- Guidelines on Handling Electrostatically Sensitive Devices (ESD), see Appendix.
- For configuring a system with SIMATIC ET 200 I/O (e.g. ET 200S, ET 200M, ...), refer to the manuals for the relevant ET 200 I/O system.
- For further information on EMC guidelines, we recommend the publication: *EMC Installation Guide*, Configuration Manual (HW), order no.: 6FC5 297-0AD30-0AP2.

4.4 Power supply

4.4.2 Standards and Regulations

VDE guideline compliance

During wiring, you must observe the appropriate VDE guidelines, in particular VDE 0100 and VDE 0113 for tripping devices and short-circuit and overload protection.

System startup after certain events:

The following list identifies considerations required for startup of a system following certain events.

- If the system starts up again following a voltage drop or power failure, all hazardous
 operating states must be prevented from occurring. If necessary, force an EMERGENCY
 OFF.
- If the system starts up again after the EMERGENCY OFF apparatus is released, the startup must not be unchecked or undefined.

4.4.3 Mains voltage

Rules for the line voltage

The following list indicates what you must take into account for the line voltage:

- For stationary installations or systems that do not have all-pole line disconnect switches, the building installation must include a line disconnect switch or a fuse.
- For load power supplies and power supply modules, the rated voltage range set must correspond to the local line voltage.
- For all circuits, the fluctuation/deviation of the line voltage from the rated value must be within the permitted tolerance (see the technical data for the SIMOTION D and SINAMICS modules).

24 V DC supply

For	Requirement		
Buildings	External lightning protection	Install lightning protection (e.g. lightning conductors).	
24 V DC supply lines, signal lines	Internal lightning protection		
24 V supply	safe (electrical) isolation of the extra-low voltage		

4.4 Power supply

Protection against external electrical phenomena

The table below shows how you must protect your system against electrical interference or faults.

Table 4-1 External electrical phenomena

For	Requirement
All plant or systems in which the component is installed	The plant or system is connected to a protective conductor for the discharge of electromagnetic interference.
Supply, signal, and bus lines	The wiring arrangement and installation complies with EMC regulations.
Signal and bus lines	A cable or wire break cannot lead to undefined states in the plant or system.

4.4.4 Connecting the power supply

Wiring the screw terminal block

The required 24 VDC load power supply is connected at the screw-type terminal block.

The 24 VDC should be configured as functional extra-low voltage with safe isolation.

Supply system lines

Use flexible cables with a cross section of 0.25 to 2.5 mm^2 (or AWG 23 to AWG 13) for wiring the power supply.

If you only use one wire per connection, a ferrule is not required.

You can use ferrules without an insulating collar in accordance with DIN 46228, Form A long version.

Pin assignments

For the pin assignment of the screw-type terminal block, see the SIMOTION D4x5 Manual.

4.5 Connecting DRIVE-CLiQ components

4.5.1 DRIVE-CLiQ wiring

Introduction

The components of the SINAMICS S120 drive family and the SIMOTION D4x5 with CX32 are wired together by means of DRIVE-CLiQ. DRIVE-CLiQ is a communication system that enables SIMOTION D4x5 to detect the connected components automatically. It provides a wiring tree whose topology can be visualized in SIMOTION SCOUT.

Note

For information on the number of DRIVE-CLiQ interfaces and their properties, refer to the *SIMOTION D4x5* Manual.

Rules for wiring DRIVE-CLiQ

The following rules must be followed for wiring DRIVE-CLiQ:

- Ring wiring is not permitted
- Components must not be double-wired
- For a motor module, the power line for the motor and the associated motor encoder must be connected.

You will find detailed information about DRIVE-CLiQ wiring in the *SINAMICS S120 Control Units and Additional System Components* Manual.

Example



The example shown in this diagram shows the rules for DRIVE-CLiQ wiring.

Figure 4-3 DRIVE-CLiQ wiring (example)

4.5.2 Connectable DRIVE-CLiQ components

Components

As a general principle, all SINAMICS components approved for SIMOTION D can be connected directly to SIMOTION D or another DRIVE-CLiQ component using the DRIVE-CLiQ interface.

Table 4- 2	DRIVE-CLiQ

Component	Description
CX32 controller extension	The CX32 supports scaling of the drive-side computing performance of the SIMOTION D435 and D445/D445-1. Each CX32 can operate up to six additional servo, four vector or eight V/ <i>f</i> axes.
Line modules	Line modules (e.g. active line modules) provide the DC link voltage and can be connected via DRIVE-CLiQ depending on the module type.
Motor modules	Motor modules are used to control motors. SMC modules for processing encoder signals, for example, can be connected to motor modules.
Motors with DRIVE-CLiQ interface	Motors with a DRIVE-CLiQ interface allow simplified commissioning and diagnostics, because the motor and encoder type are identified automatically.
SMx modules	SMx sensor modules allow the acquisition of encoder data from the connected motors via DRIVE-CLiQ.
TM15 and TM17 High Feature terminal modules	The TM15 and TM17 High Feature terminal modules are used to implement measuring input inputs and cam outputs. In addition, these terminal modules provide drive-related digital inputs and outputs with short signal delay times.
	 TM15: 24 isolated bidirectional DI/DO, with sensor and cam functionality
	 TM17 High Feature: 16 non-floating, bidirectional DI/DO with sensor and cam functionality for the highest demands with respect to resolution, accuracy and short input delay times.
TM31 terminal module	TM31 provides 8 DI, 4 bidirectional DI/DO, 2 relay outputs, 2 AI, 2 AO and 1 temperature sensor input (KTY84-130 or PTC).
TM41 terminal module	TM41 provides 4 DI, 4 bidirectional DI/DO, 1 AI and 1 TTL encoder output.
TM54F terminal module	TM54F provides the following interfaces: 4 fail-safe DO (F-DO), 10 fail- safe DI (F-DI), 2 sensor power supplies with dynamic capability, 1 sensor power supply without dynamic capability and 4 DI to check the F-DO during a test stop.

Connection

4.5 Connecting DRIVE-CLiQ components

Component	Description
DMC20/DME20	DRIVE-CLiQ hubs provide 4 more DRIVE-CLiQ interfaces. They can be used, for example, to establish star topologies.
	DMC20 is the hub for the control cabinet configuration
	 DME20 is the hub for use without a control cabinet (IP67 degree of protection)
SINAMICS S120 power module	An AC DRIVE PM340 power module can be connected using the CUA31/CUA32 control unit adapter.
(with CUA31/CUA32)	You will find more information on the CUA31/CUA32 in the <i>SINAMICS S120 AC Drive</i> Manual.

Example of axis assembly

The following figure shows a possible DRIVE-CLiQ wiring scheme for an axis grouping.



Figure 4-4 Axis assembly with DRIVE-CLiQ

4.5.3 Connecting CX32

Installation/Mounting/Wiring

Information on installing, mounting and wiring the CX32 can be found in the *SIMOTION* D4x5 Manual.

CX32 DRIVE-CLiQ topology

Unlike other DRIVE-CLiQ components (e.g. terminal modules), special rules apply when wiring the CX32.

- Only a star topology is possible between the CX32 and SIMOTION D. Each CX32 needs its own DRIVE-CLiQ port on the SIMOTION D control unit.
- When a CX32 is inserted in an existing DRIVE-CLiQ connection (destination port for CX32 is occupied by, for example, a TM31), this connection is disconnected and replaced by the CX32 connection. The component that is freed up is moved to the component archive of the SINAMICS topology overview. A notice is displayed indicating that the component has been moved to the archive. The components must then be reassigned.
- A CX32 is inserted via HW Config (see Configuring a CX32 (Page 174)). Here, the selection made for the PROFIBUS address automatically and permanently assigns the DRIVE-CLiQ port for connecting the CX32. Given that this assignment is permanent, the following points must be noted:
 - A connected and configured CX32 cannot be connected to another DRIVE-CLiQ port without taking additional measures. Reconnecting a CX32 results in a discrepancy between the specified and actual topologies of the DRIVE-CLiQ components.
 - A cross-exchange of two occupied DRIVE-CLiQ ports is not permissible. Such an exchange results in inconsistencies in the specified-actual topologies.
 - Once it has been created in HW Config, the connecting port of a CX32 cannot be changed.
 - In order to change the connecting port of a CX32, the CX32 must be deleted from HW Config and recreated with another address.
 - In order to delete a CX32, it must be deleted from HW Config before the configuration can be saved and compiled.
 - It is not possible to replace a D445/D445-1 module with a D435 if a CX32 has been configured with the address 14 or 15 (since a D435 does not have DRIVE-CLiQ ports X104/X105, it does not have addresses 14 and 15).

Note

Connection possibility

A CX32 can only be connected to and operated on a SIMOTION D445/D445-1 or D435.



Figure 4-5 CX32 topology

Drive quantity structures

If one or more CX32 modules are being used on a SIMOTION D435 or D445/D445-1, the number of drives that can be used on the SINAMICS Integrated is reduced by one. This results in the following quantity structures:

SIMOTION V4.1 and V4.2/SINAMICS V2.5 and 2.6

Table 4-3Quantity structure SIMOTION V4.1 and V4.2/SINAMICS V2.5 and 2.6

	SINAMICS Integrated	1. CX32	2. CX32	3. CX32	4. CX32
SERVO D435	5+1 (5 drives + 1 ALM ¹⁾)	6+1	6+1		
SERVO D445/D445-1	5+1	6+1	6+1	6+1	6+1
VECTOR D435	3+1	4+1	4+1		
VECTOR D445/D445-1	3+1	4+1	4+1	4+1	4+1

¹⁾ ALM = Active Line Modules; Basic Line Modules (BLM), and Smart Line Modules (SLM) can also be used.

Connection

4.5 Connecting DRIVE-CLiQ components

SIMOTION V4.0 HF2/SINAMICS V2.4

	SINAMICS Integrated	1. CX32	2. CX32	3. CX32	4. CX32
SERVO D435	5+1 (5 drives + 1 ALM ¹⁾)	6+0	6+0		
SERVO D445	5+1	6+0	6+0	6+0	
VECTOR D435	3+1	4+0	4+0		
VECTOR D445	3+1	4+0	4+0	4+0	

	Our and the state	t f			
1 able 4- 4	Quantity str	ucture for	SINUTION V4	4.0 HFZ/SINA	

¹⁾ ALM = Active Line Modules; Basic Line Modules (BLM), and Smart Line Modules (SLM) can also be used.

Note

Mixed operation of servo and vector-controlled drives

Mixed operation of servo and vector-controlled drives is not possible on a CX32. Therefore, drives on a CX32 must be operated in servo or in vector mode only. As with the SIMOTION D4x5, mixed operation of servo-controlled and V/f-controlled drives is possible on a CX32.

V/f-controlled drives

A maximum of eight V/f-controlled drives are supported by each CX32.

SIZER

The SIZER configuration tool makes it easy to configure the SINAMICS S120 drive family, including SIMOTION.

It provides you with support for selecting and dimensioning the components required for a Motion Control task.

Additional references

Further information on the CX32 can be found in the SIMOTION D4x5 Manual.

4.6 Connecting inputs/outputs

4.6 Connecting inputs/outputs

Connecting cables for the inputs and outputs of the D4x5, CX32 and TB30

The following conditions apply to connecting cables:

- Use flexible cables with a cable cross-section of at least 0.25 mm² and maximum 0.5 mm²
- Ferrules are not required
- You can use ferrules without an insulating collar in accordance with DIN 46228, Form A long version
- You can connect two cables each with a cross section of 0.25 mm² in one ferrule

Note

To achieve optimum interference immunity, shielded cables must be used for connecting analog signals, measuring inputs or external zero marks.

Tools required

Screwdriver with 2 mm blade width.

Wiring inputs/outputs

- 1. Strip off 8 to 9 mm of cable insulation and, if necessary, press on a ferrule.
- 2. Wire the digital inputs of the interface for connection of the sensors.
- 3. Wire the digital outputs of the interface for connection of the actuators.
- 4. Insert the cable into the appropriate spring-loaded terminal. This is easier when you use the screwdriver to push back the spring.

Pin assignment

For detailed information about the pin assignment of the X122/X132 interfaces of the D4x5, refer to Section "Interfaces" in the *SIMOTION D4x5* Manual. Pin assignments for the digital inputs/outputs of the CX32 and TB30 can be found in the same manual in Section "Supplementary system components".

4.6.1 Creating a shield connection

Using shielded cables

The following options are available for the shield connection when using shielded cables:

- A shield connection using a shielding bus supplied separately
- Shield connection via shield connecting element on the top of the SIMOTION D4x5 housing

Using a shielding bus

If a shielding bus is used, proceed as follows:

- 1. Attach the cable shield to a grounded shielding bus after the cable entry point in the cabinet. Strip the insulation off the cable first.
- 2. Continue routing the shielded cable as far as the module but do not make a connection to the shield there.

Using a shield connection on the D4x5

- 1. Remove the fixing bracket on the top of the D4x5.
- 2. Insert the cable. Please strip the insulation off the cable first.
- 3. Tighten the fixing bracket so that the cable shield and cable are pressed against the device housing by the fixing bracket.

This figure shows where to attach the cables to the front panel connector and where to apply the cable interference suppression using the shield connecting element.



Figure 4-6 D4x5 shield connection

Connection

4.6 Connecting inputs/outputs

4.6.2 Connecting inputs/outputs of the TB30

Pin assignment



Figure 4-7 Interface arrangement on the TB30

For detailed information about the pin assignment of the X424, X481 and X482 interfaces, refer to Section "Interfaces" in the *SIMOTION D4x5* Manual.

Shield connection on the D4x5 control unit

The following figure shows the cable routing, cable connection and the connection of the analog inputs/outputs on the TB30. The plug connector above is used accordingly for the connection of the digital inputs/outputs.



Figure 4-8 TB30 shield connection

The permissible bending radii for the cables must be maintained when the cables are being laid.

4.7 Connecting PROFIBUS/MPI

4.7.1 PROFIBUS connection components

Connection components

Individual nodes are connected via bus connectors and PROFIBUS cables. Remember to provide a bus connector with a programming port at the ends of the subnet. This will give you the option of expanding the subnet if required, for example, for a programming device or SIMATIC HMI device.

Use RS 485 repeaters for the connection between segments and to extend the cable.

Segments

A segment is a bus cable between two terminating resistors. A segment can contain up to 32 nodes. In addition, a segment is limited by the permissible cable length, which varies according to the transmission rate.

Terminating resistor

A cable must be terminated with its own surge impedance to prevent line disturbances caused by reflections. Activate the terminating resistor at the first and last node of a subnet or segment.

Make sure that the nodes to which the terminating resistor is connected are always supplied with voltage during power-up and operation.

Connection

4.7 Connecting PROFIBUS/MPI

4.7.2 PROFIBUS cables and connectors

Properties of PROFIBUS cables

The PROFIBUS cable is a two-core, twisted and shielded cable with defined properties:

Cable properties

Table 4-5 Properties of PROFIBUS cables

Characteristics	Values
Wave impedance	Approximately 135 to 160 Ω (f = 3 to 20 MHz)
Loop resistance	≤ 115 Ω/km
Effective capacitance	30 nF/km
Damping	0.9 dB/100 m (f = 200 kHz)
Permissible conductor cross section	0.3 mm ² to 0.5 mm ²
Permissible cable diameter	8 mm + 0.5 mm

Connector features

The bus connector is used to connect the PROFIBUS cable to the PROFIBUS DP interfaces (X126, X136), thus establishing a connection to additional nodes.

Only bus connectors with a 35° cable outlet should be used in order to ensure that the front cover can be closed.

See also

Manual SIMOTION D4x5, Chapter "Spare parts and accessories which can be ordered"

4.7.3 PROFIBUS cable lengths

Cable lengths and baud rate

The baud rate determines the cable length of a subnet segment.

Fable 4- 6 Permitted cable ler	ngth of a subnet	segment for sp	ecific baud rates
----------------------------------	------------------	----------------	-------------------

Baud rate	Max. cable length of a segment (in m)
19.6 to 187.5 kbit/s	1000 ¹⁾
500 kbit/s	400
1.5 Mbit/s	200
3 to 12 Mbit/s	100

¹⁾ With isolated interface

Greater cable lengths

If you must realize greater cable lengths than permitted in one segment, you must use RS 485 repeaters. The maximum possible cable lengths between two RS 485 repeaters correspond to the cable length of a segment. You can connect up to 9 RS 485 repeaters in series.

Note that an RS 485 repeater must be counted as a subnet node when determining the total number of nodes to be connected. This is true even if the RS 485 repeater is not assigned its own PROFIBUS address.

4.7.4 Rules for the laying of PROFIBUS cables

Routing bus cables

When routing the PROFIBUS cable, you must avoid:

- Twisting
- Stretch the bus cable
- Squeezing

Boundary conditions

In addition, when routing a bus cable for indoor use, you must take into account the following boundary conditions (dA = external cable diameter):

Table 4- 7	Boundary	conditions	for routing	of PROFIBUS	S cables

Characteristics	Boundary conditions
Bending radius for a single bend	80 mm (10xdA)
Bending radius for multiple bends	160 mm (20xdA)
Permissible temperature range for cable routing	-5° C to +50° C
Temperature range for storage and stationary operation	-30° C to +65° C

Additional references

Length codes for prefabricated cables can be found in:

- Catalog PM 21; SIMOTION, SINAMICS S120, and Motors for Production Machines
- Catalog IK PI (Industrial Communication)

4.7.5 Connecting PROFIBUS DP (interfaces X126 and X136)

PROFIBUS cables are connected to the corresponding interface via a bus connector.

Connecting the bus connector

Proceed as follows to connect the bus connector:

- 1. Plug the bus connector into the corresponding interface of the control unit.
- 2. Screw the bus connector into place.

If the control unit is located at the start or end of a segment, you must switch on the terminating resistor ("ON" switch setting).



Figure 4-9 Terminating resistor switched on and off

Note

Make sure that the nodes at which the terminating resistor is located are always supplied with voltage during startup and operation.

Removing the bus connector

You can remove the bus connector with a looped-through bus cable from the PROFIBUS DP interface at any time without interrupting data traffic on the bus.

Data traffic error might occur on the bus!

A bus segment must always be terminated at both ends with the terminating resistor. This is not the case, for example, if the last node with a bus connector is de-energized. The bus connector draws its power from the node, and the terminating resistor is thus disabled.

Make sure that power is always supplied to nodes on which the terminating resistor is active.

4.7.6 Connection rules in the PROFIBUS subnet

Introduction

There are a number of rules for configuring and installing cables for PROFIBUS networks to ensure seamless communication over PROFIBUS. These rules apply to both configuring and cabling as well as address assignment for the different network nodes.

Connection rules

- **Before** you interconnect individual nodes in a subnet, you must assign a unique PROFIBUS address to each node.
- Narrow down the number of nodes by limiting the PROFIBUS addresses to the highest address in the network.

Tip: Mark the address on the housing of all nodes in a subnet. Then you can always see which address is assigned to which node in your system.

 Connect all nodes in a subnet "in a series". No spur lines may be routed to the PROFIBUS DP.

In addition, integrate the programming devices and SIMATIC HMI devices for commissioning or servicing in the subnet in series.

• If you operate more than 32 nodes on a subnet, you must use RS 485 repeaters to connect the bus segments. More detailed information can be found in the description of the RS 485 repeater, see the *S7-300 Automation Systems, Module Data* Manual.

In a PROFIBUS subnet, all segments combined must have at least one DP master and one DP slave.

- Use RS 485 repeaters to connect ungrounded bus segments and grounded bus segments.
- The maximum number of nodes per bus segment decreases with each RS 485 repeater. That is, if a bus segment contains one RS 485 repeater, the bus segment can contain no more than 31 additional nodes. However, the number of RS 485 repeaters does not affect the maximum number of nodes on the bus.
- Up to 10 segments can be connected in a row (max. 9 repeaters).
- At least one terminator must be supplied with 5 V.

To accomplish this, the PROFIBUS DP connector with an activated terminating resistor must be connected to a device that is switched on.

Before inserting a new node on the subnet, you must switch off its supply voltage.

The station must be inserted first and then switched on.

When a station is disconnected, the connection must **first** be deactivated and then the connector withdrawn.

• The bus line of a segment must be terminated at **both ends**. This is achieved by switching on the terminating resistor in the PROFIBUS DP connector at the first and last node and switching off the other terminating resistors.

Example

This illustration below shows an example configuration of a subnet with D435.



Figure 4-10 Networking example for a D435

4.7.7 Operating the X136 interface as MPI

Applications

The X136 interface can also be operated as an MPI interface instead of a PROFIBUS DP interface. The typical (default) baud rate is 187.5 Kbaud. A baud rate of up to 12 MBaud can be set for communication with other CPUs. It should be noted, however, that a rate of 12 MBaud is not supported by all CPUs (e.g. smaller SIMATIC S7 CPUs).

The following list provides examples of when using MPI (multi-point interface) may prove effective:

- If a PC/PG is being used with an MPI interface
- If an OP/TP only has an MPI interface (newer devices have PROFIBUS or PROFINET interfaces)
- If SIMOTION and SIMATIC CPUs are coupled via XSEND/XRECEIVE

When communicating with XSEND/XRECEIVE, there is no need to configure the connection in NetPro. XSEND/XRECEIVE can be used via PROFIBUS or MPI.

- Via PROFIBUS: For communication between SIMOTION devices
- Via MPI: For communication between SIMOTION and SIMATIC S7 devices

The SIMOTION interface must be connected to the MPI interface of the SIMATIC S7 devices. Connection via PROFIBUS is not possible.

The baud rate of the SIMATIC S7 device must be set at the SIMOTION interface (see documentation for the relevant SIMATIC S7 devices).

Operate MPI like PROFIBUS

The information on wiring the connector (terminating resistors) and the rules for routing of cables for PROFIBUS apply to this interface as well. When carrying out this procedure, consult the relevant references.

Connector features

The bus connector is used to connect the MPI bus cable to the MPI interface (X136). This enables you to establish connections to additional nodes (e.g. PG or SIMATIC S7-CPU). Only bus connectors with a 35° cable outlet should be used in order to ensure that the front cover can be closed.

Additional information

See SIMOTION D4x5 Manual, Chapter "Spare parts and accessories which can be ordered"

MPI bus cable

The PROFIBUS cable specifications apply here as well;

Please note the relevant information on setting up an MPI network.

Setting up an MPI network

Keep in mind the following basic rules when setting up an MPI network:

- When using the interface as an MPI interface, it is not possible to arrange additional control for a drive in isochronous mode or to connect distributed I/Os to this interface.
- An MPI bus line must be terminated at both ends. This is achieved by activating the terminating resistor in the MPI connector in the first and last station and deactivating the other terminating resistors.
- At least one terminator must be supplied with 5 V.

This means that an MPI connector with an activated terminating resistor must be connected to a device that is switched on.

 Spur lines (cables leading from the bus segment to the station) should be as short as possible, that is, < 5 m in length. Unused spur lines should be removed wherever possible.
4.8 Connecting PROFINET IO components

• Every MPI station must be connected to the bus first and then activated.

To disconnect the station, it must first be deactivated. Then, the station can be removed from the bus.

- Maximum cable lengths:
 - 200 m per bus segment
 - 2000 m total length with RS 485 repeaters

Note

You can also use intelligent DP slave functionality for PROFIBUS communication between CPUs.

See also

PROFIBUS cables and connectors (Page 67) PROFIBUS cable lengths (Page 67)

4.8 Connecting PROFINET IO components

4.8.1 Wiring PROFINET

Procedure

PROFINET IO is only possible on a SIMOTION D4x5 in conjunction with a CBE30 (Communication Board Ethernet). PROFINET IO components can then be connected via the four ports of the X1400 interfaces of the CBE30. You must use suitable PROFINET cables and connectors for this purpose.

The autocrossing functionality of the CBE30 means both crossed and uncrossed cables can be used.



Figure 4-11 Connections on the CBE30

4.8 Connecting PROFINET IO components

Mixed operation of IRT and RT

For mixed operation of IRT and RT, note that the IRT-compatible devices must form a socalled IRT domain, i.e., there must not be any non-IRT devices on the data transmission link between the IRT devices.



4.8.2 PROFINET cable

Cable and connector types

Note

For connecting PROFINET IO to CBE30 it is recommended using a connector with a 145° cable outlet (IE FC RJ45 plug 145).



Figure 4-12 RJ45 PN connector with a 145° cable outlet

4.8 Connecting PROFINET IO components

Connectors	Designation	Order No.	
IE FC RJ-45 Plug 145	RJ45 FastConnect connector for Industrial Ethernet/PROFINET with 145° cable outlet		
	 1 package = 1 unit 1 package = 10 units 	6GK1 901-1BB30-0AA0 6GK1 901-1BB30-0AB0	

Table 4-8 Connector types for PROFINET

Table 4-9 Cable types for PROFINET

Cable	Designation	Order No.
IE FC Cable GP 2 (Type A)	4-wire, shielded TP installation cable for IE FC RJ45	6XV1 840-2AH10
IE FC Flexible Cable GP 2 (Type B)	4-wire, shielded flexible TP installation cable for IE FC RJ45	6XV1 870-2B
IE FC Trailing Cable GP 2x2 (Type C)	4-wire TP installation cable for trailing cable use	6XV1 870-2D
IE FC Trailing Cable 2x2 (Type C)	4-wire, shielded TP installation cable for connection to FC OUTLET RJ45, for trailing cable use	6XV1 840-3AH10
IE FC Marine Cable 2x2	4-wire, shielded marine-certified TP installation cable for connection to FC OUTLET RJ45	6XV1 840-4AH10

Table 4-10 Stripping tool for Industrial Ethernet/PROFINET

Tools	Designation	Order No.
IE FC stripping tool	Stripping tool for Industrial Ethernet/PROFINET	6GK1 901-1GA00

Note

For a description of how to connect the connector to the cable, please refer to the information on the respective connector in the *Industrial Communication* Catalog (**IK PI** Catalog). You can also order cables and connectors there.

4.9 Routing

Routing describes the cross-network transfer of information from Network x to Network y.

4.9.1 Routing on SIMOTION D

Routing between the different interfaces

The two standard Ethernet interfaces on SIMOTION D4x5 - X120 and X130 - each form a separate subnet; all ports on the CBE30 also form a common subnet.

- Routing from subnet to subnet (IP routing) is not supported. You can use an external IP router for this.
- S7 routing from a PROFINET/Ethernet subnet to PROFIBUS is possible.

There are two options for connecting a PG/PC or HMI to a SIMOTION D with CBE30 using S7 routing.

Engineering system / HMI to PROFINET (CBE30)



Figure 4-13 Example for PG/PC to CBE30

- S7 routing to the (master) PROFIBUS interfaces (only if configured)
- S7 routing to the PROFIBUS Integrated
- S7 routing to the standard Ethernet interfaces ET1/ET2 (X120, X130) (as of V.4.1 SP2)
- Access to the components on the same subnet (CBE30) via the switch functionality

Engineering system / HMI to PROFIBUS



Figure 4-14 Example for PG/PC to PROFIBUS

- S7 routing to the other (master) PROFIBUS interfaces (only if configured)
- S7 routing to the PROFIBUS Integrated
- S7 routing to X1400 on the CBE30
- S7 routing to the standard Ethernet interfaces (X120, X130) (as of V.4.1 SP2)

Engineering system / HMI to Ethernet



Figure 4-15 Example for PG/PC to Ethernet X120, X130

- S7 routing to the other (master) PROFIBUS interfaces (only if configured)
- S7 routing to the PROFIBUS Integrated
- S7 routing to X1400 on the CBE30 (as of V4.1 SP2)
- S7 routing between the Ethernet interfaces

4.9.2 Routing on SIMOTION D (SINAMICS integrated)

S7 routing to the internal PROFIBUS on SINAMICS Integrated

All SIMOTION D have an integrated SINAMICS drive control. In order to be able to access drive parameters, the message frames must be routed from the external SIMOTION D interfaces to the internal PROFIBUS DP. S7 routing can be used to access the integrated PROFIBUS. Here, the internal PROFIBUS DP forms a separate subnet. This must be especially taken into account for the communication to several routing nodes.

Additional references

Further information about routing and the differences between IP and S7 routing can be found in the *Communication* System Manual.

Connection

4.10 Connecting Ethernet

4.10 Connecting Ethernet

4.10.1 Wiring Ethernet

Procedure

An Industrial Ethernet can be connected to the 8-pin RJ45 sockets X120 and X130.

The interfaces support a transmission rate of 10/100 Mbit/s. Suitable Ethernet cables and connectors must be used for the Ethernet connection.



Figure 4-16 Connecting Industrial Ethernet

4.10.2 Ethernet cables and connectors

Characteristics of the cables

A shielded twisted pair cable is used for the networking.

Recommended connecting cables

The following cables are available:

- SIMATIC NET, Industrial Ethernet TP XP CORD RJ45/RJ45
 - TP cable prefabricated with 2xRJ45 connectors
 - Crossed send and receive cable
 - Order no.: 6XV1870-3R
- SIMATIC NET, Industrial Ethernet TP CORD RJ45/RJ45
 - TP cable prefabricated with 2xRJ45 connectors
 - Uncrossed send and receive cable
 - Order No.: 6XV1870-3Q

Devices with Ethernet interfaces can have various pin assignments.

In the case of terminal devices, for example, the send line may be on pins 1 and 2, while pins 1 and 2 on a switch or hub may connect to the receive line. If two devices are connected using Ethernet, the type of device will dictate whether crossed or uncrossed Ethernet cables need to be used. (For example, a crossed cable is required if two Ethernet terminal devices are directly connected.)

You require a crossed cable for the PG/PC connection if your PG/PC does not have an Ethernet interface with autocrossing functionality.

Additional references

For further information about the cables and connectors, see the *Industrial Communication IK PI* Catalog.

Connection

4.10 Connecting Ethernet

Commissioning (hardware)

5.1 Requirements for commissioning

Requirements

The following requirements must be satisfied for the initial commissioning of the SIMOTION D4x5 and the SINAMICS S120 modules required for operation (SINAMICS S120 line modules and SINAMICS S120 motor modules):

- Your system with SIMOTION D4x5 has been installed and wired.
- Your PG/PC has been connected to the SIMOTION D4x5 via a PROFIBUS or Ethernet interface or via PROFINET (CBE30).

Commissioning steps

Commissioning the hardware involves the following steps:

- 1. Inserting the CF card (Page 83)
- 2. Checking the system (Page 85)
- 3. Switching on the power supply (Page 85)

Additional references

For information on installing/mounting and commissioning the SINAMICS S120 components, refer to the *SINAMICS S120* Commissioning Manual.

5.1.1 Inserting the CompactFlash card

Properties of the CF card

The CF card is mandatory for operation of the SIMOTION D4x5. The SIMOTION Kernel and the software used to control the drives (SINAMICS firmware) are contained on the CF card.

In order to load the SIMOTION kernel, the CF card must be inserted when the SIMOTION D4x5 is powered up.

The CompactFlash card may only be inserted or removed when the SIMOTION D4x5 control unit is disconnected from the power supply. SIMOTION D4x5 is in a de-energized state when all the LEDs are OFF.

5.1 Requirements for commissioning

Procedure

To insert the CF card, carry out the following steps:

- 1. The direction of insertion of the CF card is indicated by an arrow located on both the plugin slot and the CF card. Align the CF card with the arrows.
- 2. Gently insert the CF card into the empty plug-in slot of the SIMOTION D4x5 until it clicks into place.

If correctly inserted, the CF card is flush with the housing.



Figure 5-1 Inserting the CF card

See also

Changing the CompactFlash Card (Page 295)

5.1 Requirements for commissioning

5.1.2 Checking the system

Procedure

Check the final installed and wired system one more time before it is switched on, keeping in mind the safety points in the following check list:

- Have you observed all ESD measures when handling the components?
- Have all screws been tightened to their specified torque?
- Have all connectors been properly inserted and locked/screwed?
- Are all components grounded and have all shields been attached?
- Have you taken the load capacity of the central power supply into consideration?

SIMOTION D445/D445-1 must not be operated without a fan/battery module. SIMOTION D445/D445-1 will not power up without a fan/battery module.

5.1.3 Switching on the power supply

Switching on the external power supply

Power is supplied to the SIMOTION D4x5 via an external power supply unit such as SITOP. Switch on this power supply.

It is essential to ensure that the external 24 VDC power supply to the D4x5 is not interrupted for longer than 3 ms. After the expiration of these 3 ms, the SIMOTION D4x5 powers down and can be recommissioned with OFF/ON only.

For additional information, refer to the section titled Properties of the user memory (Page 89).

Power-up of control unit

Once the power supply has been switched on, the SIMOTION D4x5 begins to power up:

- 1. At the start of the power-up, all LEDs are briefly illuminated. The LEDs on the SIMOTION D4x5 enable you to track the progress of the power-up. Any errors are displayed.
- 2. Power-up of the SIMOTION Kernel

5.1 Requirements for commissioning

 All DRIVE-CLiQ connections (e.g. with the SINAMICS S120 Active Line Module) are also detected automatically.

Note

As long as the RDY LED continues to flicker, power-up is not complete and it is not possible to go online.

During commissioning the components' firmware is upgraded or downgraded automatically based on the FW version on the CompactFlash Card and the FW version on the SINAMICS components (DRIVE-CLiQ components, CBE30, PM340, etc.).

The update can take several minutes and its progress is tracked by corresponding messages appearing in the alarm window of SIMOTION SCOUT.

SIMOTION D4x5/CX32/DRIVE-CLiQ components:

An FW update on DRIVE-CLiQ components is indicated by the RDY LED flashing red/green:

- FW update running: RDY LED flashing slowly (0.5 Hz)
- FW update complete: RDY LED flashing quickly (2 Hz)

These flashing patterns are also displayed on the yellow RDY LED on the SIMOTION D/CX32, and indicate that a FW update has been carried out on components connected to the SIMOTION D/CX32 or that all components have completed the FW update.

Go offline once all the FW updates are complete, POWER ON the upgraded/downgraded components.

CBE30 Option Board:

During the firmware update, the OPT LED of the SIMOTION D module and the SYNC LED of the CBE30 flash green.

 The first time it is energized, the SIMOTION D4x5 goes to STOP mode following powerup.

Following power-up, the SIMOTION D4x5 is in a state in which it can be configured.

Fan/battery module on a SIMOTION D445/D445-1 faulty or missing

While the SIMOTION D445/D445-1 is powering up, a test is performed to check whether the fan/battery module is functioning properly. If a fan/battery module is not mounted or is mounted improperly, the kernel is not downloaded and the RDY LED flashes red/yellow (2 Hz). Switch off the power supply and correct the fault before switching on the power supply again.

If the SIMOTION D445 runs for more than a minute with a missing or faulty fan/battery module, the module will switch to the reset state after approximately 1 minute. This state can only be reset with a switch-off.

5.2 RESET button

If the SIMOTION D445-1 needs to be cooled (fan switches on with temperature control) and this is not possible due to a fan/battery module having been removed or being faulty, the module state will change to reset after approximately 1 minute. This state can only be reset with a switch-off.

5.2 RESET button

Layout

The RESET button is located behind the blanking cover on the SIMOTION D4x5.

Performing a reset

A reset causes the entire system to be reset and forces the system to power up again. This operation is comparable with a "Power on Reset" but does not require the disconnection of the 24 V power supply.

5.3 User memory concept

5.3.1 SIMOTION D4x5 memory model

The following figure provides an overview of the memory model of SIMOTION D4x5.



Figure 5-2 SIMOTION D4x5 memory model

As a result, the SIMOTION Kernel (D4x5 firmware) contains the functions needed for virtually all applications and corresponds in essence to a PLC with the IEC 61131-3 command set plus system functions for controlling various components, such as inputs and outputs.

The SIMOTION Kernel can be expanded by loading technology packages (TPs), e.g. for motion control or temperature control.

In the following chapters, you will learn information about the user memories and the steps involved in certain operations.

5.3.2 Properties of the user memory

Non-volatile data

Non-volatile data make it possible to retain relevant data for the user and the system even when the SIMOTION D4x5 has been switched off. You will find information about the area that can be used for non-volatile data in the *SIMOTION SCOUT* Configuration Manual and in the *SIMOTION D4x5 Technical Data* Manual.

A SIMOTION device has the following non-volatile data:

Non-volatile data	Content	
Kernel data	Last operating mode	
	IP parameters (IP address, subnet mask, router address)	
	DP parameters (PROFIBUS DP address, baud rate)	
	Diagnostics buffer	
Retain variables	 Variables in the interface or implementation section of a unit declared with VAR_GLOBAL RETAIN 	
	Global device variables set with the "RETAIN" attribute	
Retain TO	Absolute encoder offset	
DCC blocks	SAV blocks and user-defined blocks with retain behavior ("SAV = SAVE", blocks for the non-volatile data backup)	

Table 5-1 Non-volatile data contents

Note

DCC SIMOTION blocks with retain behavior act like retain variables in terms of copying RAM to ROM, resetting memory, downloading, backing up non-volatile data (_savePersistentMemoryData) and backing up data.

With SINAMICS Integrated the SINAMICS retain data is buffered (this is also the case with SINAMICS DCC, where SuperCap or a battery is used). With _savePersistentMemoryData data is **not** saved.

With CX32 there is permanent data buffering via the FRAM. With_savePersistentMemoryData data is **not** saved.

For further information on DCC, see the "DCC Programming" Programming Manual.

The non-volatile data of the SIMOTION D4x5 has the following properties:

Property	Meaning
City:	The non-volatile data is in the SIMOTION D SRAM. The following backup options are available:
	SRAM backed up by SuperCap (maintenance-free), or
	SRAM backed up by fan/battery module; with battery mounted
	 Non-volatile data backed up from SRAM to CF card (_savePersistentMemoryData)
Backup time:	SuperCap: 5 days, minimum
	Battery: At least 3 years

Table 5-2 Non-volatile data properties

The integral real-time clock in the SIMOTION D4x5 is also backed up, like the SRAM. The same backup time applies for the integral real-time clock.

If the buffer time is exceeded on the real-time clock, the time is reset.

Fan/battery module

If the backup time is insufficient, a battery can be connected by means of an external fan/battery module. The backup time of a used type of battery is at least 3 years.

A 3 V lithium SN: 575332 battery type (with cable tail and connector) is used. The battery can be replaced without data loss, because the retain data is backed up internally via the SuperCap.

The fan/battery module is optional for the D425/D435 and must be ordered separately. Since the fan/battery module is always required for the D445/D445-1 it is included in the scope of delivery of a D445/D445-1 (see the SIMOTION D4x5 Manual)

CF card

With the _savePersistentMemoryData system function, the user program can back up the contents of the non-volatile data to the CF card. This ensures that the retain variables and the absolute encoder position are backed up in the event that a spare part is used.

Note

IP and DP parameters in the non-volatile data

If the CF card contains a configuration, the IP and DP parameters are loaded from the CF card during power-up and used by the SIMOTION device. The SIMOTION D4x5 uses the addresses defined in these parameters to go online. During power-up, the IP and DP parameters on the CF card are also written to the non-volatile data. If the SIMOTION device is then powered up with a CF card with no configuration, the IP and DP parameters are retained in the non-volatile data and are used by the device. Thus, the SIMOTION device can continue to go online if a configuration was loaded with SIMOTION SCOUT at least once or if the SIMOTION device is powered up with a CF card containing a configuration.

Volatile data (RAM / current data RAM)

The volatile data is defined by the following properties:

- The volatile data is located in the RAM memory of the SIMOTION device.
- The download data of SIMOTION SCOUT are written to this memory.

- This data is lost with the SIMOTION D4x5 is switched off.
- The "volatile data" area contains the following data:
 - SIMOTION Kernel (D4x5 firmware)
 - Technology packages (TP)
 - User data (programs, configuration data, parameter settings)



Figure 5-3 Configuration data and system variables in the volatile memory

Further information about memory management for SIMOTION appears in the *SIMOTION SCOUT Basic Functions* Function Manual.

CompactFlash card (CF card)

The CF card contain the following data:

- SIMOTION Kernel (D4x5 firmware)
- Technology packages (TP)
- User data (units, configuration data, parameter settings, task configuration)
- IP parameters (IP address, subnet mask, router address)
- DP parameters (PROFIBUS DP address, baud rate)
- Also, if required:
 - User data saved with _savePersistentMemoryData and _export/_saveUnitDataSet
 - Data from SIMOTION IT
 - Archived SCOUT project

5.3.3 Operations and their effect on the user memory

The operations marked with arrows in the figures entitled "SIMOTION D4x5 memory model" and "Configuration data and system variables in the volatile memory" and their effects on the user memory will be described below.

SIMOTION SCOUT Download

The "Download" menu command transfers the following data from the engineering system to the "volatile data" area:

- User data (units, configuration data, parameter settings, task configuration)
- Technology packages (TPs)

In addition, the IP and DP parameters are saved to the "non-volatile data" area. The retain variables are set to their initial values, but this depends on the settings in SIMOTION SCOUT. If the SIMOTION D4x5 is switched off following the download, the volatile data is lost.

Copy RAM to ROM

The Copy RAM to ROM menu command saves the following data via the engineering system to the CF card:

- Technology packages and user data (units, configuration data, parameters, task configuration) of the "volatile data" area
- Current data values are copied to the "volatile data" area, depending on the settings in SIMOTION SCOUT.

Note

The "Copy RAM to ROM" menu command does not save the current values of the retain variables to the CF card. Use the system function "_savePersistentMemoryData" for this.

Current RAM

If you change the system variable values, these take immediate effect in the current RAM. New configuration data values are initially stored in the Next memory. Configuration data that takes immediate effect is automatically transferred to the current RAM. Configuration data that will only become active following a RESTART on the technology object (set the restartactivation system variable to the ACTIVATE_RESTART value) is not written to the current RAM until after the RESTART.

To save the configuration data changed online to the offline project, you must first transfer the content of the current RAM to the RAM using the menu command "Target system" > "Copy current data to RAM".

Once you have done this, the configuration in SCOUT will no longer be consistent with the configuration in the target device, as a consistency check is performed on the RAM data. Read the data from the RAM using the menu command "Target system" > "Load" > "Load CPU / drive unit to PG" (for the configuration data only) to re-establish a consistent system state.

To save the configuration to the CF card in non-volatile format, use the menu command "Target system" > "Copy RAM to ROM".

Via the menu "Options" > "Settings..." > "Download", you can set whether current values are to be copied to the RAM and configuration data loaded to the PG with "Copy RAM to ROM" using the option "Transfer current values with copy RAM to ROM".

Note

The "Copy current data to RAM" command does not transfer the values of the system variables to the RAM memory. This means that "Save to memory card (Copy RAM to ROM)" or "Save in the engineering project (Load CPU / drive unit to PG)" is not possible.

In order to ensure that system variable values can also be saved to the engineering project and memory card, the system variable values must be changed OFFLINE and then downloaded to the target device and saved.

SIMOTION D4x5 power-up

During power-up of the SIMOTION D4x5, the SIMOTION Kernel is loaded from the CF card to the "volatile data" area.

When the SIMOTION D4x5 is switched off, the contents of the "volatile data" area are lost. When the SIMOTION D4x5 is powered up again, the following data is loaded from the CF card:

- Technology packages and user data in the "volatile data" area
- IP and DP parameters in the "non-volatile data" area

Backing up non-volatile data

You have the following options for backing up non-volatile data on the CF card:

- In the user program: With the "_savePersistentMemoryData" system function, the user program can back up the non-volatile data content to the CF card. This ensures that the retain variables and the absolute encoder position are backed up in the event that a spare part is used.
- Using a switch position (SIMOTION D4x5 Service selector switch) or IT DIAG. See Section Diagnostic data and non-volatile data (Page 310).

The contents are saved to the "PMEMORY.XML" backup file in the "USER/SIMOTION" directory. On the system side, this system function ensures that a consistent overall image of the non-volatile data is always available the next time the unit is powered on, even if there is a power failure during backup. To this end, before a new backup file is created, any existing backup file is renamed as "PMEMORY.BAK". If the save operation to the new backup file fails (e.g. because the capacity of the CF card is insufficient), this backup copy of the backup file is used the next time an attempt is made to restore the non-volatile data content. If the new file is successfully created, the backup copy of the backup file is deleted.

NOTICE

Non-volatile data that is not backed up to the CF card will be lost if a spare part is installed (in the event of a module defect). For example, failing to back up the current values of the retain variables will result in them being lost and reset to their initial values.

If an absolute encoder overflow occurs after "_savePersistentMemoryData", the actual position value will no longer be correct once the non-volatile data has been restored. In this case, homing (absolute encoder adjustment) must be repeated.

With the SCOUT functions "Back up variables" and "Restore variables", you also have the option of backing up to your PC and restoring data that was changed during operation and only stored in the runtime system.

Reloading non-volatile data

Data backed up on the CF card with **_savePersistentMemoryData** is reloaded in the following scenarios:

- 1. Loss of the SRAM contents (buffer failure due to empty SuperCap or empty backup battery)
- 2. After a module replacement, see Section Replacing modules (spare parts) (Page 267)
- 3. After a memory reset, see Section SIMOTION D4x5 memory reset (Page 249)
- 4. Via switch position, see Section Deleting/restoring non-volatile data (Page 317)

Power failure

In the event of a power failure, the data in the SRAM of the control unit is backed up by an internal SuperCap and a fan/battery module (where applicable).

The non-volatile data is available again the next time the unit is powered up. Thus, the control unit is immediately operational without data loss.

Note

After power off and then on again, the SIMOTION part starts in coordination with the SINAMICS Integrated, whereby the SINAMICS Integrated takes longer to power up. The "Incoming station" alarm is triggered, and the PeripheralFaultTask is called.

Power-up and non-volatile data

The table below lists the cases that can arise during power-up in conjunction with the non-volatile data and explains how they are handled.

Table 5-3 Cases: Power-up with non-volatile data

Case	Initial condition	Result
1	The non-volatile data is valid.	SIMOTION D4x5 powers up with the non-volatile data, meaning, for example, that the PROFIBUS address in the non-volatile data is valid.
2	The non-volatile data is invalid and there is no backup file (PMEMORY.XML) and no backup copy of the backup file (PMEMORY.BAK).	SIMOTION D4x5 copies the default settings to the non- volatile data and powers up with this data. In this case, for example, the default PROFIBUS address is used.
3	The non-volatile data is invalid. A valid backup file (PMEMORY.XML) exists.	SIMOTION D4x5 copies the backup file contents to the non-volatile data and powers up with this data.
4	The non-volatile data is invalid, the backup file is invalid and there is no backup copy of the backup file (PMEMORY.BAK).	SIMOTION D4x5 copies the default settings to the non- volatile data and powers up with this data, in which case, for example, the default PROFIBUS address is used.
5	The non-volatile data is invalid; a backup file exists, but it is invalid; a backup copy of the backup file exists and is valid.	SIMOTION D4x5 copies the backup file contents to the non-volatile data and powers up with this data.

Non-volatile data diagnostics

The user can determine the status of the non-volatile data and the battery using the diagnostic buffer, system variables, and PeripheralFaultTask.

Evaluating via the diagnostics buffer

When they are issued, the following messages are entered once in the diagnostics buffer:

Table 5-4 Messages of the diagnostics buffer

Entry	Meaning	Remedy
Level 1 battery voltage warning 1)	Battery voltage below prewarning level	Replace battery in the fan/battery module
Level 2 battery voltage warning ¹⁾	The battery voltage is below the warning level, backing up of non-volatile data / clock can no longer be guaranteed.	Replace battery in the fan/battery module
Battery voltage for data backup in permissible range		
Non-volatile data memory voltage error	The buffer voltage of the SuperCap or the battery was too low after Power On. Possible data loss in the non-volatile data / clock.	Replace battery in the fan/battery module or charge the SuperCap over a longer period.
Non-volatile data loaded from a file (Persistent Data File Loading done)	Non-volatile data has been successfully restored from the backup file on the CF card.	-

Entry	Meaning	Remedy
Non-volatile data loaded from the backup file (Persistent Data Backup File Loading done)	Non-volatile data has been successfully restored from the backup copy of the backup file on the CF card.	-
Error while loading non-volatile data from a file (Persistent Data File Loading Failure)	 Backup file or backup copy of backup file could not be loaded. Possible causes: Backup file or backup copy of backup file does not exist Data in backup file is invalid 	Use the "_savePersistentMemoryData" system function to generate a valid backup file.
Device with battery module	Fan/battery module is present.	-
Device without battery module	Fan/battery module is not present.	Connect fan/battery module if necessary.

¹⁾ These warnings are only signaled when the fan/battery module has been inserted.

Refer to the *SIMOTION SCOUT* Configuration Manual for information about how to read out the contents of the diagnostic buffer.

Evaluating via PeripheralFaultTask

Battery status changes in RUN are reported to the user program by calling PeripheralFaultTask. Changes can be evaluated here using Taskstartinfo:

- TSI#InterruptId = _SC_PC_INTERNAL_FAILURE (= 205)
- TSI#details = 16#00000040.

If there is no fan/battery module present or no battery inserted when the power is on, or in STOP mode, no PeripheralFaultTask will be triggered when powering up or in RUN (application case: D4x5 should generally be operated without a fan/battery module or battery).

References

Detailed information on setting up TaskStartInfo(#TSI) can be found in the *SIMOTION SCOUT Basic Functions* Function Manual.

Evaluating via system variables

The system variables in the "device.persistentDataPowerMonitoring" structure indicate the status of the non-volatile data and the battery.

System variable	Designation	State	Updating	
powerFailure	Buffer voltage (SuperCap or battery) too low, possible loss of data	NO (91) YES (173)	"YES" was set at too low a buffer voltage when powering up; status needs to be reset to "NO" via the application.	
persistentDataState	Reading the persistent data	See the table below, "State of non-volatile data following power- up".	During power-up	
warningBatteryVoltage Level1 ¹⁾	Battery voltage below the prewarning level	NO (91) YES (173)	During a status change, remains set if Level 2 is reached	
warningBatteryVoltage Level2 ¹⁾	Battery voltage below the warning level	NO (91) YES (173)	During a status change	

Table 5-5 Status of the non-volatile data and battery

¹⁾ **Both**battery warning levels are set under the following conditions:

- The fan/battery module has been installed and the battery has been inserted but the battery voltage is below warning level 2.
- The fan/battery module has been installed but no battery has been inserted (as of V4.1 SP2).
- No fan/battery module has been installed (as of V4.1 SP2).

System variable "device.persistentDataPowerMonitoring.persistentDataState" indicates the state of the non-volatile data after power-up.

Table 5-6 State of non-volatile data after powering up (persistentDataState system variable)

State	Meaning
FROM_RAM (1)	Non-volatile data in the SIMOTION device is used
FROM_FILE (2)	Non-volatile data is restored from the backup file
FROM_BACKUP (3)	Non-volatile data is restored from the backup copy of the backup file
INVALID (4)	Data in the non-volatile data and in the backup file / backup copy of backup file is invalid or non-existent/deleted.
	The SIMOTION device has copied the default settings to the non-volatile data and used this data to power up.

Requirement/availability of the battery (as of V4.2)

System variables can be used to evaluate:

- Whether a battery is required for the operation of the device (or not)
- Whether a battery is available (or not)

System variable on the device	States	Description
fanbattery of the st	ructfanbattery type (the	system variables are of the enumfanbattery type)
.batterynecessary	MANDATORY	Battery is required for the backup of the retain data and the real-time clock (RTC) of the device. .batteryexisting can be used to query whether a battery is available.
	OPTIONAL	The retain data and the real-time clock (RTC) are backed up via SuperCap. A battery can be used as an option to extend the backup time. .batteryexisting can be used to query whether a battery is available. Example: D4x5
	OPTIONAL_RTC 1)	A battery is not required for the backup of the retain data.
		Only the real-time clock (RTC) is backed up via SuperCap. A battery can be used as an option to extend the backup time of the real-time clock. .batteryexisting can be used to query whether a battery is available. Example: D4x5-2
	NOT_MANDATORY	A battery is not required for the backup of the retain data. The real-time clock (RTC) is backed up via SuperCap. Example: D410
.batteryexisting	EXISTING	EXISTING is only displayed when .batterynecessary is set to:
		MANDATORY or
		OPTIONAL or
		OPTIONAL_RTC
		and a battery is available.
	NOT_EXISTING	Battery is not available.

Table 5-7	System	variable batter	vnecessar	v/batter	vexisting
	Oystern	variable baller	ynecessar	y/Daller	yensung

¹⁾ If the SuperCap is discharged, the contents of the real-time clock (RTC) are lost

5.4 Fan

5.4.1 Cooling the SIMOTION D4x5

Overview

If natural convection proves inadequate in terms of dissipating heat away from the module, and the supply air temperature exceeds the permissible limits as a result, in the case of SIMOTION D425/D435 an external fan/battery module must be mounted on the underside of the module. A fan/battery module is always required for SIMOTION D445/D445-1.

Property	SIMOTION D425	SIMOTION D435	SIMOTION D445	SIMOTION D445-1
Fan/battery module	Optional	D435 with order no. 6AU1 435-0AA00- 0AA1: Optional	Always required	Always required
		D435 with order no. 6AU1 435-0AA00- 0AA0: Required for supply air temperatures of 43° C and above		
Fan/battery module included in the scope of delivery of the D4x5			Fan/ battery module (single fan) with order no. 6FC5 348-0AA01- 0AA0	Double fan/ battery module with order no. 6FC5 348-0AA02- 0AA0
Fan/battery modules which can be used in principle	Type 6FC5 348- 0AA01-0AA0 only (single fan)	Type 6FC5 348-0AA01- 0AA0 only (single fan)	Type 6FC5 348-0AA01- 0AA0 only (single fan)	Type 6FC5 348- 0AA01-0AA0 (single fan) and Type 6FC5 348-0AA02- 0AA0 (double fan)
Max. permissible supply air temperature	55° C	55° C	55° C	55° C
Fan control	Switches on at supply air temperatures of approx. 43° C and above	Switches on at supply air temperatures of approx. 43° C or above	Fan is always on	The fan switches on with temperature control (continuous operation at approx. 40° C and above)

Table 5-8 Fan/battery module for SIMOTION D4x5

The fan/battery modules are usually supplied with a backup battery.

Fan faults

Fan faults are indicated as follows:

- Entry in diagnostic buffer
- In the event of a fan failure the RDY LED flashes red/yellow at 2 Hz (SIMOTION D445/D445-1 only), which means:
 - With a fan/battery module, the single fan has failed
 - With a double fan/battery module, both fans have failed
- Indicated via system variable
- Call to the PeripheralFaultTask

For further information on the evaluation of fan faults, see Section Overview of the fan/battery module states (Page 103).

5.4.2 Fan/battery module on the D425/D435

SIMOTION D425/D435 can be operated without a fan/battery module. It is for this reason that the standard scope of delivery of the D425/D435 does not include a fan/battery module.

In the absence of a fan/battery module when the line supply is connected, a warning will be output by setting variable device.CpuDataRW.fanwarning = "NO".

If there is no fan/battery module present when the power is on, or in STOP mode, no PeripheralFaultTask will be triggered when powering up or in RUN (application case: D425/D435 is generally to be operated without a fan/battery module).

5.4.3 Fan/battery module on the D445/D445-1

A fan/battery module is always required for operation of SIMOTION D445/445-1. A corresponding module including backup battery is, therefore, included in the scope of delivery of the D445/D445-1 control unit.

- SIMOTION D445: Scope of delivery including fan/battery module (single fan)
- SIMOTION D445-1: Scope of delivery including double fan/battery module

SIMOTION D445

A fan/battery module (single fan) is always used with SIMOTION D445.

While the SIMOTION D445 is powering up, a test is performed to check whether the fan/battery module is functioning properly. If the fan/battery module is missing or faulty, the kernel is not downloaded and the RDY LED flashes red/yellow (2 Hz). Switch off the power supply and eliminate the fault. Then switch the power supply back on.

Note

If the SIMOTION D445 runs for more than a minute with a missing or faulty fan/battery module, the module will switch to the RESET state after approximately 1 minute (7-segment display shows "8"). This state can only be reset with a switch-off.

SIMOTION D445-1

For increased availability a double fan/battery module is used as standard on SIMOTION D445-1.

The double fan/battery module guarantees sufficient cooling even if just one fan is operational.

If one of the fans fails, the remaining fan continues under full load. The fan failure is signaled by the generation of an event in the PeripheralFaultTask. In this case it is strongly recommended that the double fan/battery module is replaced at the next available opportunity.

Checks are performed during power-up to determine whether the double fan/battery module on SIMOTION D445-1 is functioning correctly (i.e. at least one of the two fans is working). If a double fan/battery module is missing or faulty, the kernel is not downloaded and the RDY LED flashes red/yellow (2 Hz). Switch off the power supply and eliminate the fault. Then switch the power supply back on.

Note

If the SIMOTION D445-1 needs to be cooled (fan switches on with temperature control) and this is not possible due to a fan/battery module having been removed or being faulty, the module state will change to the RESET state after approximately 1 minute (7-segment display shows "8"). This state can only be reset with a switch-off.

If only one fan in the double fan/battery module fails, the module is still regarded as functional, although it should be replaced as soon as possible. If neither of the fans is working, the double fan/battery module is identified as defective.

5.4.4 Overview of states, fan/battery module

The states that can occur during operation are described in the following.

State	Fan 4) PeripheralFaultTask System variables 3)			
		Diagnostic buffer entry	_cpuDataRW. fanWarning	_cpuDataRW. redundantfanWar ning ²⁾ (as of V4.2)
Failure of one fan during STOP, then RUN	Single fan	PeripheralFaultTask: Is not called Diagnostic buffer entry: Fan on the module is defective	= YES ¹⁾	= NO
	Double fan	PeripheralFaultTask: Is not called Diagnostic buffer entry: Redundant fan on the module is defective	= NO	= YES
Failure of both fans during STOP, then RUN	Double fan	PeripheralFaultTask: Is not called Diagnostic buffer entry: Fan on the module is defective	= YES ¹⁾	= NO
Failure of one fan during RUN	Single fan	PeripheralFaultTask: TSI#InterruptId = _SC_PC_INTERNAL_FAILURE (= 205) TSI#details = 16#00000080 Diagnostic buffer entry:	= YES ¹⁾	= NO
	Double fan	Fan on the module is defective PeripheralFaultTask: TSI#InterruptId = _SC_PC_INTERNAL_FAILURE (= 205) TSI#details = 16#00004000 Diagnostic buffer entry: Redundant fan on the module is defective	= NO	= YES
Failure of both fans during RUN	Double fan	PeripheralFaultTask: TSI#InterruptId = _SC_PC_INTERNAL_FAILURE (= 205) TSI#details = 16#00000080 Diagnostic buffer entry: Fan on the module is defective	= YES ¹)	= NO

Table 5- 9Overview of states

¹⁾ For D445/D445-1: Module goes into the RESET state after approx. 1 minute.

²⁾ Maintenance: Replace double fan/battery module at the next available opportunity.

- ³⁾ The "YES" value must be reset to "NO" by the application.
- ⁴⁾ Single fans are only supported by SIMOTION D4x5.

Fan faults are detected if through

- A cyclic fan test (as of V4.2)
- Or when the fan is switched on

a malfunction is detected (fan does not turn or fan turns at too low a speed).

Note

If the "redundant fan" is already defective in a double fan/battery module when the system is powered-up, this is detected as a single fan/battery module depending on the type of defect (e.g. a wire breakage).

You should, therefore, also set the **.fanexisting** system variable to the "SINGLE" state to alert the personnel operating the machine to the fact that **no is redundancy available**.

Diagnostics buffer entry

The diagnostics buffer entries have the following meanings:

• Fan on the module is defective

All of the fans in a fan/battery module have failed

• There is no redundant fan available

This message only occurs in the case of modules that support double fan/battery modules with a redundant fan.

The message occurs:

- If it is only the redundant fan that has failed on a double fan/battery module or
- If a single fan/battery module is connected, but the module also supports a double fan/battery module in principle (with V4.2, this is only the case for D445-1)

Requirement/availability of a fan (as of V4.2)

System variables can be used to evaluate:

- Whether a fan is required for the operation of the device (or not)
- Whether a fan is available (or not)

System variable on the device	States	Description			
fanbattery of the structfanba	fanbattery of the structfanbattery type (the system variables are of the enumfanbattery type)				
.fannecessary	MANDATORY	Fan is required for operation of the device. .fanexisting can be used to query whether a fan is available.			
		Examples: D410, D445, D445-1, D445-2 DP/PN, D455-2 DP/PN			
	OPTIONAL	Fan can be used optionallyfanexisting can be used to query whether a fan is available.			
		Examples: D425, D435			
	NOT_MANDATORY	Fan is not required for operation of the device.			
.fanexisting	SINGLE	Single fan is available. Examples: D410, D4x5			
	REDUNDANT	Double fan is available.			
		Examples: D445-1, D445-2 DP/PN, D455-2 DP/PN			
	NOT_EXISTING	No fan available.			
		Example: D425 without optional fan			

Table 5-10 System variable fannecessary/fanexisting

References

Detailed information on setting up TaskStartInfo(#TSI) can be found in the function manual titled *SIMOTION SCOUT Basic Functions*.

5.4.5 Response to overtemperature

Operation at overtemperature reduces the module service life and can result in damage to the module.

Causes

Causes of problems in the heat dissipation of the module can be, for example:

- Violation of the maximum permissible air intake temperature
- Free convection is not ensured (clearances are not maintained, pollution, convection is prevented by cables)
- Impermissible mounting position of the module

Temperature thresholds

The internal module temperature is monitored via two module-specific temperature thresholds:

- Overtemperature is signaled when the first (lower) temperature threshold is exceeded.
- When the temperature falls below the first temperature threshold again (minus a hysteresis of approx. 5° C), "Normal temperature" is signaled.
- When the second (higher) temperature threshold is exceeded, the module shuts down in order to protect itself.

Response to overtemperature

Temperature	Response
exceeds the 1st temperature	Call of the PeripheralFaultTask:
threshold (overtemperature)	 TSI#InterruptId = _SC_PC_INTERNAL_FAILURE (= 205)
	• TSI#details = 16#0000002
	Diagnostics buffer entry:
	"Temperature exceeded in the housing"
falls below the 1st	Call of the PeripheralFaultTask:
temperature threshold minus a	 TSI#InterruptId = _SC_PC_INTERNAL_FAILURE (= 205)
	• TSI#details = 16#00000004
	Diagnostics buffer entry:
	"Temperature in the housing has returned to normal"
exceeds the 2nd temperature threshold	D445, D445-1: Module goes into permanent RESET to protect itself (7-segment display shows "8", RDY LED flashes red/yellow at 2 Hz).
	D425, D435: Module goes into the FAULT state to protect itself (7-segment display shows "F", all LEDs flicker red)

|--|

References

Detailed information on setting up TaskStartInfo(#TSI) can be found in the *SIMOTION SCOUT Basic Functions* Function Manual.

Parameter assignment / addressing

6.1 Software requirements

SIMOTION SCOUT Engineering System

To commission the SIMOTION D4x5, the SIMOTION SCOUT Engineering System must be installed on your PG/PC. Please read the information on the current DVD for "SIMOTION SCOUT."

For information on how to install SIMOTION SCOUT on your PG/PC, see the *SIMOTION SCOUT* Configuration Manual.

6.2 Creating a project and configuring communication

6.2.1 Creating a SIMOTION project and inserting a D4x5

Procedure

Proceed as follows to create a new project in SIMOTION SCOUT and insert a SIMOTION D4x5:

- 1. Select the Project > New... menu command.
- 2. In the "New Project" dialog box, assign a name and confirm with "OK."

A new folder with the name of the project will be created in the project navigator.

6.2 Creating a project and configuring communication

3. In the project navigator, double-click "Insert SIMOTION device". The "Insert SIMOTION Device" dialog box is opened:

Insert SIMOTION device		×
Device		
Device family	SIMOTION	
Device	SIMOTION D	
Device characteristic:		
Characteristic	Order no.	
D410 DP D410 PN D425 D435	6AU1 410-0AA00-0AA0 6AU1 410-0A800-0AA0 6AU1 425-0AA00-0AA0 6AU1 435-0AA00-0AA1	
D445	6AU1 445-0AA00-0AA0	
D445-1	6AU1 445-0AA00-0AA1	
D445-2 DP/PN	6AU1 445-2AD00-0AA0 6AU1 455 2AD00 0AA0	
SIMOTION version	V4.2	
SINAMICS	SINAMICS S120 Integrated	
SINAMICS version	V2.6.2	
Option module	No option module	
🔽 Open HW Config		
[OK Cancel Help	

Figure 6-1 Inserting a SIMOTION device

- 4. In the "Insert SIMOTION Device" dialog box, select the device, the device version and the SIMOTION version.
- 5. If required, make further settings:
 - SINAMICS: Select either a "SINAMICS S120 Integrated" or a "SINAMICS SM150 Integrated" (only for D445/D445-1/D455-2)
 - SINAMICS version: Select the SINAMICS Integrated version if several drive versions are available for a SIMOTION version
 - Option module: Select a CBE30 (only for D425, D435, D445 and D445-1)
- 6. The **Open HW Config** option can be used to select whether **HW Config** should be opened in the next step (e.g. in order to insert a CX32 controller extension).
- 7. Confirm the "Insert SIMOTION device" dialog box with "OK"
PROFINET version

With SCOUT V4.2

- PROFINET version V2.1 is created for SIMOTION V4.0 devices
- PROFINET version V2.2 is created for SIMOTION V4.1 and V4.2 devices

There is no selection option in the "Insert SIMOTION Device" dialog box - in exceptional circumstances (e.g. for existing systems), PROFINET version V2.1 can still be configured for V4.1 CPUs. A CPU replacement must be made in **HW Config** for this.

Please note that separate SIMOTION D firmware is available for PROFINET versions V2.1 and V2.2. The required firmware can be found on the SCOUT DVD, as well as at Internet address (http://support.automation.siemens.com/WW/view/en/31045047)

Mixed operation of the PROFINET V2.1 and V2.2 synchronization processes is not possible in a network.

SINAMICS Integrated type

The following selection options are available for SIMOTION D445/D445-1/D455-2:

- SINAMICS S120 Integrated
- SINAMICS SM150 Integrated for applications with medium-voltage converters

A separate SIMOTION D firmware is available for each of the two versions.

Version of the SINAMICS Integrated

Depending on the selected SIMOTION version, several versions are available for the SINAMICS Integrated. Please note that a separate SIMOTION D firmware is available for each version of the SINAMICS Integrated.

Additional references

For further information on IRT in accordance with PROFINET standard IEC 61158 V2.1 and V2.2, refer to the *SIMOTION Communication* System Manual.

Result

If you have not yet configured a PG/PC in your project, you can select the interface for the PG/PC connection now.

Parameter assignment / addressing

6.2 Creating a project and configuring communication

6.2.2 Configuring the PROFIBUS PG/PC interface

Requirements

The following requirements must be satisfied in order to configure the PG/PC interface:

- You have acknowledged the "Insert SIMOTION device" dialog with "OK".
- A PG/PC has not yet been configured in the project.

If these requirements have been satisfied, you can configure the interface for the PG/PC connection in the

"Interface Selection - D4x5" dialog.

Proceed as follows to configure the PROFIBUS DP interface:

Procedure

1. In the "Select Interface - D4x5" dialog box, select "PROFIBUS DP2/MPI".

Interface Selection - D435
Interface selection for PG/PC connection:
Interface parameterizations in the PG/PC:
CP5611(PROFIBUS)
OK Cancel

Figure 6-2 Selecting a PROFIBUS interface

2. Confirm with "OK".

The dialog is closed, the SIMOTION D4x5 is created in the project navigator, and **HW Config** is started automatically (if parameterized).

A PROFIBUS subnet with factory settings (1.5 MBit/s transmission rate) is created automatically.

The PG/PC is now connected to the SIMOTION D4x5 via PROFIBUS. You can configure and parameterize your system.

Note

If you do not use the factory settings, you must configure the PROFIBUS interfaces in **HW** Config.

Inserting a further SIMOTION device

If you insert a further SIMOTION device using "Insert SIMOTION device", the PG/PC interface selection dialog box is not displayed. A further SIMOTION device is automatically connected to the PG/PC via PROFIBUS and a new unique DP address is calculated (address 4, 5 ... until 125 is reached).

Additional references

Further information on the topic of "Going online" can be found:

- In the online help via the "Contents" tab at
 - "Diagnostics" > "Service and diagnostics" > "Overview of service and
 - diagnostics options" > "Part III" > "Go online"
 - "Insert device and connect to target system" > "Go online/offline"
- On the Internet at http://support.automation.siemens.com/WW/view/en/22016709 (http://support.automation.siemens.com/WW/view/en/22016709)
- In SIMOTION Utilities & Applications, FAQ "Online connections to SIMOTION devices"

SIMOTION Utilities & Applications is part of the scope of delivery of SIMOTION SCOUT.

See also

Establishing a PG/PC assignment (Page 123)

6.2.3 Configuring the Ethernet PG/PC interface

Requirement

The following requirements must be satisfied in order to configure the PG/PC interface:

- You have completed the "Insert SIMOTION device" dialog box with "OK".
- A PG/PC has not yet been configured in the project.

If these requirements have been satisfied, you can configure the interface for the PG/PC connection in the "Interface Selection - D4x5" dialog.

Proceed as follows to configure the Ethernet interface:

Procedure

1. In the "Select Interface - D4x5 dialog", select "Ethernet IE2/NET (X130)".

Interface Selection - D435
Interface selection for PG/PC connection:
Ethernet IE2/NET (X130)
Interface parameterizations in the PG/PC: <u>TCP/IP -> Broadcom NetXtreme Gig</u> TCP/IP -> NdisWanIp TCP/IP(Auto) -> Broadcom NetXtreme Gig
OK Cancel

Figure 6-3 Configuring an Ethernet Interface

2. Select the interface parameter assignment that you would like to use to go online, and confirm with "OK".

The dialog is closed, the SIMOTION D4x5 is created in the project navigator, and **HW Config** is started automatically (if parameterized).

An Ethernet subnet with factory settings is created automatically. (Factory settings, see Section Properties of Ethernet interfaces (Page 125).)

Your PG/PC is now connected to the SIMOTION D4x5 the Ethernet. You can configure and parameterize your system.

Note

If you want to change the default settings for IP addresses and the transmission rate, you must configure the Ethernet interfaces in **HW Config** and **NetPro**.

Please make sure that the PG/PC and SIMOTION D4x5 are located in the same subnet and that S7 online access has been activated (PG/PC connection must be yellow and bold in **NetPro**).

Inserting a further SIMOTION device

If you insert a further SIMOTION device using "Insert SIMOTION device", the PG/PC interface selection dialog box is not displayed. A second SIMOTION device is automatically connected to the PG/PC via Ethernet, and a new unique IP address is calculated (last digit + 1, until 255 is reached).

Additional references

Further information on the topic of "Going online" can be found:

- In the online help via the "Contents" tab at
 - "Diagnostics" ⇒ "Service and diagnostics" ⇒ "Overview of service and diagnostics options" ⇒ "Part III" ⇒ "Go online"
 - "Insert device and connect to target system" ⇒ "Go online/offline"
- On the Internet at http://support.automation.siemens.com/WW/view/en/22016709
- In SIMOTION Utilities & Applications, FAQ "Online connections to SIMOTION devices"

SIMOTION Utilities & Applications is part of the scope of delivery of SIMOTION SCOUT.

See also

Establishing a PG/PC assignment (Page 123)

6.2.4 Representation of SIMOTION D4x5 in HW Config

Once you have created a project and inserted a SIMOTION D4x5 as a module, **HW Config** opens automatically (if parameterized).

In **HW Config** the SIMOTION D4x5 units are shown with the SINAMICS Integrated and the interfaces.



Figure 6-4 Representation of SIMOTION D4x5 in HW Config

6.3 Configuring PROFIBUS DP

6.3.1 General information about communication via PROFIBUS DP

Definition of PROFIBUS DP

PROFIBUS DP is an international, open field bus standard specified in the European field bus Standard EN 50170 Part 2. PROFIBUS DP is optimized for fast, time-critical data transmissions at the field level.

Components communicating by means of PROFIBUS DP are classified as master or slave components.

Master (active bus node):

Components that represent a master on the bus define data transfer along the bus, and are therefore known as active bus nodes.

Masters components are divided into two classes:

- DP master class 1 (DPMC1):

Central master devices are thus designated, which exchange information with the slaves in specified message cycles.

Examples: SIMOTION D435, C240, P350, SIMATIC S7, etc.

- DP master class 2 (DPMC2):

These are devices for configuration, commissioning, and operator control and monitoring while the bus is in operation.

Examples: Programming devices, operator control/monitoring devices

• Slaves (passive bus nodes):

These devices may only receive, acknowledge and transfer messages to a master when so requested.

Examples: SINAMICS drives, I/O modules

Functions on PROFIBUS DP

The functional scope can differ between DP masters and DP slaves. The functional scope is different for DP-V0, DP-V1 and DP-V2.

These functions on the PROFIBUS DP are characterized by:

- Configurable equidistant isochronous PROFIBUS cycle
- Synchronization of slaves by the master by means of a global control message frame in each cycle clock
- Independent maintenance of the equidistant cycle clock by the slaves in the event of a short-term communication failure

Additional references

You will find additional information about PROFIBUS DP in the *SIMOTION Communication* System Manual.

See also

Connection rules in the PROFIBUS subnet (Page 69)

6.3.2 Operating SIMOTION D4x5 on PROFIBUS DP.

PROFIBUS DP interface (X126, X136)

SIMOTION D4x5 provides two interfaces for connection on the PROFIBUS DP. Transmission rates up to 12 Mbit/s are possible. Both interfaces can be operated isochronously.

The X136 interface can also be used as an MPI interface.

As supplied, both PROFIBUS DP interfaces are preset as a master with address 2 and a transmission rate of 1.5 Mbit/s. The PROFIBUS DP network is automatically created for this setting.

However, other settings can also be configured. This requires that you configure the network manually using **HW Config** and **NetPro**.

Note

Communication with the SINAMICS Integrated of a D4x5 or CX32 is always equidistant. Here, SIMOTION D4x5 is the master and the SINAMICS Integrated drives are slaves.

Master-slave configuration

The master/slave configuration can be used, for example, to establish hierarchical PROFIBUS networks that can be used to implement a modular machine concept.

Table 6-1 Master-slave configuration

X126	X136	Note	Actions in the application	
DP slave, isochronous	DP master,	Application synchronized to DP master (X136), application controls synchronization to DP slave (X126)	DP master/DP slave	
		Internal drive is synchronous with external cycle clock	mechanisms	
		Cycle clock DP-136 = cycle clock DP Integrated		
DP master, isochronous	DP slave, isochronous	Application synchronized to DP master (X126), application controls synchronization to DP slave (X136)	DP master/DP slave synchronization mechanisms	
		Cycle clock $DP-126 = cycle clock DP Integrated$		
DP slave, isochronous	DP master, not isochronous	Application synchronized to DP slave (X126) (can be monitored by the application)	DP slave synchronization mechanisms	
DP master, not isochronous	DP slave, isochronous	Application synchronized to DP slave (X136) (can be monitored by the application) Internal drive is synchronous with X136	DP slave synchronization mechanisms	
DP master, isochronous	DP master, isochronous	Application synchronized to DP master (X126, X136) Internal drive is synchronous with external cycle clock Cycle clock DP-126 = cycle clock DP-136 = cycle clock DP Integrated	None	
DP master, isochronous	DP master, not isochronous	Application synchronized to DP master (X126) Internal drive is synchronous with X126 Cycle clock DP-126 = cycle clock DP Integrated	None	
DP master, isochronous	DP slave, not isochronous	Application synchronized to DP master (X126) Internal drive is synchronous with X126 Cycle clock DP-126 = cycle clock DP Integrated	None	
DP master, not isochronous	DP master, isochronous	Application synchronized to DP master (X136) Internal drive is synchronous with X136 Cycle clock DP-136 = cycle clock DP Integrated	None	
DP slave, not isochronous	DP master, isochronous	Application synchronized to DP master (X136) Internal drive is synchronous with X136 Cycle clock DP-136 = cycle clock DP Integrated	None	
DP master, not isochronous	DP master, not isochronous	Application synchronized to internal drive cycle clock	None	
DP slave, not isochronous	DP master, not isochronous	Application synchronized to internal drive cycle clock	None	
DP master, not isochronous	DP slave, not isochronous	Application synchronized to internal drive cycle clock	None	
DP slave, not isochronous	DP slave, not isochronous	Application synchronized to internal drive cycle clock	None	

X126	X136	Note	Actions in the application
DP slave, isochronous	DP slave, not isochronous	Application synchronized to DP slave (X126) (can be monitored by the application) Internal drive is synchronous with X126	DP slave synchronization mechanisms
DP slave, not isochronous	DP slave, isochronous	Application synchronized to DP slave (X136) (can be monitored by the application) Internal drive is synchronous with X136	DP slave synchronization mechanisms

For detailed information about controlling synchronization across the application, see the *Basic Functions for Modular Machines* Description of Functions.

Alternatively, the X136 interface can be used as an MPI interface with a transmission rate of 19.2 kbit/s up to 12 Mbit/s.

6.3.3 Assignment of the PROFIBUS addresses in HW Config

Assigning PROFIBUS addresses

In order for all devices to communicate with each other, you must assign a PROFIBUS address to each device before connecting them:

Note

Before you assign any PROFIBUS addresses, please remember that all addresses must be unique on the PROFIBUS subnet.

You set these PROFIBUS addresses individually for each device with the PG/PC using **HW Config.** Some PROFIBUS DP slaves have a switch for this purpose.

Note

The PROFIBUS addresses set at the devices using these switches must correspond with the address settings in **HW Config**.

Recommendation for PROFIBUS addresses

Reserve PROFIBUS address "0" for a service programming device and "1" for a service HMI device, which will be connected to the subnet if required.

Recommendation for the PROFIBUS address of the SIMOTION D4x5 in case of replacement or service:

Reserve address "2" for a SIMOTION D4x5. This prevents duplicate addresses from occurring when a SIMOTION D4x5 is installed in the subnet using default settings (for example, when replacing a SIMOTION D4x5). You should therefore assign addresses greater than "2" to additional units on the subnet.

See also

Connection rules in the PROFIBUS subnet (Page 69)

6.3.4 Setting the DP cycle and system cycle clocks

All cycle clocks for SIMOTION D4x5 are based on the DP cycle of SINAMICS Integrated, which must be set in **HW Config**.

To do so, click the SINAMICS block on the integrated PROFIBUS. The "DP Slave Properties" dialog box opens. You can adjust the DP cycle of the SINAMICS Integrated on the "Isochronous mode" tab.

Table 6- 2	Range of values for SIMOTION D4x5	
------------	-----------------------------------	--

	D425	D435	D445/D445-1
DP cycle	≥ 1 ms	≥ 1 ms	≥ 0.5 ms
Grid	0.125 ms	0.125 ms	0.125 ms
Min. IPO cycle	≥ 2 ms	≥ 1 ms	≥ 0.5 ms

External DP interfaces can only be operated with a DP cycle of \geq 1 ms.

The SINAMICS Integrated always runs in isochronous mode. The DP cycle setting of the SINAMICS Integrated is displayed as the "Bus cycle clock" in the "System Cycle Clocks" dialog box. In SIMOTION SCOUT, select SIMOTION D4x5 and then select the "Set System Cycle Clocks" option in the "Target System" > "Expert" menu item.

The table below shows the possible ratio settings for the SIMOTION D4x5 system cycle clocks based on the bus cycle clock.

	Table 6-3	Ratios of system cycle clocks
--	-----------	-------------------------------

Bus cycle clock: Servo cycle clock	Servo cycle clock: IPO cycle	Servo cycle clock: IPO 2 cycle clock
1:11:4, 1:8	1:1 1:6	1:2 1:64

In addition, if the DP interfaces (DP1/DP2) are configured as equidistant master interfaces, you must set both DP cycles equal to the bus cycle clock of the SINAMICS Integrated in **HW** Config.

If the DP interfaces (DP1/DP2) are operated as the master, the system cycle clocks are obtained from an internal cycle clock of the module. Of the two DP interfaces (DP1/DP2), no more than one can also be operated as an isochronous slave interface. In this case, the system cycle clocks are obtained from the cycle clock of the slave interface.

As a result, the task system of SIMOTION and SINAMICS Integrated runs synchronously to the slave cycle clock. This assumes that a slave cycle clock exists and synchronization with the slave cycle clock has been achieved. If this is not the case, the system cycle clocks are acquired from an internal replacement clock.

	When the project is downloaded, the cycle clock configuration is downloaded to the SIMOTION D4x5 and automatically set according to the specifications.
See also	
	Setting a send cycle clock and a system cycle clock (Page 132)
	Settings for DP slave properties (Page 190)
6.3.5	Cycle clock scaling of external PROFIBUS interface to internal PROFIBUS interface
Definition	Cycle cleak appling means that an external RECEIPUS interface of the SIMOTION D4x5

Cycle clock scaling means that an external PROFIBUS interface of the SIMOTION D4x5 (X126/X136) can be operated in an integer multiple of the internal PROFIBUS interface. This reduces the CPU load, thereby allowing you to operate more axes, for example. The settings of the scaled cycle clocks for the external DP interfaces are made in **HW Config**.

Boundary conditions

The following boundary conditions are applicable to cycle clock scaling:

- An external DP interface of D4x5 is used as an isochronous slave interface. Only in this case can an integer cycle clock scaling of isochronous external DP slave interface to internal interface be specified. This is checked during compilation and an error message is output in the event of noncompliance. If the external DP interfaces are configured as equidistant interfaces but none are configured as slaves and cycle clock scaling is specified for these interfaces, an error is output during compilation.
- For SERVO, IPO, and IPO2, settings can also be made for all permissible cycle clocks. Master and slave axes can run in different IPO levels. Different cycle clocks and phase offsets are tolerated by the system.

Note

The IPO cycle clock of the IPO in which the Synchronous Operation technology object runs must be set equal to the cycle clock of the equidistant external DP slave interface.

- The second external DP interface can be operated as an equidistant master (while the other is an equidistant slave) in order to operate external drives, for example. In this case, the cycle clock must be the same as the cycle clock of the internal PROFIBUS DP. If this condition is not satisfied, an error message is output during compilation.
- One or both external DP interfaces can also be operated as non-isochronous, freerunning interfaces. In this case, there is no effect on the cycle clock settings.

Example of an application

The system consists of a synchronous master (DP master) and at least one SIMOTION D4x5 synchronous slave (DP slave). The synchronous master contains the master axis; the synchronous slave contains the following axes:

- The axes in SINAMICS Integrated of the D4x5 synchronous slave must exhibit high performance with a servo cycle clock of 1 ms and an internal DP cycle of 1 ms. This requires that the internal fast PROFIBUS DP be decoupled from the slower external PROFIBUS DP.
- The PROFIBUS DP has, for example, a cycle time of 4 ms due to the quantity framework on the bus; in all cases, its cycle time exceeds that of the cycle clock of the internal DP interface.
- The master setpoints are transferred via the DP bus. Further nodes can also be connected to the DP bus, e.g. DP drives, distributed I/Os, etc.



Figure 6-5 Example application for a cycle clock scaling

6.3.6 Creating a new PROFIBUS subnet

Introduction

SIMOTION SCOUT is used to network the SIMOTION D4x5. During the configuration process, the desired bus parameters can be set for the PROFIBUS DP interfaces.

Note

If a hardware configuration is loaded without a PROFIBUS network (DP1 or DP2) being configured on the CPU, a new PROFIBUS address that was previously set in HW Config or NETPRO will **not** be accepted by the CPU.

Requirement

You have created a project and have already inserted a SIMOTION D4x5.

Procedure

To create a new subnet, proceed as follows:

- 1. In the project navigator, double-click D4x5 to access HW Config.
- In the SIMOTION D4x5 representation, double-click the interface for which you want to create a PROFIBUS subnet.

The "DPx Properties" dialog box is opened.

- 3. Click "Properties" to show the "PROFIBUS Interface DPx" dialog box.
- 4. Click "New" to call the "Properties New PROFIBUS Subnet" dialog.
- 5. Name the new subnet and enter the properties of the new subnet, such as transmission rate, on the "Network Settings" tab.
- 6. Confirm with "OK" to accept the settings.

The new subnet is now displayed in the "Properties - PROFIBUS Interface DPx" dialog. You can now connect the new subnet to the corresponding PROFIBUS interface.

Follow the same steps to configure the second PROFIBUS interface.

A graphical representation of the PROFIBUS subnet you have created is shown in **HW** Config.

6.3.7 Modifying the data transmission rate

Introduction

You can modify the transmission rate in a PROFIBUS subnet in **HW Config** according to your requirements.

Procedure

- 1. Open the project in SIMOTION SCOUT.
- 2. Double-click the device whose PROFIBUS subnet you want to configure.

HW Config is displayed showing the settings for this device.

3. In **HW Config**, double-click in the graphical display on the PROFIBUS network whose transmission rate you want to configure.

The "Properties - DP Master System" dialog is displayed.

- 4. Click on "Properties" to display the "PROFIBUS Properties" dialog.
- Select the required transmission rate on the "Network settings" tab. If you wish to activate an equidistant bus cycle, the setting can be made under "Options".
- 6. Confirm with "OK".
- 7. Save and compile the new hardware configuration, and load it on the SIMOTION D.

Note

If you modify the transmission rate of the subnet over which you are operating the PG/PC, the PG/PC loses its active designation. You must then reconfigure it manually in **NetPro** or else you will no longer be able to go online by means of this PG/PC.

Note

PROFIBUS DP functionality is both equidistant and isochronous in nature. As such, it can guarantee that bus cycles will have exactly the same length and ensures deterministic behavior.

Applications: Connecting drives or synchronized I/O devices.

See also

Function Manual SIMOTION SCOUT Basic Functions, Chapter Isochronous I/O processing on fieldbus systems

6.3.8 Establishing a PG/PC assignment

Introduction

A PG/PC is required to create projects for a SIMOTION D4x5 and download them to the target device. The interface via which the PG/PC can be connected is polled during the automatic communication configuration. If you change these settings, you must reestablish the active designation of the PG/PC in **NetPro**. (The PG/PC connection must appear yellow and bold in **NetPro**.)

Procedure

- 1. Open the project in SIMOTION SCOUT.
- 2. Click the "Open NetPro" 🔡 button.

NetPro is accessed, and the configured network is graphically displayed. The PG/PC connection to the configured network is shown in bold in a color other than yellow.

3. Double-click the PG/PC you would like to configure.

The "Properties - PG/PC" dialog will be displayed with the "Assignment" tab in foreground.

- 4. Select the interface in the "Assigned" field and activate S7ONLINE access by clicking the appropriate checkbox.
- 5. Click "OK" to accept the settings.

The PG/PC connection to the configured network is displayed again in bold and yellow.

6. Save and compile the changes and download them to the SIMOTION D4x5.

You can now go online via the PG/PC once again.

Alternatively, you can make the assignment in SIMOTION SCOUT by clicking the "Assign PG/PC" button. This calls the properties window for PG/PC assignment, where you can modify the assignment and "activate" it (S7ONLINE access).

6.4 Configuring an Ethernet subnet

6.4 Configuring an Ethernet subnet

6.4.1 Configuring an MPI bus

6.4.1.1 Operating the X136 interface as MPI

The X136 interface can also be used as an MPI interface, for example, to connect to an external PG/PC.

When the X136 interface is used as an MPI bus, additional activation of a drive on this interface is not possible.



Figure 6-6 Connection of D4x5 (using X136) and MPI bus component

6.4.1.2 MPI parameters

MPI bus addresses and data transmission rate

Every node on the MPI bus must have a bus address in the range 0 to 31.

The data transmission rate on the MPI bus can be set to any value for the SIMOTION D4x5.

Communication attempt unsuccessful

If communication cannot be established at all, or if it cannot be established with individual nodes on the MPI bus, check the following elements:

- Is the transmission rate setting for the D4x5 used for all nodes?
- Are there any loose plug connections?
- Are all bus segments terminated properly?

Bus segments that are not terminated properly will disrupt communication on the MPI bus.

6.4.2 Properties of the Ethernet interfaces

Properties

SIMOTION D4x5 has two onboard Ethernet interfaces (X120 and X130). You can connect an Industrial Ethernet with a transmission rate of 10/100 MBit/s to the 8-pin X120 and X130 RJ45 sockets.

There is no HUB/switch functionality, i.e. message frames are not forwarded from one interface to the other. The interfaces belong to separate Ethernet subnets. SIMOTION D4x5 does not have any router functionality; it does not forward the message frames from one subnet to another.

The features of the Ethernet interfaces are as follows:

- TCP/IP timeout parameters can be set once for both interfaces.
- The transmission rate/duplex can be set individually for the two interfaces.
- The interfaces do not have autocrossing functionality.

Ethernet communication

SIMOTION D4x5 offers the following functions via Industrial Ethernet:

- Communication with STEP 7, SIMOTION SCOUT, and SIMATIC NET OPC via a PG/PC
- Communication via UDP (user datagram protocol) with other components, e.g. other D4x5 devices
- Communication with other devices via TCP/IP
- Connection of SIMATIC HMI devices such as MP27x, MP37x, or PC-based HMIs
- IT communication (SIMOTION IT DIAG, SIMOTION IT OPC XML-DA; as option: SIMOTION IT Virtual Machine)

Routing

"Services via TCP" are supported for both Ethernet interfaces. From the two Ethernet interfaces, S7 routing is possible to the

- PROFIBUS interfaces and
- PROFINET interfaces (as of V4.1 SP2).
- As well as between the Ethernet interfaces

IP routing from one Ethernet interface to another, as well as from PROFINET to the Ethernet interface and vice versa, are not possible.

You can find the MAC addresses on the nameplate located on the front of the SIMOTION D4x5.

6.4 Configuring an Ethernet subnet

See also

Further information about routing and the differences between IP and S7 routing can be found in the *Communication System Manual.*

Default Ethernet addresses

The following addresses are set on the module when shipped:

X120 (IE1/OP)

- IP address: 192.168.214.1
- Subnet mask: 255.255.255.0
- Router address: 0.0.0.0

X130 (IE2/NET)

- IP address: 169.254.11.22
- Subnet mask: 255.255.0.0
- Router address: 0.0.0.0

Note

The IP addresses 192.168.215.240 to 192.168.215.255 are reserved for internal communication in SIMOTION D4x5 (subnet mask 255.255.255.240). When configuring the external Ethernet interfaces (X120 and X130) it has to be observed that the internal addresses are not inside their network. (In IP, the network is defined as an AND link of IP address and subnet mask.)

Note

If you want to go online via Ethernet, you have to make sure that the connection from PG/PC to SIMOTION D4x5 is active. You can check this in **NetPro**. A description of how to switch a connection to active again can be found in Establishing the PG/PC assignment (Page 123).

Separate Ethernet interfaces

The two Ethernet interfaces are entirely separate and must be connected to two different networks.

The two Ethernet interfaces support:

- S7 routing (as of V4.1 SP2)
- No IP routing

SIMOTION D4x5 can, therefore, be connected to the machine user's internal company network with one interface and the second can be used, for example, by the machine manufacturer for the purpose of remote maintenance.

The Ethernet connection of the D4x5 can be configured in HW Config. Proceed as follows to do this:

- 1. Open your project.
- Open HW Config. Double-click the D4x5 module to open the "Properties D4x5" dialog box.
- 3. You can configure the Ethernet connection in the "Extended Ethernet" tab. Recommendation: Use the default setting "Automatic setting". With Automatic setting, the baud rate and duplex operating mode are automatically aligned with the connection partner.
- 4. Close the "Properties D4x5" dialog with "OK".
- 5. Save and compile the modified hardware configuration.
- 6. Load the new hardware configuration to the SIMOTION D4x5 via PROFIBUS DP/Ethernet.

For additional information, refer to the *SIMATIC NET Industrial Twisted Pair and Fiber Optic Networks* Manual. See the list of references for the order number (this is a separate document).

For further information about the cabling spectrum for Ethernet, see the *Industrial Communication IK PI* catalog.

6.4.3 Configuring Ethernet addresses in HW Config

Requirement

For configuration using Industrial Ethernet, SIMOTION D4x5 must be provided with an IP address, the subnet mask, and the router address.

Note

Only one router may be configured.

Procedure

To configure and transfer Ethernet addresses to the D4x5, proceed as follows:

- 1. Open your project.
- 2. Open **HW Config**. Double-click the interface to be configured to open the "Properties" dialog box.
- 3. On the "General" tab, click the "Properties" button of the Ethernet interface. The "Properties Ethernet Interface" dialog is displayed.
- Click the "New" button. The "New Industrial Ethernet" subnet dialog is displayed. In this dialog box, you can change the name of the new subnet or confirm the default setting with "OK".

6.4 Configuring an Ethernet subnet

- 5. The newly created Ethernet subnet is now displayed under "Subnet" in the "Properties Ethernet Interface" dialog box and must be selected.
- In this dialog box, enter the required addresses for "IP Address" and "Subnet". Under "Router", choose whether a router is to be used. If using a router, enter the router address.
- 7. Confirm this dialog box with "OK".
- 8. Close the "Properties" dialog by clicking "OK".
- 9. To configure the second Ethernet interface, open the "Properties" dialog of the second interface and repeat Steps 3 to 7.
- 10.Save and compile the modified hardware configuration.
- 11.Load the new hardware configuration to the SIMOTION D4x5 via PROFIBUS DP/Ethernet.

6.4.4 Reading out IP and MAC address

Requirement

To read out the IP and MAC addresses, the following requirements must be met:

- SIMOTION D4x5 is wired.
- You have assigned the communication parameters.
- You are online.

Procedure

The IP addresses and MAC addresses of SIMOTION D4x5 can be displayed as follows via SIMOTION SCOUT.

- 1. Right-click the module.
- 2. Select "Target Device" > "Device Diagnostics" in the context menu.

The examples below show how addresses are displayed:

X120 (IE1/OP)

- Active MAC Address: 08-00-06-73-25-3E
- IP address: 192.168.214.1
- Subnet mask: 255.255.255.0
- Standard gateway: No router used

X130 (IE2/NET)

- Active MAC Address: 08-00-06-73-25-3F
- IP address: 169.254.11.22

- Subnet mask: 255.255.0.0
- Standard gateway: No router used

As an alternative, you can set the IP address as follows:

- By selecting "Project" > "Accessible nodes" in SIMOTION SCOUT or
- By calling "Target system" > "Ethernet" > "Edit Ethernet Node..." in HW Config and browsing to "Online accessible nodes".
- Using the system function _getIpConfig

Note

The MAC address is listed on the nameplate on the front of the module.

6.5 Configuring PROFINET IO

6.5.1 General information about communication via PROFINET IO

Communication cycle

In PROFINET, the communication cycle is subdivided into different, time-specific intervals. The first interval is used for isochronous real-time communication (IRT), followed by real-time communication (RT) and standard TCP/IP communication. The bandwidth reservation for IRT ensures that RT communication and standard communication have no effect on the transmission of IRT message frames, which are important for motion-control applications.

The following figure shows how the PROFINET communication cycle is divided into isochronous real-time communication (IRT), real-time communication (RT), and standard TCP/IP communication.

6.5 Configuring PROFINET IO



Figure 6-7 PROFINET communication cycle

Isochronous realtime Ethernet

STEP 7 V5.4 and higher can be used to configure PROFINET devices supporting data exchange via isochronous real-time Ethernet (IRT). IRT message frames are transferred deterministically via planned communication paths in a defined sequence to achieve the best possible synchronism and performance.

IRT requires special network components supporting a planned data transmission.

Equidistance and Cycle Clock Synchronization

What is possible for PROFIBUS DP with isochronous bus cycles and clock synchronization, also functions for PROFINET IO.

For PROFIBUS DP, in isochronous operation all nodes are synchronized using a global control signal created by the DP master.

In PROFINET IO with IRT, a sync master generates a signal to which sync slaves synchronize themselves. Sync master and sync slaves belong to a sync domain which is assigned a name via configuration. The role of the sync master can in principle be played by an I/O controller as well as an I/O device. A sync domain has exactly one sync master.

Context: Sync domain and I/O systems

An important fact is that sync domains do not need to be limited to one PROFINET IO system: The devices of several I/O systems can be synchronized by a single sync master, provided they are connected to the same Ethernet subnet.

The following applies the other way around: An I/O system must only belong to a single sync domain.

Signal propagation delays not negligible

For the extremely exact synchronization interval, line lengths, namely the associated delay times, must be taken into consideration. You can use a topology editor to enter the properties of the lines among the ports of the switches. STEP 7 uses this data and the other configuration data to calculate the optimized process of the IRT communication and the resulting update time.

IRT runs in parallel to realtime and TCP/IP communication

Apart from IRT communication for which a defined bandwidth is reserved within the update time, RT communication and TCP/IP communication are also permitted within the update time.

With RT communication (real-time communication), the cyclic data is transferred between IO controller and IO device, though without "best possible synchronism".

With non-synchronized IO devices, data is exchanged automatically via RT communication.

Due to the fact that TCP/IP communication is also possible, other non-realtime data, e.g. configuration data or diagnostic data, can be transported.

PROFINET IO controller

Typically, the function of a PROFINET IO controller is taken on by controllers (e.g. SIMOTION C/P/D, SIMATIC S7 CPUs, ...).

The PROFINET IO controller takes on the master function for I/O data communication of the distributed field devices. The function is comparable to a PROFIBUS DP master class 1.

PROFINET IO device

Distributed field devices such as I/Os, drives (e.g. SINAMICS S120 with CBE20), or operator terminals are designated as IO devices. The function is comparable to a PROFIBUS DP slave.

Delivery condition

In the delivery condition the CBE30 does not have an IP address or a subnet mask.

6.5 Configuring PROFINET IO

6.5.2 Setting a send cycle clock and a system cycle clock

Setting the DP cycle in HW Config

All cycle clocks for SIMOTION D4x5 are based on the DP cycle of SINAMICS Integrated, which must be set in **HW Config**.

To do so, click the SINAMICS block on the integrated PROFIBUS. The "DP Slave Property" dialog box opens. You can adjust the DP cycle of the SINAMICS Integrated on the "Isochronous mode" tab. See also Additional information on configuring the SINAMICS Integrated (Page 190).

Table 6-4	Range of values for SIMOTION D4x5
-----------	-----------------------------------

	D425	D435	D445/D445-1
DP cycle	≥ 1 ms	≥ 1 ms	≥ 0.5 ms (DP internal)
			≥ 1.0 ms (DP external)
Grid	0.125 ms	0.125 ms	0.125 ms
IPO cycle	≥ 2 ms	≥ 1 ms	≥ 0.5 ms

Setting the send cycle clock in HW Config

The send cycle clock for PROFINET IO must be set in the "Domain Management" dialog in **HW Config**. To do this, select the "Edit" > "PROFINET IO" > "Domain management ..." menu command in **HW Config** and set the desired cycle clock.

The configured PROFINET send cycle clock is displayed in SIMOTION SCOUT as the "Bus Cycle Clock" in the "System Cycle Clocks - D4x5" dialog. Select SIMOTION D4x5 and then select the "Set System Cycle Clocks" option in the "Target System" > "Expert" menu item.

The PROFINET interface can be operated with a send cycle clock in the range of: $0.5 \text{ ms} \le$ send cycle clock $\le 4 \text{ ms}$. The smallest configurable grid is 0.125 ms.

If there are IO devices with RT class "RT" in a sync domain, it is only possible to set the send cycle clocks 0.5 ms, 1 ms, 2 ms and 4 ms.

Cycle clock scaling

When PROFINET is operated isochronously, the servo cycle clock must always correspond to the PROFIBUS cycle clock. The servo cycle clock and the PROFIBUS cycle clock can be scaled to the PROFINET cycle clock.

Example:

PROFINET sending cycle = 0.5 ms PROFIBUS cycle clock = position control cycle clock =1 ms

The PROFIBUS cycle clock can operated relative to the PROFINET cycle clock at a ratio of 1:1 to 1:16.

The table below shows the possible ratio settings for the SIMOTION D4x5 system cycle clocks based on the DP cycle of SINAMICS Integrated or PROFINET send cycle clock.

Table 6- 5	Ratios of sv	vstem cv	vcle clocks
	1 100 01 0	,	, 010 0100110

DP cycle/send cycle clock: Servo cycle clock	Servo cycle clock: IPO cycle clock	IPO cycle clock: IPO 2 cycle clock
1:1 1:4, 1:6, 1:8, 1:10, 1:12, 1:14, 1:16	1:1 1:6	1:2 1:64

6.5.3 Properties of PROFINET

Properties

In order to work with SIMOTION D4x5 over PROFINET IO, the Communication Board Ethernet CBE30 must be inserted into the option slot on the SIMOTION D4x5.

The PROFINET IO IRT module CBE30 supports parallel operation of:

- IRT isochronous real-time Ethernet
 - Operation of IRT I/O (e.g. ET 200S)
 - Operation of a SINAMICS S120 as an IRT device
- RT realtime Ethernet
 - Operation of RT I/O (e.g. ET 200S, ET 200pro, etc.)
 - Operation of a SINAMICS S120 as an RT device
- TCP/IP, UDP, HTTP, ... standard Ethernet services

Note

For mixed operation of IRT and RT, make sure that the IRT-compatible devices form what is referred to as an IRT domain; i.e. there must not be any non-IRT devices on the data transmission link between the IRT devices.

6.5 Configuring PROFINET IO

Additional references

You will find an overview of the specific properties of PROFINET IO on SIMOTION D4x5 in the *SIMOTION Communication* System Manual.

6.5.4 Configuration tasks

Configuration of PROFINET involves the following steps:

- 1. Insert the SIMOTION D4x5.
- 2. Insert and configure the CBE30 module in HW Config.
- 3. Create a topology: Here, you specify how the individual ports of the PROFINET IO devices are interconnected.
- 4. Configure the sync domain: Here, you specify which PROFINET nodes are sync masters (clock generator) and sync slaves.
- 5. Specify the send clock: Describes the time during which a PROFINET IO device exchanges user data with the PROFINET IO controller.
- 6. Configure the direct data exchange: With the direct data exchange you define which address areas are to be used for sending and which for receiving.

Additional references

You will find a detailed description of each configuration step in the chapter entitled "Configuring PROFINET IO with SIMOTION" of the *SIMOTION Communication* System Manual.

Commissioning (software)

7.1 Overview of commissioning

Requirements

The following requirements must be fulfilled in order to commission the SIMOTION D:

- The system has been connected and wired.
- The SIMOTION D has been switched on and powered up (STOP mode).
- SIMOTION SCOUT (with integrated STARTER) has been installed and powered up on the PG/PC.
- The communication and networks have been configured.
- You have created a project and inserted a SIMOTION D in the project.

Note

The order numbers (MLFB) of the SINAMICS S120 components must be available.

You need these order numbers when setting up a SIMOTION project to verify that the components selected from the hardware catalog in the **HW Config** application correspond to the ones used in the system.

7.1.1 Symbolic assignment / adaptation

Symbolic assignment

As of V4.2, SIMOTION supports the symbolic assignment on SINAMICS drive objects (DOs) during the configuration of technology objects (TO) and I/Os.

This simplifies the configuration of the technological relationships including the communication between controller and drive.

With the symbolic assignment:

- Only suitable assignment partners are offered in an assignment dialog box
- Communication between axis and drive is set up automatically by the engineering system and the required PROFIdrive axis message frames as well as the used addresses set up
- Message frames are extended and interconnections created automatically in the drive depending on the selected TO technology (e.g. SINAMICS Safety Integrated)

- Axis and drive configuration can initially be carried out independently of one another
- Communication connections are established automatically during the configuration of I/O variables on SINAMICS I/Os (message frames are set up automatically, the I/Os interconnected to the message frame and the addresses set up)

Apart from the symbolic assignment, no further configuration is required for the communication. As addresses no longer have to be configured, the connection is retained even with address offsets.

Note

During the configuration of drive objects (DO drive, DO encoder, ...) as well as in the Message Frame Configuration dialog box (see Section Message frame configuration (Page 216)), you can deactivate the **automatic message frame configuration** and the **automatic message frame adaptation**.

As many of the previously described advantages are lost through a deactivation, we recommend that a deactivation only be performed in exceptional circumstances.

The symbolic assignment enables an independent configuration of the axes on the SIMOTION side and the drives on the SINAMICS side.

This enables, for example:

- The PLC and motion control functions to be completely configured by a programmer even without drive know-how using technology objects (e.g. TO axis) and loaded to the device
- The drives to be separately configured and optimized by a drive expert and
- The technology objects to be symbolically assigned later to the drive objects via an interconnection dialog box

Note

The previous methods of drive, axis and I/O configuration are still available. The symbolic assignment must be deactivated for these methods.

For newly created projects, the symbolic assignment is used per default.

If projects < V4.2 are upgraded, the symbolic assignment is deactivated per default and must be activated when required.

The symbolic assignment can be activated/deactivated in SIMOTION SCOUT via the menu

"Project" > "Use symbolic assignment".

Activating the symbolic assignment later

The symbolic assignment simplifies the configuration of the technological relationships including the communication between controller and drive significantly. The names of the symbolic assignments in plain text is also advantageous for project maintenance. The symbolic assignment is therefore recommended for new projects as of V4.2 and is automatically active.

If symbolic assignment is used in a project, message frames, interconnections and addresses are automatically created by the engineering system per default.

The engineering system sets the "optimal" PROFIdrive message frames and message frame extensions for the system, makes the required BICO interconnections and determines the addresses.

It is also possible to change updated projects to symbolic assignment and this must be decided individually, as follow-up work may be required.

Extensive follow-up work is usually required, particularly for free message frame configurations (e.g. for TB30, TM15 DI/DO, TM31).

Note

If symbolic assignment is subsequently activated for a project in which message frames have already been configured and interconnected, these can be changed together with the **BICO** interconnections!

For this reason, make a backup copy of your project before activating the symbolic assignment.

Further details can be found in the SIMOTION SCOUT Basic Functions Function Manual.

Assigning a drive later

You can create an axis in SIMOTION SCOUT and assign it later to a drive. You can thus load your user program to the controller and (with the exception of the non-existent drives) test it.

Compared to a procedure with temporarily created "virtual axes", "axes without assigned drive" have the advantage that the configuration data is completely available and do not require a "virtual axis -> real axis" reconfiguration.

Adaptation

In addition to the symbolic assignment, the **automatic adaptation** facilitates the configuration of SINAMICS S110/S120 data as of SIMOTION V4.2. During power-up of the SIMOTION devices, reference variables as well as drive and encoder data of the SINAMICS S110/S120 are automatically taken over for the configuration data of the SIMOTION technology objects "TO axis" and "TO externalEncoder". This data no longer has to be entered in SIMOTION.

For further information refer to

- SIMOTION SCOUT Basic Functions Function Manual
- TO Axis Electric/Hydraulic, External Encoder Function Manual

Requirement

The symbolic assignment is supported by the TO axis, TO externalEncoder and the TO outputCam, TO camTrack and TO measuringInput. The onboard I/Os of a SIMOTION D, of a SINAMICS S110/S120 control unit as well as from a TB30 and selected terminal modules can be interconnected symbolically.

Table 7- 1	Control units that	support a	symbolic	assignment

Module	Supports symbolic assignment
SIMOTION D4x5-2	As of SIMOTION V4.2
SIMOTION D410, D4x5	As of SIMOTION V4.2
Controller extension	As of SIMOTION V4.2
• CX32-2	
• CX32	
SINAMICS S110 CU305	As of SINAMICS V4.3
SINAMICS S120	
• CU310	As of SINAMICS V2.6.2
• CU320-2	As of SINAMICS V4.3
• CU320	As of SINAMICS V2.6.2

See also

Only the drive configuration by means of symbolic assignment is described in this documentation.

The documentation of older SIMOTION versions can found on the Internet at (http://support.automation.siemens.com/WW/view/en/40211807)

For further information on the configuration of the TO axis and TO externalEncoder, refer to the *TO Axis Electric/Hydraulic, External Encoder* Function Manual.

7.1.2 Procedure when commissioning

Commissioning steps

This section shows you how to configure a system and test the configured drives and axes. The commissioning steps are listed below. The sequence is only an example and can vary depending on the supplementary conditions.

- 1. Configure the SINAMICS Integrated: You can configure the integrated drives (SINAMICS Integrated) offline or online:
 - Offline configuration: Performing D4x5 offline configuration (Page 141) and Performing CX32 offline configuration (Page 180)

For offline configuration, all of the components and their order numbers must be known.

 Online configuration: Performing D4x5 online configuration (Page 166) and Performing CX32 online configuration (Page 183)

During online configuration, you can download all of the information from the connected DRIVE-CLiQ components to your user project.

Note

The next two sections describe how a SIMOTION D4x5 including SINAMICS Integrated is configured. The described procedure also applies when CX32 controller extensions are used.

The Section "Configuring a CX32" also describes the step-by-step commissioning with a CX32 controller extension. The advantage of a step-by-step configuration is that the location and cause of an error are easier to identify.

- 2. Testing a drive with the drive control panel
- 3. Creating an axis with the axis wizard (Page 204)
- 4. Testing an axis with the axis control panel (Page 211)
- 5. Activating the infeed (line module) (Page 213)
- 6. Setting up addresses and message frames (Page 216)
- 7. Linking an additional encoder (optional) (Page 219)
- 8. Configuring drive-related I/Os (with symbolic assignment) (Page 226)
- 9. Configuring the technology (Page 230)

10. Optimizing the drive and controller (Page 238)

This section also contains additional configuration information, e.g. for vector drives, Safety Integrated, etc.

See also

Testing a drive with the drive control panel (Page 200) Creating and testing axes (Page 203)

7.1.3 Important functions for the project handling during commissioning

The following functions are very important for the project handling and commissioning:

Symbol	Function	Effect
\$ 10	Save project and compile all	Select Save project and compile all to save the entire project and compile the project data (e.g. programs) in an executable code.
<mark>₽</mark>	Connect to selected target devices	The online connection is established to the selected target devices. Under "Target system" > "Select target devices", you can set which target devices are to go online.
	Download project to target system	Downloading programs to the SIMOTION device and performing configuration for the SINAMICS Integrated and any connected CX32 modules
<u>Ś</u>	Download CPU / drive unit to target device	The configuration is only loaded to the device selected in the project tree (which means that the function needs to be performed separately for each D4x5/CX32 and each SINAMICS Integrated).
	Load CPU / drive unit to PG	The unit's configuration is only loaded to the programming device selected in the project tree (which means that the function needs to be performed separately for each D4x5/CX32 and each SINAMICS Integrated).
•3	Copy RAM to ROM	Copying from RAM to ROM is only performed for the device selected in the project tree (which means that the function needs to be performed separately for each D4x5/CX32 and each SINAMICS Integrated).

Table 7-2 Functions with their symbols

Note

Tips for going ONLINE:

In online operation, SCOUT attempts to conduct online operation with all hardware components contained in the project. This means that the time needed for going online increases.

We recommend that you make settings for SCOUT so that online operation is made only with those components currently needed. The setting can be found at "Target system > Select target devices ..." in the menu. The selection and deselection of the devices in the online state can be made via the "Connect target device" context menu on the device.

This procedure is also advantageous when the configuration of the drive unit is completed. Without going completely offline, the connection can be simply deselected via the context menu on the drive unit.

7.2 Performing offline configuration for the D4x5

7.2.1 Overview

Introduction

In the offline configuration, the project is created without all the hardware components (especially drives) being available. In this way, a SIMOTION project in the office environment can be created up to a point where a basic project specification including a program exists. You can then load the finished project to the SIMOTION D4x5 later and test it with the drives.

Requirements

- For offline configuration, all of the components and their order numbers must be known.
- You have created a project in SIMOTION SCOUT and inserted a SIMOTION D4x5 into the project in the hardware configuration.
- You have configured the communication between the SIMOTION D4x5 and the PG/PC. See Creating a project and configuring communication (Page 107).

Procedure

Offline configuration involves the following steps:

- Accessing the drive wizard (Page 142)
- Configuring components (Page 143)
- Downloading the project to SIMOTION D4x5, by means of one of the following options:
 - Download to target system (Page 161)
 - Download to the CF card (Page 163)
 - Download incl. sources and additional data (Page 164)
 - Archiving a project to the CF card (zip file) (Page 165)

Note

During offline configuration, you can also configure the available option boards (TB30) and terminal modules, e.g. TM41.

7.2.2 Accessing the drive wizard

Integrated drive

The SIMOTION D4x5 contains an integrated SINAMICS S120 drive device, which is automatically inserted along with the SIMOTION D4x5 control unit in the project navigator. The integrated drive must be operated in equidistant, isochronous mode using PROFIdrive-compliant message frame types.

The drive wizard for the integrated starter is available in SIMOTION SCOUT for configuring the integrated drive and its associated modules (e.g. SINAMICS S120 active line modules and SINAMICS S120 motor modules).

Note

Take note of all the necessary safety precautions and rules governing connections, which can be found in the latest SINAMICS S120 documentation on the SIMOTION SCOUT DVD.

Requirement

You have created a project and have already inserted a SIMOTION D4x5.

Procedure

To call the drive wizard for the configuration of your drive unit, double-click "Configure drive unit" below "D4x5" > "SINAMICS Integrated" in the project navigator.

You can configure the following components:

- Infeed (e.g. SINAMICS S120 active line module)
- Drive
- Power unit (e.g. SINAMICS S120 motor module)
- Motor
- Encoder
- Option module

7.2.3 Configuring components

Requirement

You have inserted a SIMOTION D4x5 into the project, configured the communication, and accessed the drive wizard by double-clicking "Configure Drive Unit" in the project navigator.

Note

An overview of permissible configurations, quantity structures and DRIVE-CLiQ topologies can be found in the Commissioning Manual for *SINAMICS S120*.

It should be noted, for example, that mixed operation of servo and vector **is not possible**, although mixed operation of servo and vector \mathcal{U} *i***s possible**.

Failure to comply with the rules listed in this manual will result in errors that are not output until the download is performed, rather than at the configuration stage.

Procedure

While executing the wizard you will be prompted to perform, for example, the following configuration steps:

1. In the "Option Module" dialog box, select whether you want to use a TB30 as option module.

Configuration - SINAMICS	Integrated - Option module
Option module Insert infeed Insert drive Summary	Are you using an option module (option board)?
	< <u>Back</u> Continue> Cancel Help

Figure 7-1 Selecting an option module

Note

The TB30 is displayed as a drive object below the control unit in the project navigator and can be configured there.
In the "Insert Infeed" dialog box", select whether you want to use an infeed with or without a DRIVE-CLiQ connection. If the DC link has an external supply, select "No" (no DRIVE-CLiQ connection).

✓ Option module Insert infeed	
□Insert drive □Summary	This wizard helps you to configure a drive unit with a drive and optionally with an infeed.
	Are you using a SINAMICS infeed with DRIVE-CLIQ connection in this drive unit?
	C Yes C No
	If you want to configure a number of infeeds, select the element "Insert infeed" in project navigator after completing the configuration.

Figure 7-2 Selecting an infeed with DRIVE-CLiQ connection

Note

If you have selected an uncontrolled infeed without a DRIVE-CLiQ connection, omit steps 3 to 6 below.

3. In the "Infeed Configuration" dialog box, enter a name for the drive object and select a type for your infeed (e.g. Active Infeed).

Configuration - SINAMICS_Ir	ntegrated - Infeed co	onfiguration
Option module	Configure the infeed d	rive object:
✓Insert infeed Infeed configuration Infeed	Drive object <u>n</u> ame:	Infeed
□PROFIBUS process da □Insert drive □Summary	General	
	Drive objects type:	Active infeed
	Author:	
	Version: Comment:	
	< <u>B</u> ack	<u>C</u> ontinue > <u>C</u> ancel <u>H</u> elp

Figure 7-3 Selecting the infeed type

4. Using the order number, select an infeed from the list. You can filter the information to limit the number of infeeds displayed, by using "Type", for example.

• option module	Infeed: Infeed		
✓Insert infeed	Configure the infeed comp	ionent:	
Infeed	Component <u>n</u> ame:	Infeed	
PROFIBUS process da	Supply voltage range:	380 · 480 3·phase \	/AC 💌
	Cooling method:	Internal air cooling	-
	Туре:	All	•
	Selection	,	
	Order no.	Rated power 🔺	Rated current
	6SL3130-7TE21-6Axx	16 kW	27 A
	65L313U-71E23-6Axx	36 kW	60 A
	65L3130-71E25-5AXX	55 KW	32 A
	CCL3130-71E20-04XX	120 July	134 A 200 A
1000	ECL2220.7TE22.1AAu	120 KW	200 A 210 A
	69L3330-7TE32-FAAA	160 1/1	260 A
1 1	6SL3330-7TE33-866v	235 kW	380 A
and the second se	6SL3330-7TE35-044x	300 kW	490 A
	65L3330-7TE36-144x	380 kW	605 A
	6SL3330-7TE38-444x	500 kW	840 A
	6SL3330-7TE41-0AAx	630 kW	985 A
	6SL3330-7TE41-4AAx	900 kW	1405 A

Figure 7-4 Selecting an infeed

5. You can make additional settings for the infeed in the "Infeed Drive Object - Additional Data" dialog box.

onfiguration - SINAMICS	_Integrated - Infeed - additional data
Option module Insert infeed Infeed configuration Supply Infeed - additional data Process data exchang Insert drive Summary	Infeed:Supply Line/DC-link identification at first switch-on Caution: The determined values are stored safely against power loss. If the power supply or the DC link (removal/adding of devices) of the drive line-up is subsequently changed, an identification must be performed again.
	Device connection voltage: 400 V 3-phase AC 50-60 Hz
	✓ Line filter available [41] AIM 400 V 16 kW (6SL3100-0BE21-6AB0) ▼
E	Optional Basic Line Filter booksize 400 V 16 kW (65L3000-0BE21-6DA0) Parallel connection infeed (65L3130-7TE21-6Axx - 16 kW) Number of parallel modules: Voltage sensing module available
	Number of VSMs: 0
	I Master/Slave < Back Next > Cancel Help

Figure 7-5 Making settings for the infeed

6. The communication for the control of the infeed is configured in the following dialog box. It is recommended that these settings be made automatically by the engineering system. You can also make the settings manually for the process data exchange by selecting "User-defined".



Figure 7-6 Configuring the process data exchange for the infeed

If the automatic communication setting has been selected, SIMOTION SCOUT uses PROFIdrive message frame 370 per default. This message frame is also used by the system function **_LineModule_control** to control the infeed.

You can find further information on control of the infeed in Section Activating the infeed (line module) (Page 213).

If you are using a CX32 controller extension, also refer to the information in Section Interconnecting the infeed "Operation" signal on the CX32 (Page 185).

If you activate the line module with "Free message frame configuration using BICO", you will have to connect the enabling signal via BICO. You will find information about interconnecting signals with BICO technology in the *SINAMICS S120* Commissioning Manual.

7. Now configure the drive.



Figure 7-7 Configuring a drive

✓Option module ✓Insert infeed	Configure the drive obj	ect Drive:	
✓Infeed configuration	Drive object <u>N</u> ame:	Drive_1	
Infeed drive object - ac			
PROFIBUS process da	General		
Drive properties			
Control structure	Drive objects type:	Servo 💌	
Motor		Servo	
Motor holding brake			
Lncoder	Author:		
PROFIBUS process da	Version:		
Summary	Comments		
	Commente		
AMA SE.			
42			
12			

8. Enter a name for the drive and select the type of drive object (servo or vector).

Figure 7-8 Drive properties

9. In the "Control Structure" dialog, you can select the function modules and the control type. Here, you can select "Vector" for the V/f control under "Drive objects type".

Figure 7-9 Closed-loop control structure

Configuration - SINAMICS_	Integrated - Power unit	t			
Option module Insert infeed Infeed configuration Supply Infeed - additional data	Drive: Drive_1, DDS 0 Configure the power secti	on component	:		
Process data exchang Insert drive Drive properties Control structure Power unit Motor	Connection voltage: Entwärmungsart: Type:	S10 - 720 VI Internal air c All	cooling		-
Hotor Hotaring brake Encoder Process data exchang Summary	Power unit selection: Order no. 6SL3420-2TE11-7Axx 6SL3120-1TE13-0Axx 6SL3120-2TE13-0Axx 6SL3420-1TE13-0Axx 6SL3420-1TE15-0Axx 6SL3120-1TE15-0Axx 6SL3420-2TE15-0Axx 6SL3420-2TE15-0Axx 6SL3420-2TE15-0Axx 6SL3120-1TE21-0Axx 6SL3120-1TE21-0Axx 6SL3120-2TE21-0Axx 4	Rated po 1 kW 1.6 kW 1.6 kW 1.6 kW 2.7 kW 2.7 kW 2.7 kW 2.7 kW 2.7 kW 2.8 kW 4.8 kW	Rated cur 1.7 A/1.7 A 3 A 3 A/3 A 3 A/3 A 5 A 5 A/5 A 5 A/5 A 5 A/5 A 9 A/9 A	Execution DC/AC DC/AC DC/AC DC/AC DC/AC DC/AC DC/AC DC/AC DC/AC DC/AC DC/AC	• •
	< Back	Next >	Cancel	+	lelp

10.In the "Power Unit" dialog box, use the order number to select your motor module from the list.

Figure 7-10 Selecting a power unit

11.If you have selected an infeed without a DRIVE-CLiQ connection in step 2, a message prompting you to wire the operation signal will appear. The next dialog allows you to select the source of the infeed's operation signal.



Figure 7-11 Selecting the infeed operation signal

12.In the case of double motor modules, you need to specify the terminal to which the motor is connected.

You specify the motor in the following dialog boxes:

- Either by selecting a standard motor from the list
- Or by entering the motor data
- Or by automatically identifying the motor (motor with DRIVE-CLiQ interface)

nfiguration - SINAMICS	Integrated - Motor	
Option module Inset infeed Infeed configuration Infeed drive object - ac PPDFIBUS process de Inset drive Onive properties Onivo structure Onive properties	Drive: Drive_1, DDS Configure the motor: Motor <u>p</u> ame:	O, MDS 0 Motor Motor with DRIVE-CLiQ interface F Read outmotor again Select standard motor from list C Enter motor data
Molect Molect Molect Encoder ProFIBUS process de Surmary Molect ProFIBUS process de Surmary Molect ProFIBUS process de Surmary	<u>M</u> otor type:	No motor selected ▼ No motor selected IPH2 induction motor IPH4 induction motor IPH4 induction motor IPH5 synchronous motor IPH5 synchronous motor IPH5 synchronous motor IPH5 synchronous motor IPM6 synchronous motor IPM6 synchronous motor IPM5 synchronous motor IPM6 synchronous motor IPM1 synchronous motor IPM3 synchronous motor IPM3 synchronous motor IPM3 synchronous motor
	< Back	<u>Continue ></u> <u>Cancel</u> <u>H</u> elp

Figure 7-12 Selecting a drive (1)

Note

Motors with DRIVE-CLiQ interface have an integrated encoder evaluation that is connected to the motor module via a fully digital communication interface (DRIVE-CLiQ).

In this way, motor encoder and temperature signals as well as electronic rating plate data, such as unique ID numbers, rated data (voltage, current, torque) can be transferred directly to the control unit.

✓Insert infeed	Drive: Drive_1, DDS 0,1	MDS U			
✓Infeed configuration	Configure the motor:				
✓Infeed ✓Infeed drive object - ac	Motor <u>n</u> ame:	fotor			
PROFIBUS process da	C	Motor with DRIV	'E-CLiQ inter	face	
✓ Insert drive		🔲 Read out	motor again		
Control structure		Select standard	motor from li:	st	
Power unit	C	Enter motor <u>d</u> ata			
Motor	Motor type:	FK6 synchronous	motor		•
Summary	Motor selection:				
	Order no.	Rated sp	Rated tor	Rated cur	
	1FK6032-xAK7x-xxxx	6000 U/min	0.8 Nm	1.5 A	
	1FK6033-xAK7x-xxxx	6000 U/min	0.9 Nm	1.5 A	
▲	1FK6040-xAK7x-xxxx	6000 U/min	0.8 Nm	1.75 A	_
	1FK6042-xAF7x-xxxx	3000 U/min	2.6 Nm	2.4 A	
	1FK6U43-xAH7x-xxxx	4500 U/min	2.6 Nm	4 A	
	1FK6U43-xAK/x-xxxx	6000 U/min	2 Nm	4.4 A	
No. of Concession, Name	1FK6U44-xAF7x-xxxx	3000 07min	3.5 Nm	4A 40.4	
and the second s	1FK6044-XAH7X-XXXX	4500 07min	3 INM	4.9 A	
9 000	1FK6060-XAF7X-XXXX	3000 U/min 2000 U/win	4 IND E 4 Nov	3.1 A	
	1FK6061-xAF7X-XXXX	3000 07min 4500 U2-in	0.4 Nm 4 0 Nm	5.3 A	
	1EV C0C2	4000 07min 2000 U /min	4.5 Mm	47A	
	1EK 6063-WAR 7 WARA	2000 U/min	9 Nm	754	
- dise	1FK 6064-v6H7v-vvvv	4500 U/min	5 Nm	7.5 A	_
	111120907 001110 00000	4000 0711111		10.	-
	15V COOD A E 7	2000 112-44	IT II Kime	E 11 0	

Figure 7-13 Selecting a drive (2)

- Configuration SINAMICS_Integrated Motor holding brake Drive: Drive_1, DDS 0 Option module Insert infeed ✓ Infeed configuration Motor holding brake activation: Supply 🖌 Use a motor holding brake (internal or external) 🖌 Infeed - additional data Do not use a motor holding brake 🖌 Process data exchang Motors with internal motor holding brake: Insert drive Drive properties 1FK7xxx-xxxxx-xxBx 1FK7xxx-xxxxx-xxHx Control structure Power unit Power unit connection 🖌 Motor Motor H Encoder Process data exchang Motors without internal motor holding brake:] Summary 1FK7xxx-xxxxx-xxAx • Þ 1FK7xxx-xxxxx-xxGx Holding brake configuration: [0] No motor holding brake being used -Extended brake control < Back Next > Cancel Help
- 13.Selecting a motor holding brake (if available).

Figure 7-14 Selecting a motor holding brake.

14.If you are using a motor that is not equipped with a DRIVE-CLiQ interface, select the encoder order number in the "Encoder Selection via Motor Order Number" dialog box.

Encoder Selection via N	1otor Order Number		×
The encoders listed below Select the relevant encod	w are available for the selecte der via the motor order numbe	ed listed motor. er.	
Order no.	Encoder type	Resolution	Code number
1FK7xxx-xxxxx-xAxx	Sin/cos incremental C/D	2048 S/R	2001
1FK7xxx-xxxxxx-xExx	EnDat absolute	2048 S/R	2051
1FK7xxx-xxxxx-xGxx	EnDat absolute	32 S/R	2052
1FK7xxx-xxxxx-xHxx	EnDat absolute	512 S/R	2053
1FK7xxx-xxxxx-xJxx	EnDat absolute	16 S/R	2054
1FK7xxx-xxxxx-xSxx	Resolver	n-speed	1004
1FK7xxx-xxxxx-xTxx	Resolver	1-speed	1001
•			
OK Car	ncel		

Figure 7-15 Selecting a motor encoder (1)

nfiguration - SINAMICS_I	Integrated - Encoder
Option module	Drive: Drive_1, DDS 0, MDS 0
 ✓ Infeed configuration ✓ Supply 	Which encoder do you want to use?
 Infeed - additional data Process data exchang 	Encoder 1 Encoder 2 Encoder 3
✓ Insert drive	Encoder 1
Control structure	Encoder evaluation: SM_1
Power unit connection	Encoder name: Encoder_1
✓ Motor ✓ Motor holding brake	C Encoder with DRIVE-CLiQ interface
Encoder Process data exchang	Select standard
Summary	encoder from list
	C Enter data Encoder data
	Encoder type Code number
	DRIVE-CLiQ encoder AS20, singleturn 202 DRIVE-CLiQ encoder AM20, multiturn 4096 204 DRIVE-CLiQ encoder AS24, singleturn 242
0	DRIVE-CLiQ encoder AM24, multiturn 4096 244 Resolver 1 speed 1001
and	Resolver 2 speed 1002 Besolver 3 speed 1003
No. A	Resolver 4 speed 1004
	2048, 1 Vpp, A/B C/D R 2001
	Details
	<back next=""> Cancel Help</back>

Figure 7-16 Selecting a motor encoder (2)

Note

If required, you can configure a second or third encoder in the "Encoder" dialog box. You can transfer a maximum of two encoder values to SIMOTION via the axis message frame.

In the case of motors with a DRIVE-CLiQ interface, the motor encoder is identified automatically. It is not necessary to enter encoder data in such cases (the dialog for selecting Encoder 1 is grayed out and, therefore, inactive).

15. The communication for the control of the SINAMICS drive is configured in the following dialog box.

It is recommended that these settings be made automatically by the engineering system. You can also make the settings manually for the process data exchange by selecting "User-defined".

Information about the manual setting options can be found in the online help and in the manuals for the SINAMICS S120 drive system.



Figure 7-17 Configuring the process data exchange

After you have configured all of the settings in the drive wizard, the "Summary" dialog displays a list of all settings. You can accept these settings with "Finish" or edit the configuration of individual components using the "Back" button.

Commissioning (software)

7.2 Performing offline configuration for the D4x5



Figure 7-18 Finishing the drive

Result

The configured drive will appear in the project navigator.



Figure 7-19 Representation in the project navigator

You will find an overview of the configured SINAMICS components under "SINAMICS_Integrated" > "Topology".

SINAMICS_Integrated - Topology
Topology Project set Set Actual Comparison
Topology tree
Control_Unit (1)
0-0 m Infeed.Infeed (2)
Drive_1.Power_unit (3)
T- Free
210 Drive_1.5M_to_Encoder_1 (4)
2- Free
T- Free
2- Free
3- Free
Free Free
Component depot
Free
Update topology Close Help

Figure 7-20 Displaying the topology

See also

If you configure the message frames for the infeed and drive manually, you can find detailed information on the respective message frame types in the following:

- Motion Control, TO Axis Electric/Hydraulic, External Encoder Function Manual
- SINAMICS S120 Function Manual

7.2.4 Downloading a project into the target system

Requirement

You have configured the hardware. You now need to download the hardware configuration and the entire SIMOTION project to the target system.

If you have not yet configured your SIMOTION project (i.e. created ST programs, assigned execution levels, etc.), complete this step first.

Note

You can only perform a project download in the STOP mode and for all target devices with which you are ONLINE. You cannot download to drives that cannot be configured in SCOUT, e.g MASTERDRIVES. The project data is loaded to all the devices connected ONLINE and their subordinate drive units (provided these are selected in the Target Device Selection dialog box). This can only be done in STOP mode.

Procedure

- 1. Save and compile the project.
- 2. Go online.
- 3. To load the project, perform "Download project to target system". The data must also be saved on the CF card to ensure that the project is retained in the event of a power failure. The following options are available:
 - Perform the "Copy RAM to ROM..." function manually on the D4x5-and all drives (SINAMICS Integrated, CX32, etc.).
 - In the "Download to Target System" dialog box, select the option "After loading, copy RAM to ROM". You can change the default setting for this dialog box in "Options" > "Settings" > "Download".

Download t	o target system (WWB5:824)	x
į	The data will be downloaded to the target system. This can take several minutes!	
	 Store additional data on the target device Including DCC chart data After loading, copy RAM to ROM 	
	Start download? Additional CPU options >>	
	Yes No Help	

Figure 7-21 Download project to target system

The SIMOTION project is downloaded to the target system and the online connection to the drives established automatically.

Note

Online access to the drives is not possible if HW Config is not loaded at the time you initially connect to the target system.

Download HW Config first to enable online access to the drives.

Note

If you have deselected the "Drives" option under "Tools" > "Settings" > "Download" in SIMOTION SCOUT, you must download the configuration separately to each drive (SINAMICS Integrated, CX32, etc.).

To do this, select the drive (e.g. SINAMICS Integrated) in the project navigator and perform "Download CPU / drive unit to target device". For fast operation, we recommend that, in principle, the drives be deselected and a download only performed when required.

To save the parameter calculations of the drive in the project, perform "Target device" ⇒
 "Load CPU / drive unit to PG" for each drive.

7.2.5 Downloading a project to the CF card

Requirement

Loading a project created offline to the CF card has the advantage of being faster than a download.

It should be noted, however, that the first system power-up will take longer, as the SINAMICS Integrated and CX32 controller extension will perform one-off parameter calculations. These are automatically backed up on the CF card.

Note

In order to save the project data via the PG/PC, you need a CF card adapter in which you can insert the CF card. The CF card must be displayed as a removable storage device with any drive letter in Windows Explorer.

If the CF card is not displayed, check the CF card adapter and contact the hotline if necessary.

Procedure

You can use a card adapter to write the entire project to the CF card, even in offline mode. In SIMOTION SCOUT, you can call the "Load into file system" function in the context menu of the SIMOTION device.

- 1. Save and compile the project.
- 2. Switch the SIMOTION D4x5 off.
- 3. Remove the CF card and insert it into a card adapter. The card adapter must be connected to a PG/PC.
- In the SCOUT project, select the SIMOTION D4x5 device you wish to download to the CF card.
- 5. Click "Load into file system" in the context menu. A dialog opens.
- 6. In the "Load into file system" dialog, select the "Save normally" option and click the "Select target" button.
- 7. Select the target drive.
- 8. Confirm your entries with "OK". The data is written to the CF card.

- 9. Remove the CF card and insert it into the slot on the D4x5.
- 10.Switch the D4x5 on. The D4x5 powers up with the downloaded project.

Note

The components' firmware is upgraded or downgraded automatically based on the FW version on the CF card and the FW version on the SINAMICS components (DRIVE-CLiQ components, CBE30, PM340, etc.).

The update can take several minutes and its progress is tracked by corresponding messages appearing in the alarm window of SIMOTION SCOUT.

A firmware update on DRIVE-CLiQ components is indicated by the RDY LED flashing red and green:

- FW update running: RDY LED flashes slowly (0.5 Hz)
- FW update complete: RDY LED flashes quickly (2 Hz)

These flashing patterns are also displayed on the yellow RDY LED on the SIMOTION D/CX32, and indicate that a FW update has been carried out on components connected to the SIMOTION D/CX32 or that all components have completed the FW update.

Go offline once all the FW updates have been completed. POWER ON the upgraded/downgraded components.

7.2.6 Loading a project, including sources and additional data

Overview

As of SIMOTION V4.1 SP2, it is possible to load additional data (e.g. sources) to the target device when saving a project to the CF card or downloading to the D4x5. This data is required for:

- Online object comparison (e.g. additional properties)
- Various detailed comparisons (e.g. ST source file comparison)
- Synchronization with online objects

In order to be able to load a project's sources and additional data to the PG, this must be specified in the project under "Options" \Rightarrow "Settings" \Rightarrow "Download" \Rightarrow "Store additional data on the target device".

If the sources and additional data have been saved on the CF card, the option described in the sections that follow becomes available.

Project comparison

You intend to carry out servicing work on a commissioned system and have brought a project on your PC/PG. This project is not consistent with the project on the D4x5 in the system. In order to analyze the differences, perform an object comparison via "Start object comparison".

You have the following options in terms of re-establishing consistency:

- In the object comparison, it is possible to establish consistency for sources and technology objects on an object-granular basis.
- Consistency can be established for the entire control unit by loading from the CF card via "Target system" ⇒ "Load" ⇒ "Load CPU / drive unit to PG...".

Additional references

Detailed information on "loading data to the target device" can be found in the *SIMOTION SCOUT Basic Functions* Function Manual.

7.2.7 Archiving a project to the CompactFlash Card (zip file)

Procedure

In SIMOTION SCOUT, you can save the project as a *.zip file to the CF card.

Proceed as follows to archive the SIMOTION project on the CF card:

- 1. Open SIMOTION SCOUT and select the "Project" > "Archive" menu command.
- 2. In the "Archive" dialog, select the SIMOTION project and save it to your drive (PG/PC).
- 3. Open the project.
- 4. Go online with the SIMOTION D4x5.
- In the project navigator, select the SIMOTION D4x5 and select the "Target system" ⇒ "Load" ⇒ "Save archive project on card..." menu command.
- 6. In the dialog that is displayed, select the project and click "Open". This saves the project to the CF card as Project.zip in the directory USER\SIMOTION\HMI\PRJLOG.

Note

If you want to load the current project from the card, select the "Target system" \Rightarrow "Copy archived project from card to PG/PC..." menu command.

Prerequisite is that you have backed up the project with "Save archive project on card..." each time a change was made.

Additional references

Detailed information on loading data to the target device can be found in the *SIMOTION SCOUT Basic Functions* Function Manual.

7.3 Performing online configuration for D4x5

7.3.1 Overview

Introduction

You can configure the plant in online mode after having completed its wiring. You can load the data of SINAMICS components connected via DRIVE-CLiQ to your PG/PC using the "Automatic configuration" function. However, this is only possible for initial commissioning.

Note

Components without DRIVE-CLiQ connection must be edited in offline mode. You may need to edit DRIVE-CLiQ components which were detected in the course of automatic configuration (for example, adding encoder data if using SMC modules).

Requirements

- Your system has been mounted and wired.
- You have created a project in SIMOTION SCOUT and inserted a SIMOTION D4x5 in the project.
- You have configured the communication between the SIMOTION D4x5 and the PG/PC. See Creating a project and configuring communication (Page 107).

Procedure

Online configuration involves the following steps:

- Establishing an online connection (Page 167)
- Starting the automatic configuration (Page 168)
- Editing SINAMICS components (Page 172)
- Downloading a project to SIMOTION D4x5 (Page 172)

7.3.2 Establish an online connection

Requirement

You have created a project.

Procedure

This section outlines the procedure for initial commissioning.

To perform online configuration, you must establish an online connection to the SIMOTION D4x5. In this case, no connection can yet be established to the SINAMICS Integrated. An appropriate message is output. Once the hardware configuration has been loaded to the target device, an online connection to the SINAMICS Integrated is established automatically. Proceed as follows:

- 1. Save and compile the project.
- 2. Establish an online connection.
- 3. Highlight the SIMOTION D4x5 device in the project navigator.
- Use the "Download CPU / drive unit to target device" function to download the SIMOTION D4x5 to the target device. The connection to the SINAMICS Integrated is automatically established.

Result

Now you can perform the automatic configuration on the SINAMICS Integrated. See Section Starting the automatic configuration (Page 168).

Additional references

Further information about establishing an online connection to the programming device/PC can be found in the following documentation:

- SIMOTION SCOUT Configuration Manual
- SIMOTION SCOUT Online Help
- SIMOTION Utilities & Applications FAQs SIMOTION Utilities & Applications is part of the scope of delivery of SIMOTION SCOUT.

Commissioning (software)

7.3 Performing online configuration for D4x5

7.3.3 Starting the automatic configuration

Requirements

You have established the online connection to the SINAMICS Integrated.

Procedure

1. In the project navigator, open the "Automatic Configuration" dialog box by selecting "SINAMICS Integrated" > "Automatic Configuration".

Automa	Automatic Configuration		
<u>.</u>	Configure drive unit automatically The DRIVE-CLiQ topology is determined and the electronic type plates are read out. The data is then loaded to the PG and replaces the configuration in the project. "Restore factory settings" is performed first for the target device Status of the drive unit:		
	Running operation:	Waiting for START	
	Configure	Cancel	

Figure 7-22 Starting the automatic configuration

- 2. Click the "Configure" button.
- 3. If the drive unit is not in the "Initial commissioning" state, the factory settings are restored after acknowledging a prompt.

4. The drive object types can now be selected via a further dialog box.

tomatic Comm				
	issioning			
During the automatic commissioning, components have been found that cannot be clearly assigned to a drive object type. Please select the drive object type that is to be created for the components.				
)efault setting for	all components: Serve	→▼		
Component	Drive Object Type	Identification		
Drive 1	Servo	Identification via LED		
Drive 2	Servo	 Identification via LED 		

Figure 7-23 Selecting the drive object type

- 5. Select whether a servo- or vector-type drive object is to be used.
- 6. Click "Create" to start the automatic configuration. As soon as automatic configuration has been run through, an upload operation (Load to PG) is performed automatically.

Note

The components' firmware is upgraded or downgraded automatically based on the FW version on the CF card and the FW version on the SINAMICS components (DRIVE-CLiQ components, CBE30, PM340, etc.).

The upgrade can take several minutes and its progress is tracked by corresponding messages appearing in the alarm window of SIMOTION SCOUT.

A firmware upgrade on DRIVE-CLiQ components is indicated by the RDY LED flashing red and green:

- FW update running: RDY LED flashes slowly (0.5 Hz)
- FW update complete: RDY LED flashes quickly (2 Hz)

These flashing patterns are also displayed on the yellow RDY LED on the SIMOTION D/CX32, and indicate that a FW update has been carried out on components connected to the SIMOTION D/CX32 or that all components have completed the FW update.

Go offline once all the FW updates have been completed. POWER ON the upgraded/downgraded components.

7. At the end of the automatic configuration, you are prompted whether you want to "Go OFFLINE" or "Stay ONLINE" with the drive unit.

Automatic Configuration	×
Automatic configuration completed	
Bitte denken Sie daran, zusätzlich die Projektierung der Motoren an folgenden Antrie bzw. der Einspeisung abzuschließen:	ben
SERVO_03	
Gehen Sie dazu offline und durchlaufen Sie den jeweiligen Assistenten. Falls eine Einspeisung vorhanden ist, konfigurieren Sie weitere Eigenschaften (z.B. Netzfilter).	
Do you want to go OFFLINE (only with this drive unit)?	
Go OFFLINE Stay ONLINE	

Figure 7-24 Automatic configuration completed

8. Execute the "Copy RAM to ROM ..." function on the D4x5 and the SINAMICS Integrated. This saves the project on the CF card, meaning that it does not need to be reloaded after switching off and on again.

Result

The DRIVE-CLiQ components loaded to the user project by means of automatic configuration are displayed in the project navigator.



Figure 7-25 Project navigator with real configuration

You must then

- If required, reconfigure SINAMICS components (e.g. components without a DRIVE-CLiQ interface, such as an encoder connected via SMCxx).
- Assign the "TO axis" to "Drive"

See also

Restoring the default settings of SINAMICS Integrated (Page 253)

7.3.4 Editing SINAMICS components

Requirement

- You have loaded all connected DRIVE-CLiQ components to your user project.
- You have shut down the connection to the target system (offline mode).

Procedure

You can now adapt your component to the application.

Run through the wizard for all the DRIVE-CLiQ components to be adapted and perform the required reconfigurations.

This procedure conforms to the description Performing offline configuration for the D4x5 (Page 141).

The amount of editing work involved depends on the components used. For example, in the case of a motor with a DRIVE-CLiQ interface, the motor and encoder type are identified automatically.

7.3.5 Downloading a project to SIMOTION D4x5

After you have performed the reconfigurations, you must download the configuration to the SIMOTION D4x5 (incl. SINAMICS Integrated).

- 1. Save and compile the project.
- 2. Go online.

- 3. To load the project, perform "Download project to target system". The data must also be saved on the CF card to ensure that the project is retained in the event of a power failure. The following options are available:
 - Perform the "Copy RAM to ROM..." function manually on the D4x5-and all drives (SINAMICS Integrated, CX32, etc.).
 - In the "Download to Target System" dialog box, select the option "After loading, copy RAM to ROM". You can change the default setting for this dialog box in "Options" ⇒ "Settings" ⇒ "Download".

Download t	o target system (WWB5:824)	x
į	The data will be downloaded to the target system. This can take several minutes!	
	 Store additional data on the target device Including DCC chart data After loading, copy RAM to RDM 	
	Start download?Additional CPU options >>	
	Yes No Help	

Figure 7-26 Download project to target system

The SIMOTION project is downloaded to the target system and the online connection to the drives established automatically.

Note

Online access to the drives is not possible if **HW Config** is not loaded at the time you initially connect to the target system.

Download **HW Config** first to enable online access to the drives.

Note

If you have deselected the "Drives" option under "Tools" > "Settings" > "Download" in SIMOTION SCOUT, you must download the configuration separately to each drive (SINAMICS Integrated, CX32, etc.).

To do this, select the drive (e.g. SINAMICS Integrated) in the project navigator and perform "Download CPU / drive unit to target device". For fast operation, we recommend that, in principle, the drives be deselected and a download only performed when required.

4. To save the parameter calculations of the drive in the project, perform "Target device" ⇒ "Load CPU / drive unit to PG" for each drive.

The drive has been assigned parameters and commissioned. You can now test the drive via the drive control panel.

See also

Optimizing drive and closed-loop controller (Page 238)

7.4 Configuring a CX32

7.4.1 Overview

The SIMOTION CX32 controller extension is a component in SINAMICS S120 booksize format and supports scaling of the drive-end computing performance of the SIMOTION D435 and D445/D445-1 control units. Each CX32 can operate up to six additional servo, four vector or eight *VI* drives.

The CX32 controller extension offers the following advantages:

- At only 25 mm wide, the CX32 is extremely compact.
- Since the CX32 is connected to the SIMOTION D435/D445/D445-1 via DRIVE-CLiQ, high-performance isochronous closed-loop control of the drives is possible without the need for additional modules.
- The communications interfaces on the SIMOTION D435/D445/D445-1 remain available for other connections.
- As the data for the CX32 is stored exclusively on the SIMOTION D435/D445/D445-1 CF card, no action needs to be taken if the module is replaced.
- The "Control operation" signal from an infeed connected to the SIMOTION D4x5 is particularly easy to interconnect to the drives of a CX32.

SIMOTION CX32 is automatically also updated when the SIMOTION D4x5 is updated

7.4.2 Basic principles of the CX32

Basic principles of the CX32

Each CX32 is entered as a separate DRIVE object in the project navigator on the level of SINAMICS Integrated. As a general principle, a CX32 can be configured the same way as SINAMICS Integrated.

Communication

With CX32 (as with the SINAMICS Integrated) communication takes place via PROFIBUS Integrated, although the SINAMICS Integrated is also used for routing to the relevant CX32 via DRIVE-CLiQ.

Communication with the CX32 runs in the same cycle (same DP cycle) as communication with the SINAMICS Integrated. Direct communication between two CX32 modules or the SINAMICS Integrated and CX32 is not possible Exception: Interconnection of the infeed's "Operation" signal for the CX32. Section Interconnecting the infeed "Operation" signal on the CX32 (Page 185) describes how to interconnect the "Operation" signal.

Power-up

The CX32 does not require its own CF card. Both the firmware and parameterization are stored centrally on the SIMOTION D CF card. This means that the CX32 modules only power up after the SINAMICS Integrated has done so. As a result, it usually takes longer for the system to power up than if a SIMOTION D were being used with just one SINAMICS Integrated.

Copying from RAM to ROM also takes longer, as the devices perform this function one after the other.

Please refer to Section CX32 configuring tools on how to detect if a power-up has been completed during CX32 power-up (Page 184).

Online functions

Since the SINAMICS Integrated routes online functions to the CX32 via DRIVE-CLiQ, operational performance is reduced by up to a factor of 2 in the case of online functions (e.g. parameter modifications or downloads) compared to a similar installation with CU320.

Requirements for commissioning

In order to commission a SIMOTION D with CX32, all drive components which were configured offline must also be present and connected to the correct DRIVE-CLiQ port.

Only when there are no topology errors

- Will the download be successful (where a project created offline is loaded to the target system)
- · Will the system startup be successful
- Can the CX32 modules be accessed "online"

Loading the SINAMICS Integrated

If the SINAMICS Integrated of a SIMOTION D is loaded, the connected CX32 controller extensions go offline as a result of reinitialization.

7.4.3 Preparing for configuration

Preparing for configuration

The following measures are required to enable online or offline configuration of a CX32.

- 1. Create a project and insert a SIMOTION D435 or D445/D445-1 (in this example, a D435 is used).
- 2. Double-click "D4x5" in the project navigator. The HW Config is displayed.
- 3. In the hardware catalog, open the "PROFIBUS DP" entry and select "SINAMICS".
- 4. Drag a SINAMICS CX32 to the PROFIBUS Integrated master system of the SIMOTION D module. The mouse pointer permits the CX32 to be inserted on the master system only. The "DP Slave Properties" screen form is displayed with the PROFIBUS address. The PROFIBUS address is assigned automatically. See the table below. Select the relevant DRIVE-CLiQ port by selecting the relevant PROFIBUS address (in this example, PROFIBUS address 13).



Figure 7-27 Inserting CX32 in HW Config

5. Click "OK" to confirm your settings.

The CX32 is displayed in the project navigator and can be configured there in the same way as a SINAMICS Integrated.

In **HW Config**, the respective PROFIBUS address of the CX32 is represented in parentheses in the module icon.



Figure 7-28 CX32 in the project navigator

- 6. Save the project.
- 7. A CX32 is configured in the same way as a SINAMICS Integrated on a SIMOTION D4x5.

Using an offline configuration

Where configuration is being performed offline, configure the drive components (infeed, motor modules, motor, encoder, terminal modules, etc.) by running through the drive wizard for the SINAMICS Integrated or CX32. After you have done this, carry out commissioning.

Automatic commissioning

With automatic commissioning, the drive components that are physically connected to a SIMOTION D are determined online. This means you only need a D4x5 project with the CX32 modules configured in **HW Config**.

Assigning DRIVE-CLiQ ports to PROFIBUS addresses

Table 7- 3	CX32 PROFIBUS addresses (PROFIBUS	Integrated)
		integrated)

DRIVE-CLiQ port	PROFIBUS address (PROFIBUS Integrated)
X105 (D445/D445-1 only)	15
X104 (D445/D445-1 only)	14
X103 (D435/D445/D445-1)	13
X102 (D435/D445/D445-1)	12
X101 (D435/D445/D445-1)	11
X100 (D435/D445/D445-1)	10

See also

Configuring components (Page 143) Performing CX32 configuration online (Page 183) Performing CX32 configuration offline (Page 180)

7.4.4 Displaying the topology

Topology of the SINAMICS Integrated

Because the CX32 is connected to the SINAMICS Integrated of a SIMOTION D4x5 via DRIVE-CLiQ, it is also represented in the topology tree of SINAMICS Integrated.

All inserted CX32s are represented in the SINAMICS Integrated topology without their subtopology.

SINAMICS_Integrated - Topology					_	
	Topology	Project set	<u>S</u> et	Actual	Comparison	~
Topology tree					-	
Control_Unit (1)						
Infeed.Infeed (2)						- 1
[] [Drive_1]Drive_2].Pow	er_unit, Powe	r_unit (3 4)				- 1
	ive_3].Power_	unit, Power_unit (1	1 12)			
	ree vive 4 SM to	Encoder 1 (18)				- 1
	rive_4.5M_to	Encoder 1 (15)				- 1
2-0 - Drive_1.5M	_to_Encoder_1	(5)				- 1
3-0 2.5M	_to_Encoder_1	(8)				- 1
The Free						
						- 1
Free Free						
Component depot						
Free						- 1
Filter: All DRIVE-CLiQ + option slot						
		U	pdate topology	Clo	ise Hel	P

Figure 7-29 SINAMICS Integrated topology

CX32 topology

The CX32 topology represents the DRIVE-CLiQ port required for connection to the SINAMICS Integrated. The drive objects connected to the CX32 are also displayed.

SIMOTION_CX32_1 - Topology
Topology Project set Set Actual Comparison
Topology tree
Control_Unit (1)
THE Free 2HO P Drive_1.SM_to_Encoder_1 (4)
Free
Free
Component depot
Free
Eilter: All DRIVE-CLiQ + option slot
Update topology Close Help

Figure 7-30 CX32 topology

Note

Topology errors may make it impossible to perform a download, power up a system, or access a CX32 online.

See also

CX32 diagnostics (Page 187)

7.4.5 Performing CX32 configuration offline

Options

The following options are available for commissioning a project created offline:

- Loading a project created offline to the target system
- Loading a project created offline to the CF card
7.4.5.1 Loading a project created offline to the target system

Requirement

- Your project, including all SINAMICS Integrated and CX32 drive components, must have been configured already (see Preparing for configuration (Page 176)).
- The actual topology must correspond with the reference topology.

Procedure

- 1. Deselect all target devices, with the exception of the SIMOTION D4x5, using the "Target system" > "Select target devices" menu command in SCOUT.
- 2. Go online with the D4x5 by clicking "Connect to selected target devices".
- 3. Select the D4x5 in the project tree. Load the configuration to the SIMOTION D4x5 with "Download CPU / drive unit to target device".
- 4. Copy the configuration from RAM to ROM with "Copy RAM to ROM".
- 5. Select "Connect target device" in the SINAMICS Integrated context menu. You will then be connected to the SINAMICS Integrated online.
- 6. Load the parameterization by selecting "Target device" > "Download" in the SINAMICS Integrated context menu.
- 7. Copy the parameterization from RAM to ROM with "Copy RAM to ROM".
- Then select "Load CPU / drive unit to PG" to load the parameterization from the SINAMICS Integrated back to the programming device in order to back up the SINAMICS parameter calculations.

Result

The SINAMICS Integrated is now ready for operation (RDY LED is green). The CX32 can be accessed online, although it will not yet have been configured (RDY LED is green, DP1 LED is red).

- 1. Select "Connect Online" in the CX32 context menu. You will then be connected to the CX32 online.
- 2. Load the parameterization to the CX32 and copy the parameterization from RAM to ROM.
- 3. Then load the parameterization from the CX32 back to the programming device in order to back up the SINAMICS parameter calculations.
- 4. Repeat steps 1 to 3 for each CX32.
- 5. Save the project.

Note

Topology errors may make it impossible to perform a download, power up a system, or access a CX32 online.

7.4 Configuring a CX32

See also

CX32 diagnostics (Page 187)

7.4.5.2 Loading a project created offline to the CF card

Loading a project created offline to the CF card has the advantage of being faster than a download.

It should be noted, however, that the first system power-up will take longer, as the SINAMICS Integrated and CX32 will perform one-off parameter calculations. These are automatically backed up on the CF card.

Requirement

- You will need a card reader for the SIMOTION D4x5 CF card.
- Your project, including all SINAMICS Integrated and CX32 drive components, must have been configured already (see Preparing for configuration (Page 176)).
- The actual topology must correspond with the reference topology.

Procedure

- 1. Select "Load to file system" in the SIMOTION D4x5 context menu.
- 2. Select "Normal save" and click the "Select target" button. Select your card reader's drive and confirm with "OK".
- If a project has already been saved to the CF card, the message "Memory card file already exists. Do you want overwrite this file?" appears. Confirm the message with "Yes".
- 4. Once the project has been subsequently transferred to the CF card, insert the card into the disconnected SIMOTION D4x5. Switch on the power supply for the D4x5 and connected components.
- 5. After a successful power-up, the RDY LED of the D4x5 and CX32 will be green, as will the DP1 LED of the CX32.

The components' firmware is automatically updated, depending on the FW version on the SINAMICS components and on the CompactFlash Card. Please see the corresponding instructions in the chapter titled Upgrading D4x5/CX32 (Page 188).

Note

Topology errors may make it impossible to perform a download, power up a system, or access a CX32 online.

7.4.6 Performing CX32 configuration online

Requirement

You need a project which has already been created and which contains SIMOTION D4x5 with SINAMICS Integrated, as well as the CX32 controller extension(s).

Additional drive components (line module, motor modules, terminal modules, etc.) are configured using "Automatic commissioning" and must not, therefore, be created offline.

Procedure

- 1. Deselect all target devices, with the exception of the SIMOTION D4x5, using the "Target system" ⇒ "Select target devices" menu command in SCOUT.
- 2. Go online with the D4x5 by clicking "Connect to selected target devices".
- 3. Select the D4x5 in the project tree. Load the configuration to the SIMOTION D4x5 with "Download CPU / drive unit to target device".
- 4. Copy the configuration from RAM to ROM with "Target device" ⇒ "Copy RAM to ROM".
- 5. Select "Connect target device" in the SINAMICS Integrated context menu. You will then be connected to the SINAMICS Integrated online.
- 6. Perform "Automatic Configuration" on the SINAMICS Integrated. This may take several minutes, depending on the number of components connected.

The SINAMICS Integrated is now ready for operation (RDY LED is green). The CX32 can be accessed online, although it will not yet have been configured (RDY LED is green, DP1 LED is red).

- 7. Select "Connect target device" in the CX32 context menu. You will then be connected to the CX32 online.
- 8. Perform automatic configuration on the CX32. The CX32 is now also ready for operation (RDY LED is green, DP1 LED is green).
- 9. Repeat steps 7 to 8 for each CX32.
- 10.Copy the parameterization from RAM to ROM with "Copy RAM to ROM".
- 11.Save the project.

If you run the "automatic configuration" in Step 6 and 8, a check will be made to see if the firmware on the SINAMICS components differs from the firmware on the CF card. If it does, you will be informed accordingly and the firmware on the SINAMICS components will be upgraded/downgraded automatically.

The update can take several minutes and its progress is tracked by corresponding messages appearing in the alarm window of SIMOTION SCOUT.

A firmware update on DRIVE-CLiQ components is indicated by the RDY LED flashing red and green:

- FW update running: RDY LED flashes slowly (0.5 Hz)
- FW update complete: RDY LED flashes quickly (2 Hz)

7.4 Configuring a CX32

These flashing patterns are also displayed on the yellow RDY LED on the SIMOTION D/CX32, and indicate that a FW update has been carried out on components connected to the SIMOTION D/CX32 or that all components have completed the FW update.

Go offline once all the FW updates have been completed. POWER ON the upgraded/downgraded components.

Note

Topology errors may make it impossible to perform a download, power up a system, or access a CX32 online.

See also

CX32 configuration instructions (Page 184) CX32 diagnostics (Page 187)

7.4.7 CX32 configuration instructions

This section contains configuration tips relating to a number of features which are specific to operating CX32 in conjunction with D4x5.

7.4.7.1 CX32 power-up

Powerup times

The CX32 does not require its own CF card. Both the firmware and parameterization are stored centrally on the SIMOTION D CF card. This means the CX32 will only power up once the SINAMICS Integrated has done so. As a result, it usually takes longer for the system to power up compared to when a SIMOTION D is used with a SINAMICS Integrated and any CU320 Control Units which may be connected.

Detecting when the CX32 powers up in the user program

The user must wait for the CX32 to power up before the drive objects can be accessed by the user program.

One way of checking is to query the status of system variables on the CX32 drives.

- <axis name>.actormonitoring.cyclicinterface = ACTIVE AND
- <axis name>.sensordata[1].state = VALID

This procedure can also be used to establish when the SINAMICS Integrated drives power up.

7.4.7.2 Interconnecting the infeed "Operation" signal on the CX32

Requirement

- Drive line-up with SIMOTION D4x5 Control Unit and Line Module with DRIVE-CLiQ interface
- One or more CX32 Controller Extensions with no Line Module of their own (in other words, the Motor Modules of the D4x5 and CX32 modules are supplied by the same DC link).

In this example, the Line Module must to be connected to the SIMOTION D4x5 (not the CX32).

Procedure

When drives are created in Drive System 1, the signal "Closed-loop control operation" r863.0 from the Line Module is automatically interconnected with the "Infeed operation" signal from the drives (Drive 1...n) via p864.

There is an internal communication channel available (V4.1 SP1 and higher) for the CX32 Controller Extension (Drive System 2), via which the following signals from the SIMOTION D4x5 Control Unit can be automatically interconnected to the CX32 Controller Extensions:

- "Closed-loop control operation" from the Line Module connected to SIMOTION D4x5
- Status of the SIMOTION D4x5 onboard digital inputs

These signals are available on the CX32 Controller Extension; since there is no need to perform any additional configuration steps, it is very easy to make additional interconnections with them within the CX32.

7.4 Configuring a CX32

Interconnecting the infeed operation signal

The "Closed-loop control operation" signal from the Line Module connected to the SIMOTION D4x5 is available in parameter r8510.0 of the CX32. Using the expert list or the drive wizard, interconnect parameter p864 (drives on CX32) with parameter r8510.0 of the CX32 Controller Extension.



Figure 7-31 Interconnecting the infeed operation signal



Figure 7-32 Operation signal interconnection (explanatory illustration)

Terminal status of D4x5 onboard digital inputs

The terminal statuses of the SIMOTION D4x5 onboard digital inputs are available in parameter r8511[0..15] of the CX32. Additional interconnections can be made on the CX32 using these.

7.4.7.3 CX32 diagnostics

Error analysis/Error correction

In order to commission a SIMOTION D with CX32, all drive components which were configured offline must also be present and connected to the correct DRIVE-CLiQ port.

Only when there are no topology errors

- Will the download be successful (where a project created offline is loaded to the target system)
- Will the system startup be successful
- Can the CX32 modules be accessed online

Error correction procedure

If the actual topology of the SINAMICS Integrated is either incomplete or has been inserted incorrectly,

- The RDY LED of the D4x5 remains yellow.
- The RDY LED and DP1 LED on the CX32 are yellow and red respectively.
- The CX32 cannot be accessed online in this state.

Procedure

Rectifying a topology error

- 1. Select "Target System" > "Select Target Devices" in SCOUT.
- 2. In the next window, deselect all the target devices apart from the D4x5 and the SINAMICS Integrated.
- 3. Close the window by clicking "OK".
- 4. Now click the "Connect to selected target devices" button. The D4x5 and the SINAMICS Integrated are connected.
- 5. Using the alarm window and the topology view of the SINAMICS Integrated, the topology error can now be analyzed (for example, a component may be missing or in the wrong port).

7.4 Configuring a CX32

- 6. Switch off the D4x5 and the CX32, rectify the topology error, and switch all devices back on again.
- 7. Once the SINAMICS Integrated has started up successfully, the RDY LED of the D4x5 will be green.
 - If the CX32 has been configured and has powered up successfully, the RDY LED and DP1 LED of the CX32 will also be green.
 - If, however, the RDY LED on the CX32 is green but the DP1 LED is red, this means the CX32 has not yet been configured. If this is the case, complete the next 4 steps.

On the CX32, the RDY LED is green but the DP1 LED is red:

In this state, the CX32 can be accessed online but has not been configured.

- 1. Select the CX32 and select "Connect Online" in the context menu.
- 2. Click the "Download CPU/drive unit to target device" button. This will load the CX32 configuration.
- 3. Save the data with "Copy RAM to ROM".
- 4. Once the SINAMICS Integrated and the CX32 have started up successfully, the RDY LED of the D4x5 and the CX32 will be green, as will the DP1 LED of the CX32.

7.4.7.4 Upgrading D4x5/CX32

CX32 modules are always operated with the same firmware version as the SINAMICS Integrated of a SIMOTION D.

This means no additional measures need to be taken for CX32 modules.

If the firmware version of the SIMOTION D is upgraded via **HW Config**, the SINAMICS Integrated and the connected CX32-2 controller extension are also automatically upgraded as of SCOUT V4.2.

If a SIMOTION SCOUT < V4.2 is used, the SINAMICS Integrated and CX32 must be manually upgraded via the context menu "SINAMICS drive" \Rightarrow "Target device" \Rightarrow Device version".

7.4 Configuring a CX32

For instructions on upgrading a SIMOTION D see also Section Adapting a project (Updating the project / Replacing the SIMOTION controller) (Page 272).

Note

The components' firmware is upgraded or downgraded automatically based on the FW version on the CF card and the FW version on the SINAMICS components (DRIVE-CLiQ components, CBE30, PM340, etc.).

The update can take several minutes and its progress is tracked by corresponding messages appearing in the alarm window of SIMOTION SCOUT.

A firmware update on DRIVE-CLiQ components is indicated by the RDY LED flashing red and green:

- FW update running: RDY LED flashes slowly (0.5 Hz)
- FW update complete: RDY LED flashes quickly (2 Hz)

These flashing patterns are also displayed on the yellow RDY LED on the SIMOTION D/CX32, and indicate that a FW update has been carried out on components connected to the SIMOTION D/CX32 or that all components have completed the FW update.

Go offline once all the FW updates have been completed. POWER ON the upgraded/downgraded components.

7.4.7.5 Replacing D4x5/CX32

Replacing a module

When used as a replacement part, a CX32 behaves like other DRIVE-CLiQ components.

D445/D445-1 ⇔ D435 replacement

Drag-and-drop can be used to carry out D445/D445-1 ⇔ D435 module replacement in HW Config.

Please note that it will not be possible to replace a D445/D445-1 with a D435 if a CX32 has been configured with the address 14 or 15. (since a D435 does not have DRIVE-CLiQ ports X104/X105, it does not have addresses 14 and 15).

7.5 Additional information on configuring the SINAMICS Integrated

7.5 Additional information on configuring the SINAMICS Integrated

7.5.1 Settings for DP slave properties

Settings in HW Config

Depending on the cycle clock ratios (bus cycle clock, servo cycle clock) and the drives used, it may be necessary to change the properties of the DP slave (SINAMICS Integrated) on the PROFIBUS Integrated.

Open HW Config. Double-click the SINAMICS Integrated to display and, if necessary, change the properties of the DP slave on the "Isochronous mode" tab. Example:

Synchronizing a drive to the isochronous DP cycle

SINAMICS Integrated and CX32 can only be operated isochronously. For this reason, this option cannot be deactivated.

Changing the master application cycle (T_{MAPC})

The master application cycle must always be the same as the servo cycle clock set (setting: "Context Menu of the D4x5" > "Set System Cycle Clocks" in the project tree). Provided that the DP cycle is not scaled down to the position control cycle clock, the master application cycle will always be the same as the DP cycle.

• Changing the DP cycle (T_{DP})

Depending on the requirements in terms of the quantity structures and the response times, the DP cycle may need to be changed (see also *SIMOTION SCOUT Basic Functions* Function Manual).

In addition, the minimum DP cycle for vector drives also depends on the speed controller clock cycle, which in turn depends on the drive quantity structure and the device type used. This means that, particularly in the case of vector drives, the DP cycle must be checked and changed if necessary (see Using vector drives (Page 191)).

Note

After T_{DP} has been changed on the PROFIBUS master, the drive system must be switched on (POWER ON).

Changing the T₁ and T₀ times

A change to T_I/T_0 is required in the case of vector drives, for example, where the T_I/T_0 time depends on the number of vector drives or, with chassis devices, on the device type used.

If you are changing settings for the SINAMICS Integrated, you must also change the settings on the CX32 modules accordingly. This is easily done by using the Align button to transfer the settings for all the CX32 modules.

Commissioning (software)

7.5 Additional information on configuring the SINAMICS Integrated

HW Config - [SIMOTION D (Configuration) prg_sample]	
	inew options window help Ba (R.) 🚵 🎰 (R) 🗖 🖼 192	
Image: Construction (0) SIMOTION D435 2 D435 X126 DP1 X136 DP2/MPI PCI DP Integrat X120 IE1/OP X130 IE2/WET	PROFIBUS Integrated: DP master system (1)	
	OP slave properties	×
	Synchronize drive to equidistant DP cycle Network settings in ms Equidistant bus cycle activated Equidistant DP cycle: 3.000 Data_Exchange_Time comp. Tdx:	
•	Master application cycle Tmapc [ms]: 3.000 = 1 × 3.000	
(3) SINAMICS_Inte	DP cycle Tdp [ms]: 3.000 = 24 x 0.125	
Slot M Message fra	Time Ti [ms] Gard / base time [ms] (actual value acquisition): 0.125	
5 6 7	Time To [ms] 0.250 = Factor Grid / base time [ms] (setpoint acceptance): 0.250 = 2 x 0.125	
8	Align	
10 11 12	OK Cancel Help	

Figure 7-33 HW Config - settings

The times are modified by changing the value in the "Factor" field.

Additional references

For additional information, please refer to the

- SINAMICS S120 Function Manual
- SIMOTION SCOUT Basic Functions Function Manual

7.5.2 Using vector drives

Changes need to be made in HW Config when using SINAMICS vector drives. This means, for example, that the T_I/T_O time and the minimum DP cycle depend on the number of vector drives or, with chassis drives, also on the device type used.

7.5 Additional information on configuring the SINAMICS Integrated

Therefore, we recommend adopting the following procedure is when using vector drives with SIMOTION D4x5.

Scenario 1: Current and speed controller cycle is known

As long as you know the current and speed controller cycle, you will be able to determine times T_{MAPC} , T_{DP} , T_{I} , and T_{O} . Where there are several drives with different cycle clocks, the largest cycle clock must be used for the current and speed controller cycle.

Procedure

- 1. Open HW Config. Double-clicking SINAMICS Integrated allows you to change the properties of the DP slave on the "Isochronous mode" tab.
- 2. For $T_1 = T_0 =$, enter an integer multiple of the current controller cycle.
- 3. For T_{DP}, enter an integer multiple of the speed controller cycle. For drives on the SINAMICS Integrated, T_{DP} must always be ≥ T_O.
- Enter T_{MAPC} = T_{DP} (exception: You are working with cycle clock scaling; i.e. position control cycle clock > DP cycle).
- 5. Use the "Download project to target system" menu command to load the configuration to the SIMOTION D4x5.
- 6. After the download has successfully completed, you should determine the current and speed controller cycles of the drives from the drives' expert lists, as the cycle clocks are set in the SINAMICS drive unit after a project has been downloaded.

p115[0]: Current controller cycle

p115[1]: Speed controller cycle

7. If the current and speed controller cycles from the expert lists are different to the cycle clocks used in steps 2 and 3, you will have to repeat the steps with the current values for the current and speed controller cycles.

Table 7-4	Example for	power units in	booksize format	(vector drives)
-----------	-------------	----------------	-----------------	-----------------

Example	Settings
1 or 2 vector drives	$T_1 = T_0 = at least 250 \ \mu s$
Current controller cycle = 250 µs	T _{DP} = 1 ms (or 2 ms, 3 ms, etc.)
Speed controller cycle = 1 ms	T _{MAPC} = T _{DP}
3 or 4 vector drives	$T_I = T_O = at least 500 \ \mu s$
Current controller cycle = 500 µs	T _{DP} = 2 ms (or 4 ms, 8 ms, etc.)
Speed controller cycle = 2 ms	T _{MAPC} = T _{DP}

Note

Vector drives in chassis format can also be operated with a current controller sampling time of 400 $\mu s,$ amongst other settings.

In a SIMOTION context, the following should be considered:

- A current controller sampling time of 400 µs is only possible if control is via a SINAMICS S120 control unit, which is not operated isochronously via PROFIBUS/PROFINET on SIMOTION D.
- If the bus is operated isochronously, only cycle clocks with an integer multiple of 125 µs are possible (375 µs or 500 µs instead of 400 µs, for example).
- The PROFIBUS Integrated of a D4x5/CX32 is always isochronous! This means a current controller sampling time of 400 µs is not possible.
- With CU parameter p0092 = 1, the sampling times are pre-assigned so that isochronous operation with a controller is possible.

Scenario 2: Current and speed controller cycle is not known

This procedure is especially suitable for devices in chassis format, as the current and speed controller cycle also depends on the relevant device type.

- To determine which cycle clocks are set in the SINAMICS drive unit after a project has been downloaded, first set reliable values for the cycle clocks in HW Config (see table "Recommended cycle clock settings in HW Config").
- 2. Use the "Download project to target system" menu command to download the parameterization.
- 3. After the download has successfully completed, you will be able to determine all the current and speed controller clock cycles of the drives from the drives' expert lists.
 - p115[0]: Current controller cycle
 - p115[1]: Speed controller cycle
- If required, it is now possible to optimize the T_{MAPC}, T_{DP}, T₁ and T₀ times in HW Config (see procedure for Scenario 1).

Setting	Explanation
T _{DP} = 3.0 ms	T _{DP} = DP cycle time
$T_1 = T_0 = 1.5 \text{ ms}$	T _I = time of actual value acquisition
	To = time of setpoint transfer
T _{MAPC} = 3.0 ms	T _{MAPC} = master application cycle time

Table 7-5 Recommended cycle clock settings in HW Config

Output cams / measuring inputs with vector drives

With vector drives, the cycle clock ratios (current controller cycle clock, speed controller cycle clock, sampling time of the inputs/outputs, etc.) depend on the number of vector drives, or with chassis units also on the device type used.

Note the information in Section Current controller cycle clocks <> 125 μ s / Using output cams and measuring inputs (Page 199).

7.5 Additional information on configuring the SINAMICS Integrated

Additional references

Additional information on quantity structures and cycle clock settings can be found in the *SINAMICS S120* Function Manual.

See also

Settings for DP slave properties (Page 190)

7.5.3 Setting the time of day

Time on SIMOTION (real-time clock)

SIMOTION D4x5 has an integrated real-time clock. All events on a module (alarms, messages, etc.) are "time-stamped" based on the time shown by this real-time clock.

To set the clock from SIMOTION SCOUT, select the D4x5 in the project tree, followed by "Target system" \Rightarrow "Set time".

Alternatively, the clock can be set using the "rtc" system function block.

SINAMICS system runtime (operating hours meter)

With the SINAMICS Integrated of a SIMOTION D, controller extensions and the SINAMICS S110/S120 control units, faults and alarms are "time-stamped" on the basis of the system runtime. This means that events are recorded by default on the basis of operating hours rather than a particular time of day or date.

System runtime

The entire system runtime is displayed in CU parameter p2114.

- p2114[0] indicates the system runtime in milliseconds. After reaching 86,400,000 ms (24 hours), the value is reset.
- p2114[1] indicates the system runtime in days.

At power-off the counter value is saved. After the drive unit is powered-up, the counter continues to run with the value that was saved the last time that the drive unit was powered-down.

As a result, the drive displays the system runtime from 00:00:00 on 01/01/1992 in both the alarm window in SIMOTION SCOUT and the diagnostic buffer for entries.

If faults and warnings need to be "time-stamped" based on a time of day, "Time-stamp operating hours" needs to be changed to "Time-stamp UTC format" as described below.

Requirements

A message frame 39x is required for the time synchronization. If the automatic PROFIdrive message frame setting is selected for the control unit, this message frame is used automatically.

(See Section Calling the drive wizard (Page 142), Standard/automatic setting)

If the message frames are specified manually, message frame 39x must be set up. See Section Message frame configuration (Page 216).

So that drive units can be synchronized with the SIMOTION time, they must support message frame 39x and the UTC time format.

These include, for example:

- SINAMICS Integrated of the SIMOTION D
- CX32/CX32-2 controller extensions
- SINAMICS S110/S120 CU305, CU310, CU320, CU320-2 control units connected via PROFIBUS or PROFINET

Synchronizing the SINAMICS clock

Proceed as follows to convert the SINAMICS clock to UTC format and to synchronize this with the SIMOTION clock:

- 1. Call the D4x5 context menu in the project navigator.
- 2. Select the "Properties" entry in the context menu.
- 3. Select the "Perform time synchronization with SINAMICS drive units" option in the "Settings" tab of the "Properties D4x5" dialog box.

Note

This setting is automatically activated for new projects as of V4.2 and applies for all drive units connected to the D4x5. The SINAMICS clock is automatically synchronized with the SIMOTION clock for all drive units with configured message frame 39x.

The first time synchronization is performed after the SIMOTION D control unit has reached the RUN mode.

To compensate for deviations between the SIMOTION and SINAMICS clocks, the time of day is automatically resynchronized at regular intervals.

Via the system variable _driveStates.allClocksSynchronized on the device, the user program can query whether the automatic time synchronization is activated (=YES) or deactivated (=NO).

Before the first synchronization, alarms and messages are stored with the time stamp valid in the SINAMICS at this time, all subsequent alarms and messages with the synchronized time.

The first time synchronization after switching on is entered with the status of the operating hours counter and the time (UTC time, synchronized with SIMOTION) in the diagnostic buffer of the drive (e.g. SINAMICS Integrated).

Commissioning (software)

7.5 Additional information on configuring the SINAMICS Integrated

Diag	gnost	ics buffer			
		Help for event		Display	hex values only 🗖
	No.	Time of day	Date	Event	▲
	01	14:23:17:441	12.11.10	Fault D0 1: Fault code 1915, fault value 0x0	
	02	14:22:17:232	12.11.10	Fault DO 1: Fault code 1915, fault value 0x0	
	03	14:22:01:331	12.11.10	Switchover to UTC time for operating hours count 0 142502	
	04	00:00:32:582	01.01.92	Ram2Rom of DO 0 performed	
	05	00:00:28:336	01.01.92	Ram2Rom of DO 0 started	
	06	10:26:05:245	09.01.92	Ramp-up completed, cyclic operation	
	07	10:26:02:047	09.01.92	Cyclic data exchange PZD IF1 started	
	08	10:26:02:023	09.01.92	Cyclic data exchange PZD IF1 completed	
	09	00:00:13:289	01.01.92	New ramp-up, reason 3	
	10	00:00:12:997	01.01.92	Cyclic data exchange PZD IF1 completed	
	•				
E	Event details: 3 of 204 Event ID: 16# F360:241A				
9	Switchover to UTC time for operating hours count 0 142502				



Note

The time synchronization must be performed "applicatively" for SIMOTION versions < V4.2. You can find a sample program in the SIMOTION Utilities & Applications.

If the "applicative time synchronization" is used for SIMOTION versions \geq V4.2, the time synchronization must be deactivated via the "Settings on the Device" dialog box.

SIMOTION Utilities & Applications is part of the scope of delivery of SIMOTION SCOUT.

Compensation of runtime deviations

To compensate for deviations between the SIMOTION and SINAMICS clocks, the time of day is automatically resynchronized at regular intervals.

The following behavior must be taken into consideration when setting the SIMOTION time:

- "Time/date to be set" is after "Time/date on SINAMICS": Time and date on SINAMICS is updated.
- "Time/date to be set" is before "Time/date on SINAMICS": The SINAMICS clock must be stopped until the SINAMICS "Time/date" has caught up with "Time/date to be set".

Adopting this procedure ensures that the sequence of SINAMICS diagnostic buffer entries remains the same, even when the runtime differences are aligned.

The SINAMICS clock operates with a resolution of 1 ms. A synchronization accuracy of 1 ms can be achieved for all bus cycle clocks that can be divided exactly by 1 ms (e.g. 1 ms, 2 ms, 3 ms, etc.).

A slightly lower synchronization accuracy is achieved for all bus cycle clocks that cannot be divided exactly by 1 ms (e.g. 1.25 ms) due to the system.

7.5 Additional information on configuring the SINAMICS Integrated

7.5.4 SINAMICS diagnostic buffer

Requirement

The diagnostic buffer is supported for SINAMICS S120 devices as of version V2.6. The SINAMICS Integrated variants support the diagnostic buffer as of version V2.5. There are minimum requirements for the HW version for the following components:

- For D425/D435, product version "D",
- For CU320 (-0AA1), product version "C".

Procedure

To do this, select the SINAMICS Integrated, the CX32 or the SINAMICS S120 control unit in the project tree. Then select "Target System" > "Device Diagnostics" in the menu.

In addition, the SINAMICS diagnostic buffer entries are displayed in the D4x5 device diagnostics. All D4x5 diagnostics buffer entries are displayed first, followed by those for the SINAMICS Integrated and the CX32. The start of the SINAMICS diagnostics buffer entries is identified by the following entry:

You also have the option of viewing the SIMOTION D4x5 and SINAMICS Integrated diagnostics buffers via IT DIAG.

7.5.5 Acyclic communication with the drive

Overview

PROFIdrive drive units are supplied with control signals and setpoints by the controller and return status signals and actual values. These signals are normally transferred cyclically (i.e. continuously) between the controller and the drive.

For the SINAMICS S110/S120, configure the axis message frames for data exchange (see Performing the configuration for the D4x5 offline (Page 141)).

As well as offering cyclic data exchange, PROFIdrive drive units have an acyclic communication channel. In particular, this is used for reading and writing drive parameters (e.g. error codes, warnings, controller parameters, motor data, etc.).

As a result, data can be transferred on an "acyclic" as opposed to a "cyclic" basis when required. Acyclic reading and writing of parameters for PROFIdrive drives is based on the DP V1 services "Read data set" and "Write data set".

The acyclic DP V1 services are transferred in parallel to the cyclic communication via PROFIBUS or PROFINET. The PROFIdrive profile specifies precisely how these basic mechanisms are used for read/write access to parameters of a PROFIdrive-compliant drive.

The PROFIdrive standard states that "pipelining" of jobs on PROFIdrive drives is not supported. This means:

7.5 Additional information on configuring the SINAMICS Integrated

- Only one "Write/read data set" can be performed at any one time on a drive unit (e.g. SINAMICS S110/S120 control unit or the SINAMICS Integrated of a SIMOTION D).
- However, if several PROFIdrive drive units are connected to a controller, a job can be
 processed for each of these drive units at the same time. In this case, the maximum total
 number of jobs will depend on the control (for SIMOTION, this is a maximum of eight jobs
 at a time).

For acyclic data exchange with SINAMICS drives, this means you will have to coordinate the write/read jobs with each other (buffer managemenr). An interlock must be set to prevent the application or different parts of the application from sending overlapping jobs to the same PROFIdrive drive unit.

Additional references

Additional information on how to use DP V1 services can be found in the *SIMOTION Communication* System Manual.

SIMOTION Utilities & Applications also has a DP-V1 library with functions that are capable of performing coordination tasks commonly associated with acyclic communication. The library not only coordinates access to the system functions

(_ReadRecord/_WriteRecord/_readDriveParameter/_writeDriveParameter/, etc.), but also expands the range of functions for frequently required tasks, e.g. the reading of faults and alarms from the drive unit.

SIMOTION Utilities & Applications is part of the scope of delivery of SIMOTION SCOUT.

The following functions are available in the DP V1 library:

- Buffer management (coordination of a number of parallel DP V1 services)
- StartUp (function for coordinating the power-up of the SINAMICS drive with SIMOTION)
- TimeSync (applicative time synchronization: Transfer of SIMOTION time of day to the SINAMICS drives)
- SetActIn (activating/deactivating objects in SIMOTION and SINAMICS)
- RwnPar (reading and writing of drive parameters)
- GetFault (reading of faults and alarms from the drive)

7.5.6 Control properties and performance features

With a few exceptions, the integrated drive control of SIMOTION D4x5 and CX32 has the same control properties and performance features as the SINAMICS S120 CU320 control unit.

However, the following points must be particularly observed:

- SINAMICS Integrated and CX32 have no basic positioner (EPOS). The EPOS functionality is provided by the SIMOTION technology functions.
- The BOP20 Basic Operator Panel cannot be connected to the SIMOTION D4x5.

The following alternative options are available:

- Use of SIMATIC HMI devices (e.g. TP177B, configurable with WinCC flexible)
- Use of SIMOTION IT DIAG: You can use a Web browser to access the standard diagnostics pages of the SIMOTION D4x5 (diagnostics and alarm buffers, Watch table, read/write SIMOTION variables and drive parameters, access protection, trace function, etc.)

You also have the option of creating your own Web pages, in order for example to visualize machine states and implement service functions. The SIMOTION D4x5 Web pages can be accessed for example using a PC or PDA over Ethernet. Wireless access is also possible in conjunction with WLAN.

• The use of the CU parameter p972 is restricted with SIMOTION D4x5. CU parameter p972 can be used to reset the drive unit. You can use this method, for example, in the context of the implementation of modular machine concepts to force a restart of the CX32 controller extension (see the description of functions titled *Motion Control Basic Functions for Modular Machines*).

NOTICE

You are not permitted to use parameter p972 on the SIMOTION D4x5 to reset the drive. This leads to a fault on the SIMOTION D4x5, with all eight status LEDs flickering red. In this fault situation, the SIMOTION D4x5 must be switched off and back on again.

7.5.7 Current controller cycle clocks <> 125 μs / use of output cams and measuring inputs

If current controller cycle clocks <> 125 μ s are used, the parameter calculations of the drive must be transferred to the PG when using cam outputs on the TM15 / TM17 High Feature or for global measuring inputs, and FastIO configuration generated again.

A change of the current controller cycle clock may have effects on the sampling times of the inputs/outputs on the drive side (e.g. TM15/TM17 High Feature, p4099 Sampling time of the inputs/outputs).

Sampling times > 125 µs occur in the following cases:

- For servo drives with manual change of the current controller sampling time (drive parameters p112 and p115[0])
- For vector drives depending on the number of vector drives and with chassis units depending on the device type used
- If only an infeed and no drives are connected to the drive unit, then the sampling time is 250 µs

For the cam outputs and the measuring input inputs (only for global measuring inputs) to function correctly, the sampling times must be known to the engineering system.

7.6 Testing a drive with the drive control panel

	Current controller cycle clock has no effect on the function	Current controller cycle clock has an effect on the function
Cam outputs	SIMOTION D	TM15/TM17 High Feature
Measuring input inputs (global measuring inputs)	D4x5-2 (terminal X142)	 TM15/TM17 High Feature SIMOTION D (except D4x5-2, terminal X142) Controller extension (CX) SINAMICS S110/S120 control units
Measuring input inputs (local measuring inputs)		

 Table 7- 6
 Influence of the current controller cycle clock on the dead time compensation

In order that the changed cycle clock ratios are taken into account by the the engineering system, proceed as follows:

- 1. Go online and perform a project download. The SINAMICS performs parameter calculations once. These are automatically backed up on the CF card.
- 2. Perform an upload to the PG ("Target system" > Load" > "Load CPU / drive unit to PG").
- 3. This transfers the parameter calculations of the drive to the PG. The cycle clock ratios are then known in the engineering system.
- 4. Go offline.
- Generate the configuration information (Fast IO configuration) again. To do this, select the SIMOTION CPU in the project tree and right-click to open the context menu "Fast IO" > "Create new configuration".
- 6. Click "Save project and compile all".
- 7. Go online and download the project to the target system.

SCOUT uses the described procedure to calculate internal system data that is required for outputting/detecting signals with a high level of position accuracy.

Note

If the cycle clock ratios are not set correctly, an appropriate message is output in the diagnostic buffer.

7.6 Testing a drive with the drive control panel

Introduction

You can test a configured drive with the drive control panel, where you can specify a speed and adjust it with a scaling factor. The drive control panel should only be used for commissioning purposes.

7.6 Testing a drive with the drive control panel

Requirements

- The project has been downloaded to the target system.
- SIMOTION SCOUT is in online mode.
- The drive is not being used by a current project in RUN mode.

WARNING	
Make sure no one is endangered by the drive test.	

Testing a drive with the drive control panel

 Change to the configured drive in the Project Navigator and open the drive control panel by selecting "Commissioning" > "Control panel". The drive control panel opens in the detail view.

SINAMICS_Integrated - SERVD_02 Help		
Assume control priorityl I 0 ▲▼ In setpoint specification I CDS: 0 Image: CDS: 0 I Enables DDS: 0	0% n x 100 % 200%	•
Diagnostics Specified Actual OFF2 enable Specified Actual	Output frequency, smoothed 0.0 Hz C0: Output voltage, smoothed	
OIF3 enable OFF3 enable Ramp-function generator start Setpoint enable	0.0 Vrms Motor current: 0.00 Arms Motor utilization: 0.0 %	•
🚪 Alarms 💋 Control panel [🚟 Symbol browser 🏢 Target system output 🏢 Compile/check output 🌿 Diagnostics overview		

Figure 7-35 Drive control panel

2. To display the control range and axis diagnostics, click the "Show/hide control range" and "Show/hide diagnostics area" buttons.

7.6 Testing a drive with the drive control panel

3. Click "Assume control priority". The "Assume Control Priority" dialog box is opened.

Note

If you are using an infeed without a DRIVE-CLiQ interface, you will have to interconnect the "Infeed operation" signal (drive parameter p864) yourself. If you are using an infeed with a DRIVE-CLiQ interface, select the infeed for which the control priority is to be assumed under "Infeed" in the "Assume Control Priority" dialog box.

If the infeed signal "Closed-loop control operation" already has a BICO interconnection to the drive, the infeed is permanently specified (infeed selection and checkbox are grayed out).

The infeed must be switched on before the drive can move ("LM" button, switch infeed on/off).

Assume Control Priority		
Life-sign monitoring		
Act.		
Monitoring time: 1000 ms		
✓ Infeed:		
Assume control priority		
None		
None		
SINAMICS_Integrated.Infeed ed!		
When the control priority is returned via the tool, the infeed is switched off. This can interfere with a program of a higher-level		
control, il triis uses the same inteed.		
This function may only be used under observance of the relevant safety notes. Failure to observe these safety notes may		
damage.		
Safety notes		
Accept Cancel Help		

Figure 7-36 Assuming control priority

- 4. Read the notices and click "Accept" to confirm.
- 5. Select the "Enables" checkbox to enable the drive.

All enables are now set except ON/OFF1.

Enter the desired setpoint in the entry field, and, as a safety setting, slide the scaling to 0%.

Give up control priority/	In setpoint specification In = 300 re	v/min 0 ² n x 100 % 200% = 300.00 rev/min
Enables available Diagnostics OFF1 enable OFF2 enable OFF3 enable OFF3 enable OFF3 enable Fanghunction generator stat Septort mable	power-up - set "ON/OFF1" = "0/1" (p0840) Specified Actual Speed 0.0 -0.0 rev/min	Output frequency, smoothed 0.0 Hz CD: Dulput voltage, smoothed 0.0 Vims Motor current: 0.00 Arms
Alarms 💋 Control panel 🚟 Symbol browser 🛄	Target system output See Diagnostics overview	TCP/ID(Arto) -> Broadrom NetVitrame Gin Online more

Figure 7-37 Entering a setpoint

- 7. Click the "Drive On" button. The green "Enable available" LED lights up. If you move the slider to the right, the drive rotates. The current motor speed is displayed under "Actual".
- 8. Click "Drive Off" to stop the drive after the test.
- 9. Deactivate the enable and click the "Give up control priority" button to deactivate control from the PG/PC. In this state, you can no longer make the drive rotate.

7.7 Creating and testing axes

7.7.1 Overview of SIMOTION engineering

Performing engineering with SIMOTION SCOUT

You use the engineering software to configure the individual axes and define the project sequence by means of programs.

- 1. First, run through the axis wizard to configure the axes and interconnect to the real drive (e.g. SINAMICS Integrated).
- 2. Then, select the "SINAMICS_Integrated" in the project navigator and deactivate the "Connect Online" option in the context menu. This only downloads the project to the SIMOTION D4x5.

Provided you have completed configuration at the drive end, we strongly recommend you deactivate the SINAMICS Integrated so that work can be carried out faster via "Target system" > "Select target device".

- 3. Complete your SIMOTION application, for example, by creating axis functions and SIMOTION execution programs.
- 4. Compile the project and download it to the SIMOTION D4x5.

See also

Downloading a project into the target system (Page 161) Downloading a project to the CF card (Page 163)

7.7.2 Creating an axis with the axis wizard

Overview

The TO axis provides the user with the technological functionality and the interface to the drive/actuator. The TO axis processes the motion control commands from the user program (e.g. MCC) and coordinates the interface to the drives. It executes control and motion commands and indicates statuses and actual values. The TO axis communicates with an actuator (drive or hydraulic valve) via a field bus system (PROFIBUS or PROFINET via PROFIdrive protocol) or via a direct setpoint interface (analog ±10 V or pulse/direction).

When running through the axis wizard, the basic settings are made for the axis and the TO axis interconnected to a drive (e.g. SINAMICS Integrated). Further options are available when "Symbolic assignment and adaptation" is used:

- A real axis is interconnected to an already configured drive
- A real axis including drive is created via the axis wizard and the drive interconnected to the axis
- A real axis is created without assigning this to a drive (assignment is made later)

Inserting an axis

1. In the project navigator, double-click the entry "Axis" > "Insert Axis".

This will access the axis wizard. Set the required technology and then click "OK".

Insert Axis	×
Name: Axis 1	
General Object address Which technology do you want to use? Author: Speed control Version: Synchronous operation Path interpolation	
Existing Axes	
Comment:	
OK Cancel Help	

Figure 7-38 Inserting an axis

2. Set an axis type and, if required, configure the units.

Axis configuration - Axis_1 - Axis Type			
Axis Type Drive assignment Encoder assignment Encoder configurati Summary	You can select the axis type on this page. Already set data can be lost if this entry is changed, as the structure of the configuration data changes.		
	Axis type:	 € Linear C Rotary 	
		 Electrical Hydraulic Virtual 	
	Mode:	Standard 💌	
	< Bac	k Next > Cancel Help	

Figure 7-39 Defining the axis type

3. Create a new drive or make the assignment to an existing drive.

Axis Type	🖂 Assignment partner [IN/OUT]*	Assignment
Drive assignment	Al	All
Encoder assignment	1 > Define assignment later	
Summary	2 🖂 🗊 S120_CU320	Set up addresses
	3 ^L 🔂 Drive_1.Actor	Free
	4 🖂 🗊 S120_CU320_2_DP	Create drive
	5 ^L 🔂 Drive_1.Actor	Free
	6 🕞 🗱 SINAMICS_Integrated	Create drive
	7 fin Drive_1.Actor	assign
	8 ^L 🔂 Drive_2.Actor	Free
	Motor type: St.	andard motor 🖉

Figure 7-40 Assigning a drive

The following setting options are available for the drive assignment:

- Assign drive Assigning a previously configured drive
- Assign later The TO axis is to be assigned to a drive at a later point in time. This enables
 - The PLC and motion control functions to be completely configured by a programmer even without drive know-how using technology objects (e.g. TO axis) and loaded to the device
 - The drives to be separately configured and optimized by a drive expert and
 - The technology objects to be symbolically assigned later to the drive objects via an interconnection dialog box

Create drive

From the assignment dialog box, a new drive can be created on an existing drive unit (e.g. S120 CU320-2 or SINAMICS Integrated) and assigned to the axis. This allows the axis, including the drive, to be created in one operation. It is not necessary to configure a drive before creating an axis.

• Set up addresses

The addresses must be set up manually if "Symbolic assignment and adaptation" is not used. This corresponds to the previous methods of the drive and axis configuration, available in SCOUT versions < V4.2. This is required, for example, for drive units that do not support symbolic assignment (e.g. SINAMICS S120 with FW version < 2.6.2, MASTERDRIVES, SIMODRIVE, etc.)

The address list in the "All Addresses" view provides an overview of the assignments to all interfaces of the TO axis. From this view, the assignments can also be changed via the interconnection dialog box (_____ button).

Note

The methods of the drive and axis configuration, previously available in SCOUT versions < V4.2, are still available. The symbolic assignment must be deactivated for these methods.

4. Run through the wizard and enter the settings of your system. The required axis message frames as well as the addresses used are automatically specified by the engineering system. Message frames are also extended and interconnections created automatically in the drive depending on the selected TO technology (e.g. SINAMICS Safety Integrated)

5. Click **Finish** to confirm the "Summary" window. The configured real axis is displayed in the project navigator.

Axis configuration - Axis_1	- Summary	
 ✓ Axis Type ✓ Drive assignment 	All the necessary data for configuration has been entered:	
Encoder assignment Summary	Name: - Axis_1 Technology: - Position axis Axis type: - Linear axis - Electric Axis mode: - Standard Drive: - SINAMICS_Integrated.Drive_1.Actor Encoder: - SINAMICS_Integrated.Drive_1.Encoder_1 Encoder type: - Incremental	
	< Back Finish Cancel Help	

Figure 7-41 Axis wizard summary

Note

During system power-up, reference variables as well as drive and encoder data of the SINAMICS are automatically taken over for the SIMOTION configuration data of the SIMOTION technology objects "TO axis" and "TO externalEncoder".

Encoder assignment

With a position axis, encoder 1 is also created at the Axis TO (motor encoder) and automatically assigned to the first encoder on the drive.

If encoder 2 (direct encoder) is created at the TO axis, it is assigned to the second encoder of the drive control.

Result

The configured axis will appear in the project navigator.

Save and compile the project and download it to the target system.

On completion of the axis wizard, the symbolic drive assignment is visible:

- Via the "configuration" of the axis
- Via the address list (view all addresses)

The assignment dialog box can be called again from these dialog boxes using the "____" button.

Instead of calling the assignment dialog, it is also possible to edit the input field SINAMICS_Integrated.SERVO_02.Actor ... containing the symbolic name directly.

Safety data block (SIDB) and technology data block (TDB)

The activation of

- The technology data block (for the cyclic exchange of technology data, e.g. actual torque value) and
- The safety data block (to support the SINAMICS Safety Integrated extended functions by the TO)

can be made in the Configuration of the TO Axis dialog box. ("Change ..." button under functions).

The assignment is always made to the drive DO of the actuator of the axis. The system automatically generates a message frame extension and the BICO interconnection of the relevant SINAMICS parameters.

Note

The safety data block (SIDB) is automatically configured by the engineering system and interconnected in the drive.

The PROFIsafe message frame must be configured by the user.

If the activation of the safety functions is to be made using PROFIsafe, configure the PROFIsafe communication to the higher-level SIMATIC F-CPU (see *SINAMICS S120 Safety Integrated* Function Manual).

I/O signals at the TO axis

For the assignment of I/O signals on the TO axis (e.g. the inputs for the homing output cam or hardware limit switches), call the assignment dialog box from the parameterization dialog boxes of the created TOs or from the address list (view of all addresses) by clicking the _____ button.

See also

See Section Downloading a project to the target system (Page 161). For further information about the symbolic assignment, see the *SCOUTBasic Functions Function Manual.*

7.7.3 Testing the axis with the axis control panel

Axis control panel

The axis control panel is used exclusively for testing axes. You can use the axis control panel for the following tasks, for example:

- To test each part of the system individually before program-driven axis motions are initiated.
- In the event of an error, to test whether the individual axes and drives can be traversed from the axis control panel
- To traverse the axes for optimization purposes (controller optimization)
- To perform active homing
- To set and remove the axis enable
- To test an axis that has been created

Requirement

The following requirements must be fulfilled for testing:

- The project has been downloaded to the target system.
- SIMOTION SCOUT is in online mode.
- The mode switch is in position STOPU.

Recommendation: Operate the mode selector **only** via SIMOTION SCOUT ("Target system" > "Control operating mode").

Axis test

1. Open the AXES folder in the project navigator and click the "Control Panel" entry below the axis (for example, Axis_1).

The axis control panel is displayed.

D435 - Axis_1	- Relp
Assume control priority	v = */s 0 '' ' 200% v = * 100.00 %
Axis stationary S Axis alarm Drive error Velocity: In operation Enables available Position: Power enable Position:	pecified Actual */s
Velocity limitation (pluslimitsofdyn 🔪 100000000000.0 */s	Remaining distance * Following error: * Active data set: 1
📕 Alarms 💋 Control panel 📰 Symbol browser 🛛 🎛 Target system output 🕽	🌐 Compile/check output 🏢 Load to PG output 👫 Diagnostics overview

Figure 7-42 Axis control panel

- 2. To display the control range and axis diagnostics, click the "Show/hide control range" and "Show/hide diagnostics area" buttons.
- 3. Click "Assume control priority".

If the CPU is in RUN mode, confirm the prompt that appears with "Yes" to set the control to STOPU mode.

Note

In order to move the axis from the PG/PC, you must assume control priority. However, by pressing the SPACER bar, you can stop the axis at any time.

If you are using the axis control panel for a real axis, you must first activate the infeed for SINAMICS drives before the axis can be moved. The infeed must be activated before you enable the axis.

4. The "Assume Control Priority" dialog box is opened.

Read the notices and click "Accept" to confirm. The activated Service function is displayed via the LEDs (RUN flashes green at 2 Hz and SU/PF flashes yellow at 2 Hz)

5. To enable the axis, click the "Set/remove enable" button.

Confirm the "Switch Axis Enable" dialog with with "OK".

Note

If you are using **an infeed without a DRIVE-CLiQ interface**, you will have to interconnect the "Infeed operation" signal (drive parameter p864) yourself.

If you are using **an infeed with a DRIVE-CLiQ interface**, select the infeed for which the control priority is to be assumed under "Infeed" in the "Switch Axis Enable" dialog box. Select this checkbox when the control priority is to be fetched and activated. If the infeed signal "Closed-loop control operation" already has a BICO interconnection to the drive, the infeed is permanently specified (infeed selection and checkbox are grayed out).

- 6. To traverse the axis, click the "Position-controlled traversing of the axis" button.
- 7. Enter a velocity and close the dialog box by clicking "OK".
- 8. Click the "Start motion" button to traverse the axis. You can monitor the traversing motion under speed and position. Use "Stop motion" to stop axis movement again.
- 9. To cancel the enable and switch off the infeed, click the "Set/remove enable" button. Confirm the "Remove Axis Enable" dialog with with "OK".
- 10.Click the "Give up control priority" button to deactivate axis control from the PG/PC. In this operating mode, the axes can no longer be controlled from the PG/PC.

See also

Activating the infeed (line module) (Page 213)

7.8 Activating the infeed (line module)

Requirement

Before a drive can be traversed, the infeed (line module) must be switched on and the "Closed-loop control operation" signal of the infeed must be present at the drives.

If this is not taken into account, this can result in a fault state, and in the worst case, damage to the infeed.

How the infeed is controlled and how the drives receive the Ready signal depends on the type of infeed used.

A distinction is made between:

- Infeeds without DRIVE-CLiQ connection
- Infeeds with DRIVE-CLiQ connection

7.8 Activating the infeed (line module)

7.8.1 Infeed without DRIVE-CLiQ connection

The infeed is controlled via terminals on the line module, e.g. DO Ready (DC link is precharged and 'pulse enable is set).

These terminals must be connected to the SIMOTION D4x5 (e.g. wire "DO Ready of the infeed" to "X122, DI 0 of the D4x5").

The enable signal is queried when the drive is configured and must be interconnected accordingly.

Configuration - SINAMICS	Integrated - Power unit BICO		
Control structure	Drive: Drive_1, DDS 0		
Power unit BICO Power unit connection Motor Motor holding brake Encoder Process data exchang Summary	Infeed in operation	Drive in operation	
	Control_Unit Further interconnections enables	 r722 : Bit0, CO/BO: CU digita r722 : Bit1, CO/BO: CU digita r722 : Bit2, CO/BO: CU digita r722 : Bit3, CO/BO: CU digita r722 : Bit4, CO/BO: CU digita r722 : Bit5, CO/BO: CU digita 	inputs, status: : DI 0 (X122.1/X121.1) (1=High / 0=Low) inputs, status: : DI 1 (X122.2/X121.2) (1=High / 0=Low) inputs, status: : DI 2 (X122.3/X121.3) (1=High / 0=Low) inputs, status: : DI 3 (X122.4/X121.4) (1=High / 0=Low) inputs, status: : DI 4 (X132.1) (1=High / 0=Low) inputs, status: : DI 5 (X132.2) (1=High / 0=Low)
		r722 : Bit6, CO/BO: CU digita r722 : Bit7, CO/BO: CU digita	l inputs, status: : DI 6 (X132.3) (1=High / 0=Low) l inputs, status: : DI 7 (X132.4) (1=High / 0=Low)
		Further interconnections	
	< Back Next >	Cancel Help	

Figure 7-43 Interconnection of the "Infeed in operation" signal

7.8.2 Infeeds with DRIVE-CLiQ connection

The infeed is controlled via DRIVE-CLiQ. The infeed is switched on or off by the SIMOTION D4x5 via PROFIdrive message frame 370.

If "Symbolic assignments and adaptation" is used, message frame 370 is set automatically when setting standard/automatic (see Section Calling the drive wizard (Page 142)).

7.8 Activating the infeed (line module)

With message frame 370, the required BICO interconnections to the message frame are created automatically on the drive unit.

If an infeed with DRIVE-CLiQ connection has already been created, the infeed signal "Closed-loop control operation, r863.0" is automatically interconnected to "Infeed operation, p864" of the drive when drives are inserted (only applies to drives that are attached to the same drive unit as the infeed).

The **FB_LineModule_control** function block is available on the controller for control and diagnostics of the infeed.

Note

Always create the infeed first so that the infeed "Closed-loop control operation" signal is automatically interconnected to a drive when this is inserted.

Recommendation: If the drive unit has not been configured, use "Configure drive unit" in the project navigator. "Configure drive unit" has the advantage that all basic settings for the drive unit are queried via one wizard.

FB _LineModule_control

The **_LineModule_control** function block (FB) can be used to switch the infeed on and off and also perform simple diagnostics.

The following infeeds are supported by the **_LineModule_control** function block:

- Basic line modules (BLM)
- Smart line modules (SLM)
- Active line modules (ALM)

The **_LineModule_control** FB is part of the command library of the "SIMOTION SCOUT" engineering system. You can find the FB at "Drives" \Rightarrow "SINAMICS".

For detailed information on the **_LineModule_control** FB, refer to the SIMOTION SCOUT online help or the *Standard Function for SINAMICS S120 Line Modules* Function Manual.

CX32

Further information on how to use line modules with the CX32 can be found in Section Interconnecting the infeed "Operation" signal on the CX32.

Additional references

For a detailed description of the control words and status words of the PROFIdrive message frames for SINAMICS S120 drives, see the *SINAMICS S120 Commissioning Manual*.

See also

Interconnecting the infeed "Operation" signal on the CX32 (Page 185)

7.9 Setting up addresses and message frames

7.9 Setting up addresses and message frames

Overview

After all SINAMICS components have been configured, addresses must be determined for the process data exchange between the drive and the controller.

This procedure depends on whether symbolic assignments are used.

- With **symbolic assignment**, the addresses are determined automatically by the engineering system, see Section Setting up communication for symbolic assignment (Page 216)
- Without symbolic assignment, the determination of the addresses must be started manually, see Section Message frame configuration (Page 216).

7.9.1 Setting up communication for symbolic assignment

The communication for symbolic assignment is set up with the following actions:

- Via the SCOUT menu (call the following in the menu: "Project" > "Set up communication for symbolic assignment")
- at "Download project to target system"
- at "Save project and compile changes"

When setting up the communication, the message frames, BICO interconnections and addresses are set up for the entire project.

See also

Message frame configuration (Page 216)

7.9.2 Message frame configuration

Requirement

You have configured the drive unit.

On the basis of this configuration, one or more of the following actions should be performed:

- The automatic PROFIdrive message frame setting for a drive object should be activated/deactivated
- The automatic message frame extension for a drive object should be activated/deactivated
- The automatic address adaptation for a drive object should be activated/deactivated
- PROFIdrive message frames should be configured for drive objects
7.9 Setting up addresses and message frames

- The addresses should be set up
- Message frames should be extended manually

Procedure

Proceed as follows:

In the project navigator, open the "Communication" > "Message frame configuration" entry under "SINAMICS_Integrated".

The "SINAMICS Integrated - Message Frame Configuration" dialog box is displayed with the PROFIdrive PZD message frames tab.

The dialog box lists all the available drive objects. The possible setting options are described in the following.

Note

When using the symbolic assignment, the default setting does not have to be changed or configured.

Note

When using the symbolic assignment, the default setting does not have to be changed or configured.



Figure 7-44 Message frame configuration

7.9 Setting up addresses and message frames

Table 7- 7	Explanation of the	ne figure
------------	--------------------	-----------

Number	Meaning					
1	Selection of a message frame					
	• The drive message frames (message frames 1 6 and message frame 1xx) are defined in accordance with the PROFIdrive specification and can be selected based on the required functional scope.					
	• You can transfer the signals of the I/Os or the global measuring inputs, for example, via the message frames 39x. Message frame 39x is also required for the time synchronization between SIMOTION and SINAMICS.					
	 Free message frame configuration with BICO allows you to define your own message frame. 					
	 Free message frame configuration with p915/p916 (for TM15/17). 					
	Message frames 37x for control of the infeed.					
2	The "Standard/automatic" and "User-defined" settings are only visible if "Use symbolic assignment" is activated. Using the setting "Standard/automatic" is generally recommended.					
	The "User-defined" setting allows the automatic message frame setting, message frame extension, and address adaptation to be deactivated or activated.					
	 "Automatic PROFIdrive message frame setting" allows the message frame to be set by the system depending on the configured technology (message frame selection, e.g. for infeed, drive, and control unit incl. onboard I/O). 					
	• "Automatic message frame extension" allows the message frame to be extended by the system depending on the configured technology (e.g. if the technology data block is activated in the axis configuration).					
	• "Permit automatic address adaptation" allows addresses to be adapted by the system in the case of address offsets, for example. Address offsets can occur, for example, if a message frame is extended and the adjacent addresses are already occupied by other message frames.					
	With TM15/TM17 High Feature, "Automatic PROFIdrive message frame setting", "Automatic message frame extension", and "Automatic address adaptation" cannot be deactivated by design, since for these drive objects the message frame is always set up in accordance with the parameterized terminal functionality (DI, DO, output cam, measuring input) and cannot be extended.					
	"Automatic PROFIdrive message frame setting" and "Automatic message frame extension" must be deactivated if the message frames are to be configured manually for TM15 DI/DO, TM31, and TB30 and interconnected with BICO.					
See Section Setting up communication for symbolic assignment (Page 216).						
3	The icons in the status column show the following information:					
	The message frame is configured differently in HW Config. You must align it with HW Config.					
	You are using a predefined standard message frame or free BICO interconnection.					
	You are using a modified standard message frame, which you have extended to include additional data.					
	You are using a message frame for which one of the two message frame lengths is too long. The drive object cannot process this entry.					
	Message frame status					
4	Length: Displays the size of the message frame component.					
	Address: Address area in HW Config. The addresses will be displayed only after the addresses have been set up.					
5	Displays the SIMOTION object that is interconnected to the SINAMICS object (e.g. axis or encoder).					

7.10 Linking an additional encoder (optional)

Number	Meaning
6	Changing the message frame sequence Before the alignment, all drive objects without input/output addresses ("") must be moved behind the objects with valid input/output addresses or those still to be aligned ("??????").
7	"Manual" adaptation of the message frame configuration (e.g. when additional data, such as a motor temperature, is to be transferred via the message frame)
8	Display of the individual control and status words of the associated message frame.
9	Setting the addresses (alignment of the addresses with HW Config) Only the addresses of the respective device are determined (no automatic determination of message frames / BICO interconnections)

Note

If symbolic assignment is deactivated, the following applies:

If the message frames for drive objects change (drives, terminal modules, etc.), you must set up the addresses again. The addresses are not updated automatically.

7.10 Linking an additional encoder (optional)

7.10.1 Fundamentals

Using encoders

In addition to a motor encoder, additional encoders can be linked and configured:

- Additional encoders on the drive
 - Encoders with DRIVE-CLiQ interface
 - Encoders connected to a CU310 or CUA32 via the onboard encoder interface
 - Encoders connected to SIMOTION D via an SMx module
- Additional encoders on SIMOTION D
 - Encoders connected via PROFIBUS
 - Encoders connected via PROFINET

7.10 Linking an additional encoder (optional)

Configuring additional encoders

The additional encoder can be used in SIMOTION, for example, as:

• Machine encoder (second encoder = direct measuring system)

A direct measuring system measures the technological parameter directly, i.e. without the interference of influences such as torsion, backlash, slip, etc. This can facilitate improved smoothing of mechanical influences by means of the closed-loop control. If you use a second encoder as a machine encoder, you can work with the encoder changeover function.

• External encoders

You can use the external encoder to record an external master value, for example.

- Encoder for hydraulic axes
- · Encoders for the implementation of cam controllers

7.10.2 Additional encoders on the drive

The following options are available for configuring additional encoders on the drive:

- Configuration of a second encoder on the drive
- Configuration of an encoder as drive object (as of SINAMICS firmware V4.3).

The following options are available for configuring additional encoders on the drive.

Second encoder on the drive

The configuration of a second encoder on the drive is useful when the second encoder value is also to be used for this drive (e.g. motor or machine encoder). Note that only a maximum of two encoder values can be transferred via PROFIdrive message frames.

In principle, the second encoder value can be freely used (e.g. for acquisition of an external master value), however the use of an encoder as a separate drive object (drive object DO encoder) is preferable because of the clear functional separation.

onfiguration - SINAMICS_Integrated - Encoder				
Control structure	Drive: Drive_1, DDS 0, MDS 0			
Power unit Power unit BICO Power unit connection Motor Motor	Which encoder do you want to use?			
Motor holding brake	Encoder 1 Encoder 2			
Summary	Encoder evaluation: SM_1			
	Encoder name: Encoder_2			

Figure 7-45 Configuration of a second encoder on the drive

7.10 Linking an additional encoder (optional)

Encoder as drive object

The configuration of an encoder as drive object (drive object DO encoder) has the advantage that this encoder can be used independently of a configured drive (e.g. for acquisition of a master value).

The configuration is performed by inserting an encoder via the project navigator.

The DO encoder is only available as of SINAMICS V4.3, i.e. only available on control units of the latest generation (e.g. SINAMICS S120 CU320-2, SIMOTION D4x5-2, CX32-2 --- but not for the SINAMICS Integrated of a D4x5 and CX32)



Figure 7-46 Configuration of an encoder as drive object

7.10.3 Additional encoders via PROFIBUS/PROFINET

Additional encoders for the encoder integration can be connected via PROFIBUS or PROFINET. The following options are available:

- Encoder interconnection using a PROFIdrive message frame (encoder with message frame type 81)
- Encoder interface as a direct value in the I/O area

Additional references

Detailed information is contained in the *SIMOTION TO Axis, Electric/Hydraulic, External Encoder* Function Manual

7.11 Symbolic assignment of I/O variables (PROFIdrive message frame / drive parameters)

7.11.1 Symbolic assignment of I/O variables to the PROFIdrive message frame of the TO axis

You can assign I/O variables from the address list which you require for display and diagnostic purposes, for example, to individual components (status word, for example) of the PROFIdrive message frame using the assignment dialog. Only components suitable for the data type of the I/O variable are displayed. If no data type is specified at the I/O variable, this is determined via the assignment partner after the selection.

As	Assign D445.my_variable					
Γ		🗆 Assignment partner [IN]	Assignment			
ľ	1	All	All			
ſ	1	> Free address input				
	2	SINAMICS_Integrated				
	3	🕀 🗗 Control_Unit				
	4	🔁 💼 Drive_1				
	5	+ Actor				
	6	- Encoder_1				
	7	Gn_XIST1	assign			
	8	⊕ Gn_XIST2	Free			
	9	L⊕ Gn_ZSW	Free			
	10	L 🖀 Parameter selection				
	11	t⊕ 🙍 Drive_2				
	12	L⊕ 🛗 Supply				
	Pead the following situations of the police below					
- The expected assignment partners are not displayed. - Assignment to non-SINAMICS devices (free address input)						
		ОКСС	ancel Help			

Figure 7-47 Assignment of I/O variables to the PROFIdrive message frame

7.11.2 Symbolic assignment of I/O variables to drive parameters

I/O variables from the address list can be assigned to drive parameters using the assignment dialog. Only parameters suitable for the data type of the I/O variable are displayed. If no data type is specified at the I/O variable, this is determined by the parameter selection.

An extension of the standard message frame is created automatically for the transfer of the parameters to/from the drive.

Procedure

- Open the assignment dialog box from the address list (view of all addresses). The assignment dialog opens with the corresponding assignment partners.
- 2. Click the ____ button in the parameter selection line to open the parameter list.

Assign D	425.My_temp	×
	Assignment partner [IN]	Assignment
1	> Free address input	
2	2	
3	3 🕀 🗗 Control_Unit	`
4	🖡 🦕 🔂 Drive_1	
6	5 🕀 Actor	
6	€ Encoder_1	
7	Parameter selection	
	• • • • • • • • • • • • • • • • • • •	
	Read the following situations of the online he . The expected assignment partners are not	lp: displayed
	 Assignment to non-SINAMICS devices (free 	address input)
	-	
	OK C	ancel Help

Figure 7-48 Assignment dialog for drive parameters

3. Select the desired signal source (e.g. DO drive). Then select the required parameter.

Please se	lect the signal source	Transfer as 16-bit value				
Drive_1		O Transfer as 32-bit value				
	⊕P no.	Parameter text				
T.	All 🗾	All				
1	r21	CO: Actual speed smoothed				
2	r25	CO: Output voltage smoothed				
3	r26	CO: DC link voltage smoothed				
4	r27	CO: Absolute actual current smoothed				
5	r32	CO: Active power actual value smoothed				
6	r34	:O: Motor utilization				
7	r35	CO: Motor temperature				
8	r36	CO: Power unit overload I2t				
9	⊕r37	Power unit temperatures, Inverter, maximum value				
10	r46	CO/BO: Missing enable sig				
11	r50	CO/BO: Command Data Set CDS effective				
12	r51	CO/BO: Drive Data Set DDS effective				
13	r56	CO/BO: Status word, closed-loop control				
14	r60	CO: Speed setpoint before the setpoint filter				
15	r⊕ r61	Actual speed unsmoothed, Encoder 1				
		OK Cancel				

Figure 7-49 Dialog box for the DO and parameter selection

4. Click "OK" to accept the selection.

5. The desired SINAMICS parameter is assigned to the I/O variable in the interconnection dialog box.

Ass	ign D4	25.my_temp	X
Г		🗆 Assignment partner [IN]	Assignment
	T _i	All	All
	1	> Free address input	
	2	SINAMICS_Integrated	
	3	🔁 🗗 Control_Unit	
	4	🔁 🙍 Drive_1	
	5	t⊕ Actor	
	6	⊕ Encoder_1	
	- 7	L 🖀 Parameter selection	
	8	l 📔 bico_iw.r35	assign
	9	L 🕀 🔛 Supply	
	10		
	9	Read the following situations of the online he - The expected assignment partners are not - Assignment to non-SINAMICS devices (free	lp: displayed. • address input)
		ОК С	ancel Help

Figure 7-50 Assigned drive parameters

6. Click "OK" to accept the assignment.

The following table shows the possible types of assignment:

Name of the assignment	Data type	Direction	Transferrable BICO parameters
BICO_IW. <parameter number=""></parameter>	WORD	Input	All CO parameters (BICO source)
BICO_QW. <parameter number=""></parameter>	WORD	Output	All CI parameters (BICO sink)
BICO_ID. <parameter number=""></parameter>	DWORD	Input	All CO parameters (BICO source)
BICO_QD. <parameter number=""></parameter>	DWORD	Output	All CI parameters (BICO sink)

Syntax of the assignment names

- A number of parameters (separated by periods) are specified for outputs (SINAMICS side = received data) which can be interconnected with a number of BICO sinks.
- If the transferred parameter is on another drive object (DO), the DO name precedes the parameter. "#" is used as a separator between the DO name and the parameter.
- Individually transferred bits of a parameter appear in brackets [x].

7.12 Configuration of drive-related I/Os (with symbolic assignment)

7.12 Configuration of drive-related I/Os (with symbolic assignment)

Overview

SIMOTION D4x5, the CX32 controller extension as well as the SINAMICS S110/S120 control units and additional components (TB30, TMs) have I/Os that can be used by the drive unit and SIMOTION.

So that I/Os, which were originally assigned to SINAMICS can be used by SIMOTION they must be interconnected to a message frame.

Symbolic assignment

As of version V4.2, SIMOTION SCOUT supports the symbolic configuration of I/Os. "Use symbolic assignment" must be activated for this purpose (see also Section Symbolic assignment/adaptation (Page 135))

The symbolic assignment simplifies the configuration significantly:

 Table 7-8
 Comparison of configuration with/without symbolic assignment

	With symbolic assignment	Without symbolic assignment
Configuring message frames	So that SIMOTION can use SINAMICS I/Os, the required message frames are created automatically	Message frames must be set manually (either predefined message frame (e.g. 39x) or free message frame configuration)
BICO interconnections	The required BICO interconnections are made automatically (I/Os are interconnected to message frame)	With predefined message frames (e.g. 39x), the BICO interconnections are made automatically
		With free message frame configuration with BICO, the interconnection must be made by the user
Parameterization the I/O functionality (e.g. measuring input)	Parameterization via screen forms	Parameterization via screen forms and partly via parameters in the expert list
Handling of I/O addresses	Handling of addresses is not required because of symbolic assignment	I/O addresses must be determined
Setting up addresses	Addresses are set up automatically, see also Section Setting up communication for symbolic assignment (Page 216)	Addresses must be set up manually, see also Section Message frame configuration (Page 216)

Only the configuration with symbolic assignment is described in the following. For further information on the configuration of drive-related I/Os without symbolic assignment, see Appendix

Configuration of drive-related I/Os (without symbolic assignment) (Page 323).

7.12 Configuration of drive-related I/Os (with symbolic assignment)

Procedure

The configuration of the I/Os is divided into two basic steps:

- 1. Configuration of the I/O terminals (Page 227). The functionality of an I/O channel is configured (e.g. configuration of a DI/DO as digital output)
- Configuration of the technology objects and I/O variables (Page 230). The access of technology objects and I/O variables to I/Os is configured. The configuration is performed symbolically, whereby only "function-compatible" I/O channels are offered for selection. Example: For the TO measuringInput, only symbolic assignments of the type MI (measuring input) are offered for selection.

The required message frames and the interconnection are then set automatically by the engineering system.

See also

Configuration of drive-related I/Os (without symbolic assignment) (Page 323)

7.12.1 Configuration of the I/O terminals

The following table provides an overview of the configuration options for the I/O terminals of various modules.

Module	Use of the I/Os by		Configuration of the I/O terminals	Supports symbolic assignment
	SIMOTION	SINAMICS		
SIMOTION D4x5-2				As of SIMOTION V4.2
- X122/X132	X ¹⁾	Х	On the drive unit (CU)	
- X142	х	-	On the D4x5-2 (HW Config)	
SIMOTION D4x5	X ¹⁾	Х	On the drive unit (CU)	As of SIMOTION V4.2
CX32-2,	X ¹⁾	х	On the drive unit (CU)	As of SIMOTION V4.2
CX32				
SINAMICS S110 CU305	X ¹⁾	х	On the drive unit (CU)	As of SINAMICS V4.3
SINAMICS S120	X ¹⁾	Х	On the drive unit (CU)	
- CU310				- As of SINAMICS V2.6.2
- CU320				- As of SINAMICS V2.6.2
- CU320-2				- As of SINAMICS V4.3
TB30, TM15 DI/DO, TM31	X ¹⁾	x	On the drive unit (TB30 or TM)	Yes

Table 7-9 Overview of the configuration of the I/O terminals

Commissioning (software)

7.12 Configuration of drive-related I/Os (with symbolic assignment)

	Use of the I/Os by		Configuration of the I/O terminals	Supports symbolic assignment
TM41	X ¹⁾	Х	On the drive unit (TM41)	Yes ²⁾
TM15, TM17 High Feature	x	-	On the drive unit (TM15 or TM17)	Yes

¹⁾ I/Os are originally assigned to a SINAMICS drive unit and can be assigned to SIMOTION via configuration

²⁾ TM41 only supports the symbolic assignment for the encoder interface (no symbolic assignment for the DI, DO and AI)

Note

The module hardware for TM15 and TM15 DI/DO is identical. A distinction is only made by the addition of the component in the SIMOTION SCOUT project navigator using "Inserting input/output component".

I/Os that are originally assigned to the SINAMICS drive unit can also be used by SIMOTION via configuration.

- An output is always only exclusively available for the SINAMICS drive unit or SIMOTION.
- An input used by SIMOTION can also be interconnected on the drive side.

The configuration of the I/O terminals is described in detail in the following:

- Configuration of the D4x5 I/Os (terminal X122/X132) (Page 228)
- Configuration of the CX32/CU3xx/TB30/TMxx I/O terminals (Page 229)

7.12.1.1 Configuration of the D4x5 I/Os (terminal X122/X132)

Procedure

The I/Os of terminals X122 and X132 are originally assigned to the drive unit. The configuration is therefore performed via the drive unit ("SINAMICS_Integrated" > "Control_Unit" > "Inputs/outputs).

The properties of the I/O channel can be configured in the parameterization dialog box. With the bidirectional digital inputs/outputs, for example, an I/O channel can be:

- Parameterized as input or output
- Inverted
- BICO-interconnected (use as drive I/O)
- Used as digital input for SIMOTION with "DI (SIMOTION)"

7.12 Configuration of drive-related I/Os (with symbolic assignment)

- Used as digital output for SIMOTION with "DO (SIMOTION)"
- Used as global measuring input for SIMOTION with "Measuring input (SIMOTION)"



Figure 7-51 Configuration of the D4x5 I/Os (terminal X122/X132)

7.12.1.2 Configuration of the CX32/CU3xx/TB30/TMxx I/O terminals

The configuration is performed in a similar way as for the onboard I/Os X122/X132 for the SIMOTION D4x5, i.e. I/Os can be

- BICO-interconnected (use as drive I/O)
- Used by SIMOTION

See also Section Configuration of the D4x5 I/Os (X122/X132) (Page 228)

Note

If symbolic assignment is subsequently activated for a project in which message frames have already been configured and interconnected, these can be changed together with the BICO interconnections!

For this reason, make a backup copy of your project before activating the symbolic assignment. TB30, TM15 DI/DO and TM31 are especially affected.

See also Section Symbolic assignment / adaptation (Page 135)

7.13 Configuration of the technology objects and I/O variables

7.13.1 Configuration of global measuring inputs

Overview

The type of measuring input must be selected during the configuration of the TO measuringInput.

The following measuring input types are available:

Table 7-10 Measuring input types

Measuring input types	Explanation
Standard (global measuring input)	Compared with the drive-related local measuring inputs, global measuring inputs have extended functionality and also support a symbolic configuration. They are therefore set as standard.
Drive-related (local measuring input)	The drive-related local measuring inputs are configured via drive parameters, see Section Configuration of drive-related I/Os (without symbolic assignment) (Page 323) in the appendix.
Listening measuring input	Through the configuration of a listening measuring input, measuring can be performed simultaneously on several axes or external encoders with one measuring input. Detailed information can be found in the <i>SIMOTION Motion Control Output Cams and Measuring Inputs</i> Function Manual.

A detailed comparison of "local" and "global" measuring inputs as well as an overview of which modules support local or global measuring inputs can be found in Section Configuration of drive-related I/Os (without symbolic assignment) (Page 323) in the appendix.

Procedure

If a global measuring input is selected, it must be assigned a hardware input.

To do this, open the assignment dialog box via ____ and select a free (i.e. not yet used) I/O.

Note

Only those I/Os are displayed that have the appropriate measuring input functionality (MI_xx [channel name, terminal number]). If no suitable I/Os are displayed, you must first configure the I/Os (I/O must be configured as "measuring input")

Commissioning (software)

7.13 Configuration of the technology objects and I/O variables

SIMOTION SCOUT - Sample - [D445.Measuri	ing_Input_1 - Configuration] Options Window Help	_ 🗆 × _ ð ×
Sample Sa	Configuration Units Name: Measuring_Input_1 Proc. cycle clock IPD Axis measuring system no: 1 Correction value for time stamp: 0.0 Measuring input selection: • Standard (global measuring input) Drive-related (local measuring input) • Define assignment later Dive-related (local measuring input) • Define assign Monitoring measuring input • • • • • • • • • • • • • • • • • • •	
Homing Homing Profiles Control panel Signal flow Massuing_Input_1 Configuration Expent lat Default Cutrput_CAM Project Command library		

Figure 7-52 Configuration of a global measuring input for the D4x5

Detailed information on the configuration of the TO measuringInput can be found in the *SIMOTION Output Cams and Measuring Inputs* Function Manual.

7.13.2 Configuration of local measuring inputs

Local measuring inputs are drive-related measuring inputs. The configuration is performed via drive parameters.

For further details, see:

- Section Configuration of drive-related I/Os (without symbolic assignment) (Page 323) in the appendix
- SIMOTION Output Cams and Measuring Inputs Function Manual

See also

Configuration of drive-related I/Os (without symbolic assignment) (Page 323)

7.13.3 Configuration of output cams / cam tracks

Overview

The type of cam output must be selected during the configuration of the TO outputCam and TO camTrack.

The following output types are available:

Cam output on	Explanation						
Cam output (CAM)	The cam output is performed on the basis of an internal time stamp. The temporal resolution of the cam output depends on the hardware used.						
	Supported hardware:						
	 SIMOTION D4x5-2 (terminal X142): Resolution 1 μs 						
	 TM17 High Feature: Resolution 1 µs 						
	 TM15: Typical resolution 125 μs (DRIVE-CLiQ cycle clock) 						
High-speed digital output (DO)	The cam output is performed via onboard outputs of the SIMOTION CPU. The output is via a hardware timer, whereby the cam output is achieved with a resolution with respect to time < servo cycle clock.						
	Supported hardware:						
	SIMOTION D4x5 (terminal X122, X132)						
	SIMOTION D410 (terminal X121)						
	SIMOTION C240, C240 PN (terminal X1)						
Standard digital output (DO)	The output cam calculations are performed in the execution cycle (IPO or IPO2 cycle clock or in the servo cycle clock). The actual cam output is performed in the servo cycle clock. The resolution with respect to time of the cam output is generally reduced by the output cycle of the I/O used.						
	The resolution is therefore dependent as follows:						
	 For the standard I/O (e.g. ET 200), on the cycle time of the bus system (PROFIBUS DP / PROFINET IO) 						
	 For the TM15 / TM17, on the cycle time of the bus system (PROFIBUS Integrated / PROFIBUS DP / PROFINET IO) 						
	 For the TM15 DI/DO, TM31, TM41, TB30, on the configured sampling time: 						
	 cu.p0799 (CU inputs/outputs sampling time) for the TB30 and onboard outputs 						
	 p4099 (TMxx inputs/outputs sampling time) for TM15 DI/DO, TM31 and TM41 						
	Supported hardware:						
	 Onboard outputs (SIMOTION D, CX controller extension, SINAMICS CU3xx control unit) 						
	Centralized I/O (SIMOTION C)						
	 Distributed I/O via PROFIBUS DP / PROFINET IO (e.g. ET 200, etc.) 						
	 Drive-related I/O (TM15, TM15 DI/DO, TM17 High Feature, TM31, TM41, TB30) 						

Table 7-11 TO outputCam / TO camTrack output types

Procedure

To achieve the best possible output cam resolution on the onboard I/Os of a SIMOTION D4x5, activate the output and select "Cam output on fast digital output (DO)".

Then assign a hardware output. To do this, open the assignment dialog box via ____ and select a free (i.e. not yet used) I/O.

Note

Only those I/Os are displayed that have the appropriate functionality (DO_xx [channel name, terminal number]). If no suitable I/Os are displayed, you must first configure the I/Os (I/O must be configured as "DO")



Figure 7-53 Configuration of an output cam for the D4x5

Detailed information on the configuration of the TO outputCam / TO camTrack can be found in the *SIMOTION Output Cams and Measuring Inputs* Function Manual.

7.13.4 Configuration of the I/Os (variables / TO axis)

I/O variables

The I/O variables are configured via the address list. Components that support a symbolic assignment can be configured without I/O addresses. Components that do not support symbolic assignment (e.g. standard PROFIBUS I/O) are configured via I/O addresses.

D445 : Address list																	
C 💡 View	1/0s			•													
Name	▲ I/O addres	ss Rea	d or Data typ	e	Array	le Pro	ocess image	Strategy	Disp	olay	Replacemen		Control valu Ass	signment		Assign	nr
All	💌 All	🔳 All	🔳 All	-	Al 🗈	All	•	All 🗾	All	•	Ali 🗾	All 💌	All 💌 All		•	All 📘	•
1 Sensor	IN		BOOL			1							Not :	assigned			
2																	
							A	ssign D4	45.Se	nso	r				×	1	
													K				
									🗆 As:	sign	ment partne	r (IN)		 Assignment 			
								Tix 1	4.II					💌 All	▼		
								1	⇒ Fi	ree	address inpu	ıt					
								2		SIN/	MICS_Integrat	ed					
								3	E	3 EV	Control_Unit						
								4		-	S-DI_8 [DI/DO	28, X	122.7]	Free			
								5		ŀ	S-DI_11 [DI/D	0 11,	X122.11]	Free			
								6		ŀ	S-DI_13 [DI/D	013,	X132.8]	Free			

Figure 7-54 Address list

TO Axis

The symbolic assignment of I/Os is also supported by the TO axis (e.g. for a HW limit switch).

Substitute values for I/O variables

Substitute values cannot be specified for input variables of the BOOL data type. If you do require substitute values however, proceed as follows:

- 1. Assign a digital input (e.g. SINAMICS_Integrated.Control_Unit.DI_0 [DI 0, X122.1]) to an input variable of the BOOL type (e.g. sensor).
- 2. Create a global variable (e.g. all_inputs) (at least data type WORD, e.g. SINAMICS_Integrated.Control_Unit.DI_0_15).
- 3. Configure the substitute value The appropriate bit of the substitute value must then contain the substitute value for the BOOL variable.

In the same way, you can assign a substitute value to a BICO parameter.

For various SINAMICS drive objects, higher-level types are available for the assignment of substitute values.

	D445:/	Address list															
	View	1/0s 💌													0	?	
ſ		Name A	•	Data type	A	Array le	Process image	Strategy	Displa	y Replacemer		Control valu	Assignment	Assi	ign r C	omment	
ľ	Tie	All	-	All 🗾	A	All 🔳	All 🗾	All 💌	AI	AI 🔳	Al	Al 🔳	All	💌 All	– A	JI.	-
	1	Sensor	E	BOOL		1							SINAMICS_Integrated.Control_Unit.DI_0 [DI 0, X122.1]	4: Se	t up		
	2	All_inputs	1	WORD	Τ	1		Ersatzw	HEX	16#00_00			SINAMICS_Integrated.Control_Unit.DI_0_15	4: Se	t up		
II.	3																

Figure 7-55 Configuration of substitute values

7.14 DMC20/DME20 DRIVE-CLiQ hub

7.14.1 Hub properties

DRIVE-CLiQ hub characteristics

The DMC20 and DME20 DRIVE-CLiQ hub modules are used to implement point-to-point distribution of a DRIVE-CLiQ line. With the DMC20/DME20, an axis grouping can be expanded with four DRIVE-CLiQ sockets for additional subgroups.

- DMC20 is the hub for the control cabinet configuration
- DME20 is the hub for use without a control cabinet (IP67 degree of protection).

The modules are especially suitable for applications which require DRIVE-CLiQ nodes to be removed in groups, without interrupting the DRIVE-CLiQ line and therefore the data exchange.

Application examples

Typical applications of DRIVE-CLiQ hubs are encoder expansion and hot plugging.

- In an encoder expansion, direct measuring systems are connected. For example, these
 are attached directly to the machine in the control cabinet. Several encoders can be
 connected to one hub in the cabinet.
- Hot plugging is the option for changing motor modules while in operation. To do so, the motor modules are connected via a DRIVE-CLiQ hub in the form of a point-to-point topology. This means they can be deactivated without impairing downstream components (via cascading).

Note

Cascading is permitted one time only (from hub to hub).

Additional references

Additional information on the DMC20/DME20 DRIVE-CLiQ is contained in the

- *SIMOTION D4x5* Manual.
- SINAMICS S120 Control Units and Additional System Components Manual.

7.15 TM41 Terminal Module

7.14.2 Creating a DMC20/DME20 DRIVE-CLiQ hub

Introduction

A DMC20/DME20 can be inserted directly in the project navigator. The hub is not wired when you insert the DMC20/DME20 and is displayed in the topology tree in the component storage. The hub has to be wired manually.

Procedure

- 1. Right-click "Topology" in the project navigator.
- Select the "Insert new object" > "DRIVE-CLiQ hub" command from the context menu and confirm with "OK".
- 3. Double-click "Topology" to display the topology tree.

In the topology tree, the hub is stored in the component archive.

4. Drag-and-drop the hub to the required DRIVE-CLiQ interface.

The components connected to the hub are displayed in the topology tree.

Result

The added hub is displayed for the "Topology" entry in the project navigator. All components connected to a hub are also displayed during an automatic configuration.

7.15 TM41 Terminal Module

7.15.1 Overview

The TM41 terminal module can be used to expand the number of digital I/O and of analog inputs within a drive system. TM41 also returns TTL signals which emulate an incremental encoder, for example, for a master control system.

The emulated encoder signal has the signal characteristic of an incremental TTL encoder (A track, B track, R track). The resolution of the encoder signal can be specified in the configuration.

Note

The digital I/Os and the analog input can be interconnected with BICO configuration in the same way as a TM31.

The TM41 encoder interface (incremental encoder representation) can

- Be interconnected with an encoder signal of the control unit by means of parameterization, e.g. sin/cos incremental encoders. For detailed information, see the SINAMICS manuals.
- From the SIMOTION viewpoint, can be accessed as axis. This allows you to return the axis position (a master value) as an encoder signal to a second controller, for example. The configuration can be performed symbolically and is described in the following.

Note

TM41 only supports the symbolic assignment for the encoder interface (no symbolic assignment for the DI, DO and AI).

Configuring the TM41 involves the following steps:

- Configuring TM41 at SINAMICS Integrated
- Configuring TM41 using the axis wizard.

7.15.2 Configuring TM41 at SINAMICS Integrated

TM41 can be configured after you completed the configuration of SINAMICS Integrated. Proceed as follows:

- 1. Double-click "Insert input/output component" at "Input/output component" in the project navigator.
- 2. Select TM41 from the "Drive object type" field of the "Insert Input/Output Component" dialog box and assign a unique name to the module.
- 3. Confirm your entry with "OK".

The TM41 is inserted in the project navigator by the name you entered.

- 4. Double-click "Inputs/outputs". The "Inputs/Outputs Properties" dialog box of TM41 opens.
- 5. Set "SIMOTION" as the operating mode on the "Pulse encoder emulation" tab, and make the settings for the emulated sensor signal.
- 6. Double-click "Configuration" under "SINAMICS_Integrated" in the project navigator and select the "PROFIdrive message frame" tab.
- 7. Click "Close" to exit the dialog box.

You programmed TM41 and aligned it with HW Config.

7.15.3 Configuring TM41 using the Axis Wizard.

After configuring the TM41 for a SINAMICS Integrated device in the project navigator, you can interconnect it with an axis using the axis wizard. The wizard implements the TM41 as drive device.

- 1. Open the axis wizard and create a positioning or synchronization axis (electrical).
- 2. Step the axis wizard forward until the "Drive Assignment" dialog box opens.
- 3. Select "SINAMICS_Integrated" as the drive device and "TM41" as the drive.

TM41 operates as setpoint sink of the axis with this setup.

4. Run through the wizard to the end.

Detailed information on configuring incremental encoder emulation with the TM41 can be found in:

- FAQ list http://support.automation.siemens.com/WW/view/en/27554028
- SIMOTION Utilities & Applications.

SIMOTION Utilities & Applications is part of the scope of delivery of SIMOTION SCOUT.

7.16 Optimizing drive and closed-loop controller

7.16.1 Overview of automatic controller setting

Overview

For the controller optimization of the drive, SIMOTION SCOUT offers a wizard for the automatic controller setting.

In the "Automatic Controller Setting" screen form, you can configure an automatic setting for the speed controller and the DSC (dynamic servo control) position controller for SINAMICS drive units. The necessary steps for this calculation can be controlled from this screen form. The parameter values calculated for the speed controller or position controller are displayed; these can then be transferred online to the drive or axis on the controller. You can set the controller automatically using the menu command "Target system" > "Automatic controller setting".

For a detailed description of the parameters that can be defined, to the *SIMOTION SCOUT* Online Help.

Commissioning (software)

7.16 Optimizing drive and closed-loop controller

Requirements

- You have configured a SINAMICS drive.
- The configured drive is operated in the "Servo" drive object type.
- · Closed-loop control takes place with the motor encoder.
- There is an online connection to the relevant drive unit.

Procedure

Automatic controller setting involves the following steps:

- 1. Setting the speed controller
- 2. Setting the position controller

Note

You can cancel automatic controller setting by pressing the SPACEBAR.

- The step currently being executed is aborted.
- The drive enable is canceled.

Additional references

Information on the controller structure can be found in the *SIMOTION TO Axis, Electric/Hydraulic, External Encoder* Function Manual.

In addition to automatic controller setting, SIMOTION SCOUT also offers the option of optimizing the drive and controller manually by means of measuring functions, trace, and function generator (see Measuring functions, trace, and function generator (Page 242) and Manual speed controller optimization (Page 243) in this manual).

7.16.2 Automatic speed controller setting

Characteristics

The automatic speed controller setting has the following features:

- · Attenuation of resonances in the speed-controlled system
- Automatic setting of the gain factor Kp and the integral time Tn of the speed controller
- The speed setpoint filter and the reference model are not changed

Procedure

To perform an automatic setting of the speed controller, proceed as follows:

- 1. Select the "Target system" > "Automatic controller setting" menu command.
- 2. Select the drive unit and the drive.
- 3. Select the "Speed controller" from the "Controller selection".
- 4. Click "Assume control priority" to assume control priority.
- 5. Press the "Drive On" button to enable the drive.

Perform these steps (1 to 4) in automatic mode or as individual steps.

- 6. Click "Transfer" to transfer the calculated parameter values for the speed controller to the drive.
- 7. Disable the drive by clicking the "Drive Off" button.
- 8. Click "Give up control priority" to give up control priority of the PG/PC.
- 9. Save the online parameters.

You can now transfer the automatically set parameters to the project.

Backing up parameters

Proceed as follows to back up the parameters:

- 1. In the project navigator, select the SINAMICS unit with the drive for which you want to perform the automatic setting
- 2. Select "Target device" > "Copy RAM to ROM" in the context menu.
- 3. Select "Target device" > "Load CPU / drive unit to PG" in the context menu.

If necessary, the automatic controller settings can be verified with the measuring functions.

7.16.3 Automatic position controller setting

Introduction

In the "Automatic Controller Setting" screen form, you can select the SINAMICS drive unit and the drive for which you want to carry out an automatic DSC position controller setting. The necessary steps for this calculation can be performed from this screen form. The calculated Kv value is displayed and can then be accepted online in the configuration data of the axis that is assigned to the drive.

Requirements

In addition to the General requirements for the automatic controller setting, the following boundary conditions apply for setting the position controller:

• DSC is required for the position controller setting. **Tip:**

Activate the project setting "Use symbolic assignment" and select the Standard/Automatic option for the axis-drive communication when configuring the drives. You automatically use DSC for the servo drives with these settings.

- The speed controller has already been configured (e.g. with the automatic speed controller setting).
- At least one axis is connected to the SINAMICS drive (servo).
- An online connection to the SIMOTION device must be established to transfer the results of the automatic position controller setting.
- The balancing filter is not changed.
- For operation without precontrol, the equivalent time constant of the position controller must be adjusted manually by the user (PositionTimeConstant = 1/Kv).
- Vibration on the load side is not taken into account for the position controller setting.

Procedure

To perform an automatic setting of the position controller, proceed as follows:

- 1. Select the "Target system" > "Automatic controller setting" menu command.
- 2. Select the drive unit and the drive (axis).
- 3. Select the "Position controller (DSC)" from "Controller selection".
- 4. Click "Assume control priority" to assume control priority.
- 5. Press the "Drive On" button to enable the drive.

Perform the steps either in automatic mode or as individual steps.

- 6. Select the axis data sets to which the Kv factor is to be transferred.
- 7. Click "Transfer" to transfer the calculated Kv factor to the axis data sets.
- 8. Disable the drive by clicking the "Drive Off" button.
- 9. Give up the control priority of the PG/PC.
- 10.Save the online parameters.

You can now transfer the automatically set parameters to the project.

Backing up parameters

Proceed as follows to back up the parameters:

- 1. In the project navigator, select the SIMOTION unit with the axis for which you want to perform the automatic setting
- 2. Select "Target device" > "Copy current data to RAM" in the context menu.

- 3. Select "Target device" > "Copy RAM to ROM" in the context menu.
- 4. Select "Target device" > "Load CPU / drive unit to PG" in the context menu.

If necessary, the automatic controller settings can be verified with the measuring functions.

7.16.4 Measuring functions, trace, and function generator

Drive optimization

Drive optimization is part of commissioning and can be performed with SIMOTION SCOUT.

Controller optimization may only be performed by skilled personnel with control engineering knowledge.

Controller optimization

Various measuring functions are available for controller optimization of the drive. These measuring functions enable the control of the higher-level control loop to be selectively switched off and the dynamic response of individual drives to be analyzed through simple parameter assignment. The function generator and the trace recorder are used.

The control loop is supplied with the ramp-function generator signal at a specific point (e.g., speed setpoint), and the signal from the trace recorder is recorded at another point (e.g., speed actual value).



Figure 7-56 Optimizing a closed-loop controller

Depending on the form of controller optimization to be performed, it is possible to define the quality (e.g. signal form, amplitude, transient recovery time) of the disabled signal, the measuring duration for step functions in the time range, or the bandwidth and number of averaging operations in the frequency range for the trace. The analytical and graphical evaluation can then be performed accordingly (FFT diagram, Bode diagram).

The following measuring functions are available:

- Setpoint step-change at current controller
- Reference frequency response at current controller
- Setpoint jump at speed controller
- Disturbance step-change at speed controller
- Reference frequency response at speed controller
- Disturbance frequency response at speed controller
- Speed-controlled system (input at current setpoint filter)

Additional references

For additional information about drive optimization, consult the *SINAMICS S120* Commissioning Manual.

Additional information on trace and measuring functions, as well as on the function generator, can be found in the *SIMOTION SCOUT* Online Help.

7.16.5 Manual speed controller optimization

Requirement

You have already created a project and configured an axis and a drive. You can now optimize the speed controller.

Procedure

- 1. Open the project and go to online mode.
- 3. Select the drive unit and the drive.

 Select "Speed controller setpoint jump". You can change the values in the following fields: "Settling time", "Amplitude", "Offset", "Ramp-up time" and "Measuring time".

X_{I}	6	۵	18 18 E E	Nofileo Y	95
	Measuring f	unction i	inactive SINA	MICS_Integrated	
Measurin	ng function	Measur	ements Time diagram	FFT diagram Bode diagram	
	Measurii Drive:	ng functi	on: Speed controller Antrieb_1	setpoint jump (after speed setpoint fitter)	•
書 22 ?	Setting I Amplitud Offset: Ramp-up Measurii Max. me	time: le: p time: ng time: asuring l	50.000 20.00 50.000 100.000 ime: 682.500	ms 1/min 1/min ms ms ms ms	-
				□ Values in %	Reset
	Ho.	Active	Signal	Comment	Color
	1	~	Antrieb_1 r62	Antrieb_1 r62: Speed setpoint after the filter	
	2	~	Antrieb_1 r80	Antrieb_1.r80; Torque actual value	
	3	~	Antrieb_1 r61	Antrieb_1.r61: Speed actual value motor encoder	
	4		<u>m</u>	[•

Figure 7-57 Speed controller measuring function

Four channels can be traced. Certain channels are preassigned, depending of the measuring function.

5. Download the changes to the drive by clicking 👪 (Download parameter assignment).

Starting the measuring function

1. Click "Assume control priority" to assume control priority.

Read the notice that appears and click "Accept" to confirm.

2. Press the "Drive On" button to enable the drive.

3. Click **•** (Start measuring function) to start the measuring functions.

The axis is moved during the measurement. For this reason, a safety message that allows the process to be aborted is displayed.

After reading the notices, you can begin the measurement with "Accept" or abort it with "Abort".

4. The traced signals are represented on the "Timing Diagram" tab.



Figure 7-58 Timing diagram before parameter change

Adjusting the P-Gain

You can adjust the P-gain of the controller to optimize the transient response.

- In the project navigator under the corresponding drive, for example, Servo_1, use the menu command "Open-Loop/Closed-Loop Control" > "Speed Controller" to display the "Speed Controller with Encoder" dialog.
- 2. Enter an appropriate value in the "P-gain" field and the "Integral time" field.

	TION			
The valu	es entered take immediate	effect.		
Speed controller				•
Control type	[21] Speed control (with encoder)	•		-
Torque precontrol	No			
Reference model	Off	0.009 Nms/rad	125.00 με	
Static speed setpoir 0.00 rpm	Ad P gain 0.009 Nms/rad Reset time 10.00 ms t 0.000 rpm O Speed setpoint imited	aptation 10.0 ms 0.00 rpm PI controller	0.00 Nm 0.00 Nm 0.00 Nm 0.00 Nm 1 comp. 0.00 rpm	

6 SERVO_02 ∫

Figure 7-59 Entering P-gain

3:2 CDS: 0 (Activ 💌 DDS: 0 (Activ 💌 MDS: 0 (Active)

₩ 5

Close

Help

7.17 Downloading and storing user data

- 3. For verification purposes, perform the measurement again.
- 4. With the modified parameters, the controller displays a much better transient response. If necessary, you can continue changing the value until the transient response is optimal.



Figure 7-60 Measurement with modified P-gain

7.17 Downloading and storing user data

Overview

After commissioning the SIMOTION D4x5, we recommend that you back up the user data (programs, configuration data, and parameter assignments) to the CF card.

Loading user data

The menu command "Target system" > "Load" > "Download project to target system" is used to transfer the following data from the SIMOTION SCOUT engineering system to the "non-volatile data" area of the SIMOTION D4x5:

- Configuration data
- Programs
- Parameter assignments
- Technology packages

7.17 Downloading and storing user data

The hardware configuration of SIMOTION D4x5 and the retain variables are also saved to the "non-volatile data" area.

Note

Using the menu:

- "Target system" > "Load" > "Load project to target system" downloads all of the project data to the target system.
- "Target system" > "Load" > "Download CPU / drive unit to target device" only downloads the data of the selected device / drive element to the target device.

After the SIMOTION D4x5 is switched off, the contents of the "volatile data" area are lost.

Additional information on the SIMOTION SCOUT Engineering System can be found in the *SIMOTION SCOUT* Configuration Manual.

Storing user data

The "Copy RAM to ROM" function is used in SIMOTION SCOUT to save the following data from RAM to the CF card:

- Technology packages and user data (units, configuration data, parameter assignments, task configuration) from the "volatile data" area
- Current values are copied to the "volatile data" area, depending on the settings in SIMOTION SCOUT

Note

The "Copy RAM to ROM" function does **not** save the current values of the retain variables to the CFcard.

You have the following options for backing up the current values of retain variables to the CF card:

- In the user program Use the "_savePersistentMemoryData" system function for this purpose.
- Using a switch position (SIMOTION D4x5 Service selector switch) or IT DIAG. See Section Backing up diagnostics data and non-volatile data (Page 310).

With the SCOUT functions "Back up variables" and "Restore variables", you also have the option of backing up to your PC and restoring data that was changed during operation and only stored in the runtime system.

Execute the "Copy RAM to ROM" function separately for the SINAMICS Integrated. This requires that the drive element has been selected in the project navigator.

See also

Properties of the user memory (Page 89)

7.18.1 Overview of data deletion

The SIMOTION D4x5 memory described in the "user memory concept" can be deleted in various gradations. This enables you to determine whether data in your system should be deleted completely or partially.

You have the following options for deleting SIMOTION C4x5 data:

- Memory reset of SIMOTION D4x5 (Page 249)
- Deleting user data on CF card (Page 252)
- Setting SINAMICS Integrated to the factory settings (Page 253)
- Setting SIMOTION D4x5 to the default settings (Page 253)
- Deleting/restoring non-volatile data (Page 317)

7.18.2 Overall reset of SIMOTION D4x5

Introduction

During the overall reset, the memory of the SIMOTION D4x5 and the non-volatile data in the SRAM (with the exception of the communication configuration (baud rates, network addresses, etc.)), are deleted. The data on the CF card are retained during the memory reset.

You must perform a memory reset of SIMOTION D4x5:

- When you want to undo changes you have made to your user data (programs, configuration data, parameter assignments) that you have not backed up with the "Copy RAM to ROM" menu command.
- If the STOP LED is flashing (yellow and slowly) to indicate that the SIMOTION D4x5 is requesting a memory reset.
- If the non-volatile data and the project on the CF card do not match and an error occurs (diagnostic buffer entry).

You can perform the memory reset online via SIMOTION SCOUT or offline via the mode selector on the SIMOTION D4x5.

Data deleted on memory reset

The following data is deleted during a memory reset:

- User data (units, configuration data, parameter settings, task configuration)
- Technology packages

- Retain TO (absolute encoder adjustment)
- Retain variables

Retain variables are variables in the interface or implementation section of a UNIT that are declared with VAR_GLOBAL RETAIN or global device variables with the RETAIN attribute.

Note

Absolute encoder data is deleted during a memory reset operation and must therefore be readjusted after the memory reset.

Reset-proof data

The following data is retained during a memory reset:

- TCP/IP parameters and DP parameters
- Diagnostics buffer
- Data saved with the _savePersistentMemoryData, _saveUnitDataSet or _exportUnitDataSet system functions and with the "Copy RAM to ROM" function

If backup files (PMEMORY.XML/PMEMORY.BAK) have been backed up with _savePersistentMemoryData, the data in these files are backed up again to the non-volatile data after the memory reset. Thus, the user can perform a memory reset to force the backed up non-volatile data to be restored. This also includes the absolute encoder position.

Licenses

The technology packages and user data (configuration data, programs, parameter assignments) that were previously backed up to the CF card using the "Copy RAM to ROM" menu command will be transferred to the "non-volatile data" area of the SIMOTION D4x5 during the next power-up. Thus, an existing configuration on the CF card is loaded to the SIMOTION device following the memory reset.

Memory reset via SIMOTION SCOUT

You can only perform a memory reset via SIMOTION SCOUT if you are online with the SIMOTION D4x5.

- 1. Select the SIMOTION D4x5 in the project navigator of SIMOTION SCOUT.
- 2. Select "Target device" > "Operating mode" in the context menu to open the "D4x5: Operating Mode" dialog.
- 3. Select the STOP mode.
- 4. Then select MRES mode to perform the memory reset.

Memory reset with the mode selector

You can perform a memory reset with the mode selector if you are offline with the SIMOTION D4x5.

CAUTION

Always use an insulated screwdriver to activate the mode selector. Otherwise, static electricity can destroy the switch.

Proceed as follows to initiate a memory reset:

1. Place the mode selector in the STOP position (switch setting 2, see figure below).



Figure 7-61 Memory reset with the mode selector (STOP position)

 When the STOP LED is steadily yellow, turn the switch to the MRES position (switch position 3). The STOP LED starts to flash slowly (slow yellow flashing).

Wait until the STOP LED stops flashing.

3. Turn the switch back to the STOP setting.

4. You must turn the selector back to the MRES position again within 3 seconds. The memory reset will now be performed.

The SIMOTION D4x5 has completed the overall reset when the STOP LED lights up steady yellow.

Note

If you do not return the mode selector to the MRES position (switch setting 3) within 3 seconds (i.e. you allow more time to elapse), under certain circumstances the memory reset will not take place. You must then repeat the procedure.

5. Now move the mode selector back to the required operating mode.

NOTICE

Note that the MRES position (switch setting 3) during power-up causes the default settings to be restored. See Setting SIMOTION D4x5 to the default settings (Page 253).

Make sure you do not accidentally switch the power supply OFF/ON in the MRES selector setting, as this will reproduce the default settings instead of performing the desired memory reset.

7.18.3 Deleting user data from CF card

Overview

If you want to save a different (new) project to the CF card, it may be necessary to delete user data from an "old project" (e.g. unit data sets) which might be stored on the CF card

You can delete the user data with SIMOTION SCOUT. This requires you to go online on the SIMOTION D4x5. The following data is deleted during this operation:

- User data from the "volatile data" area
- Non-volatile data, with the exception of IP and DP parameters
- User data on the CF card (user directories), including the SINAMICS configuration

You can thus continue to go online to the SIMOTION D4x5 with your PG/PC. The licenses on the CF card are retained.

Deleting user data

- 1. In SIMOTION SCOUT, open the project you want to modify.
- 2. Go online with the SIMOTION D4x5.
- 3. Select the SIMOTION D4x5 in the project navigator and select the "Delete user data on card" option in the "Target system" menu.
- 4. Confirm the "Delete user data from card" prompt with "OK".

The user data is deleted and the SINAMICS Integrated goes offline.
See also

Upgrading technology packages (Page 279)

7.18.4 Restoring the default settings of SINAMICS Integrated

Prerequisite

You must be online to SINAMICS Integrated in order to restore its default settings.

Restoring the default settings

1. Right-click "SINAMICS_Integrated" in the Project Navigator.

2. Select the "Target device > Restore default settings" command from the shortcut menu. This restores the delivery state of SINAMICS Integrated.

7.18.5 Setting SIMOTION D4x5 to the default settings

Overview

SIMOTION D4x5 is supplied with preset parameters, such as the transmission rate or PROFIBUS addresses. You can restore the default settings with the mode selector. The following data are deleted during this operation:

- Non-volatile data in the SIMOTION device
- The backup copy of the non-volatile data on the CF card (PMEMORY.XML/PMEMORY.BAK)
- User data from the "volatile data" area and on the CF card
- The communication configuration (IP and DP parameters) on the CompactFlash Card is set to the factory settings.

The licenses on the CompactFlash Card are retained.

Restoring default settings with the mode selector

- 1. The power supply is switched off.
- 2. Set the mode selector on the SIMOTION D4x5 to MRES (selector setting 3).

7.19 Powering down the system

3. Switch on the power supply.

The backed-up SRAM and the user data are deleted. The default settings are loaded. SIMOTION D4x5 is in STOP mode.

4. Now use the mode selector to change to the desired operating mode.

Note

The communication parameters are now reset to the default settings (PROFIBUS address 2, baud rate of 1.5 Mbit/s). The communication configuration for SIMOTION D4x5 must be repeated.

7.19 Powering down the system

If you wish to shut the system down, you must ensure that all axes and system parts are set to a safe state. You can set this up by providing a separate motion task, for example.

Once the system is at a standstill, you can switch off the power supply.

Note

You must observe the safety notes for SINAMICS components, which you will find in the corresponding SINAMICS manuals.

7.20 Configuring Safety Integrated functions

Integrated safety functions

When used in conjunction with SIMOTION D, the integrated safety functions of SINAMICS S120 provide highly effective practical protection for personnel and machinery.

The following Safety Integrated functions on the basis of the SINAMICS FW V2.6.2 are currently available:

(Terms in accordance with IEC 61800-5-2)

- Safe Torque Off (STO)
- Safe Brake Control (SBC)
- Safe Stop1 (SS1)
- Safe Stop2 (SS2)
- Safe Operating Stop (SOS)
- Safely-Limited Speed (SLS)
- Safe Speed Monitor (SSM)

Control circuit

The Safety Integrated functions are completely integrated into the drive system. They can be activated as follows:

- Via terminals on the control unit and on the power unit (STO, SBC, SS1 only)
- Via terminals on the TM54F terminal module (as of SIMOTION V4.1 SP1)
- Via PROFIBUS with PROFIsafe (as of SIMOTION V4.1 SP1 HF6)
- Via PROFINET with PROFIsafe (as of SIMOTION V4.2)

The Safety Integrated functions are implemented electronically and therefore offer short response times in comparison to solutions with externally implemented monitoring functions.

Note

Although SIMOTION does not contain any safety-related functionality, it provides support for SINAMICS drives that can perform safety-related functions.

The purpose of this support that SIMOTION offers for the safety-related monitoring functions is to prevent fault reactions at the drive end by ensuring that the drive does not exit the monitored operating state.

Hardware required

Where safety functions are controlled via the TM54F or via PROFIBUS/PROFINET with PROFIsafe, at the very least the following hardware versions must be used:

- SIMOTION D425: 6AU1425-0AA00-0AA0, product version D
- SIMOTION D435: 6AU1435-0AA00-0AA1, product version D
- SIMOTION D445: 6AU1445-0AA00-0AA0, product version B
- SIMOTION D445-1: 6AU1445-0AA00-0AA1, product version A
- SIMOTION CX32: 6SL3040-0NA00-0AA0, product version A

The hardware requirements of the drive components can be found in the SINAMICS S120 Safety Integrated Function Manual.

Quantity structures

The maximum number of servo drives with Safety Integrated functions for each control unit is:

Table 7- 12	SIMOTION D4x5 c	nuantity	structures
		Juantity	311 401 41 63

Control unit	Maximum number of servo drives when safety function is activated				
	Via CU/EP terminals (STO, SBC, SS1 only)	Via TM54F terminals	Via PROFIBUS with PROFIsafe ¹⁾	Via PROFINET with PROFIsafe (as V4.2) ²⁾	
SIMOTION D4x5	6	5	5	5	
SIMOTION D4x5 (with CX32)	5	4	4	4	
CX32	6	5	4 (V4.1 SP1 HF6) 5 (as of V4.1 SP2)	5	
CU320	6	5	5 (as of V4.1 SP2)	4	
CU320-2	6 (as of V4.1 SP5)	6 (as of V4.1 SP5)	6 (as of V4.1 SP5)	6 (as of V4.2)	

¹⁾ If SIMOTION D is operated as an intelligent DP slave on an F-CPU, a maximum of 32 safety slots can be configured for each intelligent DP slave in **HW Config**. If the Safety Integrated functions are controlled via PROFIBUS with PROFIsafe, one slot in the input area and one slot in the output area are used for each safety axis. This results in a maximum of 16 drives with the Safety Integrated function for each PROFIBUS interface (intelligent DP slave) of the D4x5. If with SIMOTION D both PROFIBUS interfaces are operated as intelligent DP slave on a F-CPU, the quantity structure increases to 2 x 16 drives (sum of the drives on the SINAMICS Integrated, CX32 and SINAMICS control units). In this case however, no PROFIBUS master interface is available for the connection of I/Os, for example.

²⁾ The maximum permissible quantity structure for the D4x5 is 64 drives with Safety Integrated function (sum of the drives on the SINAMICS Integrated, CX32 and SINAMICS control units).

Safety Integrated functions with TM54F

Safety Integrated functions are activated via fail-safe digital inputs on the TM54F. This means that every drive control (SINAMICS Integrated of SIMOTION D4x5, CX32, CU320, CU320-2, etc.) requires its own TM54F (assuming relevant safety functions are to be used on the control unit concerned). Only one TM54F can be connected for each SIMOTION D4x5, CX32 or SINAMICS S120 control unit.

Safety Integrated functions with PROFIsafe (PROFIBUS example)

Safety Integrated functions are activated via "PROFIsafe on PROFIBUS" safe communication. Control (F logic) is based on a SIMATIC F-CPU connected via PROFIBUS with PROFIsafe, e.g. a SIMATIC S7-300 F-CPU (see figure) or an ET 200S IM151-7 F-CPU with PROFIBUS DP master interface module (not shown in the figure).



Figure 7-62 SIMOTION D, control of F functions via PROFIBUS with PROFIsafe

A function example can be found at

(http://support.automation.siemens.com/WW/view/en/36489289)

Topologies

The topologies that may be used with the SIMOTION D4x5 and CX32 are listed below. In each case, the description specifies whether the control of Safety Integrated functions is routed through the drives.

- SIMATIC F-CPU (master), connected via PROFIBUS with PROFIsafe to SIMOTION D4x5 (intelligent DP slave)
 - Routing to SINAMICS Integrated drives for the D4x5 and CX32, as of V4.1 SP1 HF6
 - Routing to the drives of a SINAMICS S120 CU as of V4.1 SP2 connected to the D4x5
 CU is connected as slave via PROFIBUS to the DP master interface of the D4x5
 Routing to a CU connected via PROFINET is not possible.
- SIMATIC F-CPU (controller), connected via PROFINET with PROFIsafe to SIMOTION D4x5 (intelligent device)
 - Routing to SINAMICS Integrated drives for the D4x5 and CX32, as of V4.2
 - Routing to the drives of a SINAMICS S120 CU as of V4.2 connected to the D4x5
 CU is connected as intelligent device via PROFINET to the PROFINET interface of the
 - D4x5 (=controller)
 - CU is connected as slave via PROFIBUS to the DP master interface of the D4x5.
- The SIMOTION D4x5 is the PROFIBUS master for a fail-safe data exchange broadcast, e.g. between a SIMATIC F-CPU (e.g. ET 200S F-CPU) and a SINAMICS S120 CU as of V4.1 SP1

Note

Control for the Safety Integrated functions cannot be routed to the SINAMICS Integrated of the D4x5 or a CX32 in this constellation.

Additional references

Additional information on configuring Safety Integrated functions can be found in the

- SINAMICS S120 Safety Integrated Function Manual
- TO Axis Electrical/Hydraulic, External Encoder Function Manual
- Available on the Internet at (http://support.automation.siemens.com/WW/view/en/27585482).

Commissioning (software) 7.21 Migration D445 to D445-1

7.21 Migration D445 to D445-1

7.21.1 Overview

Characteristics

Due to the following functional improvements, we recommend using SIMOTION D445-1 in place of SIMOTION D445 for new applications:

- An increase of 30% in PLC and motion control performance, dependent upon the application
- Less mounting depth (mounting is possible even without spacers)
- New fan/battery module with increased availability thanks to double fan



Figure 7-63 SIMOTION D445-1 control unit

Requirements

Components		Comment
Designation	Version	
SIMOTION SCOUT	as of V4.1 SP2	Full support for SIMOTION D445-1 configuration

Commissioning (software)

7.21 Migration D445 to D445-1

	V4.1 SP1	Support of SIMOTION D445-1 configuration, with the constraint that the D445-1 control unit must be configured as "D445".
SIMOTION D firmware (kernel)	as of V4.1 SP2 HF3	For information on firmware updates, see Section Performing a firmware and project update (Page 284).
SIMOTION D445-1 hardware	as of HW version A	Order number 6AU1 445-0AA00-0AA1
CompactFlash cards (CF cards) supported by SIMOTION D445-		1 GB CF card (6AU1 400-2PA01-0AA0) 1 GB CF card (6AU1 400-2PA00-0AA0) 512 MB CF card (6AU1 400-2NA00-0AA0)
1		The 32 MB and 64 MB CF cards used previously are no longer supported. We recommend using 1 GB CF cards.
SIMOTION project version	≥ V4.1 SP1	Projects from any V4.1 SPx version can run on SIMOTION D445-1 provided that the CF card has firmware \geq V4.1 SP2 HF3.

7.21.2 Configuration

SCOUT as of V4.1 SP2

SIMOTION D445-1 can be configured with SIMOTION SCOUT as of V4.1 SP2. The D445-1 features "D445" in the "Create new device" dialog as a variant of the CPU type. In the HW Config module catalog, the D445-1 can be found in the SIMOTION D445 folder under order number 6AU1 445-0AA00-0AA1.

SCOUT V4.1 SP1

SIMOTION D445-1 can also be configured with SIMOTION SCOUT V4.1 SP1. To do this, configure a SIMOTION D445- in place of the SIMOTION D445-1 Control Unit.

With SIMOTION SCOUT V4.1 SP1 you can:

- Go online with a SIMOTION D445-1
- Download the configuration to the SIMOTION D445-1

A D445-1 Control Unit which has been defined with SCOUT V4.1 SP2 as a D445-1 cannot be configured with SCOUT V4.1 SP1.

7.21.3 Compatibility

As of V4.1 SP2, SIMOTION D445-1 (6AU1 445-0AA00-0AA1) is upwardly compatible for use with SIMOTION D445 (6AU1 445-0AA00-0AA0).

Project $\leftarrow \rightarrow$ Firmware $\leftarrow \rightarrow$ Module

The following compatibility factors must be taken into account for V4.1 SPx:

- Device replacement in HW Config A D445 (6AU1 445-0AA00-0AA0) can be replaced by a D445-1 (6AU1 445-0AA00-0AA1) of the same version (and vice versa) in HW Config. Configurations are retained in the case of replacements, as is a CBE30, including configuration.
- Common firmware As of V4.1 SP2 HF3, D4xx firmware can run on all SIMOTION D platforms (D410, D425, D435, D445, and D445-1).
- D445 and D445-1 are project-compatible with firmware as of V4.1 SP2 HF3. This allows a V4.1 SPx CF card from a D445 to be used in a D445-1 without SCOUT. Using windows tools and a card reader, copy the "/USER" directory from any V4.1 SPx version to a CF card with a firmware version ≥ V4.1 SP2 HF3; this will enable the project to run on both a D445 and a D445-1.
- A D445-1 project can run on a D445 (and vice versa).
- It is possible to go online on a D445-1 using a SCOUT project for D445 (and vice versa). In this case, it is possible to download from SCOUT and HW Config.
- D445 and D445-1 projects on a CF card with a firmware version as of V4.1 SP2 HF3 can be used in both D445 and D445-1 control units.

Note

A CF card can likewise run on D445 and D445-1 subject the following conditions:

- When changing from D445-1 to D445, the lower PLC and motion control performance is sufficient for the application. If this is not the case, adjustments (e.g. cycle clock settings) need to be made.
- When changing from D445 to D445-1, the application is able to cope with the increased PLC and motion control performance; i.e. the application is designed in such a way that shorter running times do not alter the program sequence.

Spacers

SIMOTION D445-1 comes with pre-assembled spacers. In contrast to the D445, these spacers can be removed from the D445-1 in the same way as from the SIMOTION D425 and D435. (In the case of the D445, spacers are always required due to the cooling fins on the module backplane.)

Mounting on the side of the line module

Mounting on the SINAMICS S120 line module using five lateral fixing elements is not possible with SIMOTION D445-1. SIMOTION D445-1 must always be screwed to the control cabinet wall.

Interfaces

The interfaces (connectors) of a D445-1 are compatible with a D445.

Fan/battery module

7.21 Migration D445 to D445-1

The standard scope of delivery of SIMOTION D445-1 includes a double fan/battery module (SIMOTION D445: fan/battery module with single fan).

8

Service and maintenance

8.1 Overview

Introduction

It is possible to distinguish between the following scenarios when replacing and updating components:

- Replacing modules (spare part scenario)
 - General information about the spare parts procedure for SIMOTION D4x5 (Page 267)
 - Removal and replacement of the SIMOTION D4x5 (Page 268)
 - Replacing DRIVE-CLiQ components (Page 269)
 - For information on replacing SIMOTION D4x5 fans, see Section "Replacing the battery in the fan/battery module" in the *SIMOTION D4x5* Manual
 - Replacing the CompactFlash card (Page 272)
- Adapting a project (new device type / device version) The project needs to be adapted if you want to change the type (e.g. D425 ⇒ D435) or version of the SIMOTION device in your existing project.
 - Creating backup copies (Page 273)
 - Backing up user data (backup variables) (Page 273)
 - Upgrading a user project to the new SCOUT version (Page 275)
 - Platform replacement via XML export/import (Page 276)
 - Preparing the device replacement (Page 277)
 - Device replacement in HW Config (Page 279)
 - Upgrading technology packages (Page 279)
 - Upgrading the device version of SINAMICS S120 control units (Page 282)
 - Upgrading a library (Page 283)
 - Save project, compile and check consistency (Page 284)
- Performing a firmware and project update
 - Upgrading the CF card's boot loader (Page 284)
 - Update preparatory measures (Page 285)
 - Update via IT DIAG (Page 286)
 - Upgrade via device update tool (upgrading SIMOTION devices) (Page 286)

8.1 Overview

- Upgrade via CF card (Page 291) with the steps:
 - Backing up the CF card data (Page 291)
 - Firmware update via CF card (Page 292)
 - Upgrading the SINAMICS (Page 293)
 - Downloading the project to the target system (Page 294)

The upgrade data is generated with the SCOUT function "Start device update tool" and then transferred to the SIMOTION D4x5 via CF card or IT DIAG file. Upgrading modules using upgrade data offers the option of downgrading if the upgrade does not produce the desired result.

Note

Upgrading using the device update tool offers a number of advantages (keeping retain data, option of downgrading, no license key handling, etc.). We would, therefore, recommend using this method for firmware and project upgrades.

Please also observe the information on handling the CompactFlash card.

- Changing the CompactFlash card (Page 295)
- Writing to a CompactFlash card (Page 296)
- Formatting the CompactFlash card (Page 297)
- Boot loader on the CompactFlash card (Page 297)
- Recommended method of handling CF cards (Page 298)
- Card reader for CF cards (Page 298)

Note

This document uses the following terms:

- Upgrade: Denotes upgrading to a higher version of a component/software
- Downgrade: Denotes reverting to a previous version of a component/software
- Update: In general terms, denotes the act of bringing a component/software up to date (or, more specifically, an upgrade or downgrade)

Overview

The exact procedure when replacing or upgrading components depends on various factors.

If a project is upgraded, the procedure depends on the scope of change of the versions.

- Change of the SIMOTION main version
- Change of the SIMOTION service pack or hotfix version
- Change of the PROFINET version
- Change of the SINAMICS version (There are SIMOTION versions that contains several SINAMICS versions for a device)

If another SIMOTION controller is to be used, then the procedure depends on whether a device or a platform replacement is required.

Examples of upgrade scenarios are listed in the following overview table. They are shown in the columns. The lines list the principle measures that have to be performed. Whether the measure has to be performed in a specific case, must be decided project-specifically.

Grayed-out cells mean that a measure is not required.

Note

If the version is changed and the SIMOTION controller replaced at the same time, then all measures apply; the measures must be performed in the TOP-DOWN sequence according to the table.

Service and maintenance

8.1 Overview

Overview of upgrade options

Action/measure	Upgrading a project			Replacement of the SIMOTION controller		Activity	
	Main version	Service pack or hotfix version	PROFINET Version	SINAMICS version	Device replacement via HW Config	Platform replacement via XML export/import	affects
Examples	V4.1 → V4.2	V4.1 SP2 → V4.1 SP4	PN2.1 → PN2.2	V2.5 → V2.6.2	D445-2 → D455-2 D4x5 → D4x5-2 D410 DP → D410 PN	$\begin{array}{ccc} C240 & \longrightarrow D445-2 \\ D410 & \longrightarrow D445-2 \\ D445 & D445 \\ (S120) & \longrightarrow (SM150) \end{array}$	
Creating backup copies (project/CF)							
Backing up user data (backup variables)	only if required				only if required	only if required	
Upgrading a user project to the new SCOUT version							oject
Platform replacement via XML export/import	When replaci determined (ng the platform, the version of the de	he target vers evice into whi	ion is also ich it is imported)			JT/pr
Preparing the device replacement							10
Device replacement in HW Config							N SC
Upgrading technology packages (TP)	4)	4)			4)		DTION
Upgrading device version of SINAMICS S120 CUs				for external CUs if required			SIMO
Upgrading a library	Libraries are version- dependent				Libraries may be device-dependent	Libraries may be device-dependent	
Save/compile project; check consistency						1	
Updating firmware and/or project	t						
Upgrading the boot loader on the CompactFlash Card	Check if the requires a ne	new version ²⁾ w bootloader			Check if the new device ²⁾ requires a new bootloader		
Update - preparatory measures							are
Update via IT DIAG Update via device update tool	Selection	of the 3 update me	thods		only possible if the CompactFlash Card features a valid firmware version	only possible if the CompactFlash Card features a valid firmware version	jet hardw
Upgrade via CompactFlash Card							arç
Backup of the CompactFlash Card data							card/t
Firmware update using a CompactFlash Card							iory c
Upgrading SINAMICS ⁵⁾							Mem
Downloading the project ¹⁾ to the target system							

not relevant

1) Alternative: Loading the project to the CF card using a card reader

2) See SW compatibility list (http://support.automation.siemens.com/WW/view/en/18857317)

3) The version of the SINAMICS Integrated and the Controller Extensions are automatically upgraded in HW Config during a device replacement

4) The technology packages are upgraded automatically. The user can directly specify a TP

5) SINAMICS components are upgraded/downgraded to the component version of the CompactFlash Card. Ensure that LED codes are observed. Following an upgrade, a POWER ON/OFF is required

Figure 8-1 Upgrade options

8.2 Replacing modules (spare part scenario)

8.2.1 Parts replacement for SIMOTION D4x5

Replacement rules for SIMOTION D435

In the case of replacement parts, you cannot replace the modules as you wish. You must comply with the following rules for a SIMOTION D435:

- A SIMOTION D435 with the order number 6AU1 435-0AA00-0AA0 can be replaced by a SIMOTION D435 with the order number 6AU1 435-0AA00-0AA1.
- A SIMOTION D435 with the order number 6AU1 435-0AA00-0AA1 cannot be replaced by a SIMOTION D435 with the order number 6AU1 435-0AA00-0AA0.

SIMOTION D4x5 replacement with firmware downgrade

When replacing a SIMOTION D4x5 V3.2.x with a SIMOTION D4x5 on which a version \geq V4.0 has previously been run, the following behavior may be observed:

- The module signals "Reset requested" (after power-up, the STOP LED flashes yellow at 0.5 Hz) and
- It is not possible to go online.

This scenario occurs if the module still contains retain data from a project \geq V4.0 that is not compatible with a V3.2.x project (buffering of retain data by SuperCap or the battery used).

The following is a description of how you can delete the retain data.

Use of used modules

If a used D4x5 is used for the module replacement, we recommend that the retain data be deleted on the used D4x5.

Two options are available for this.

Option	Reference to description	Notes
Module memory reset	See Section SIMOTION D4x5 memory reset (Page 249)	Controller via mode selector (position "3" MRES). Is available on all SIMOTION platforms.
Deleting/restoring non- volatile data	See Section Deleting/restoring non- volatile data (Page 317)	Controller via Service switch (position "1"). Is only available on SIMOTION D.

NOTICE

With a Power OFF/ON, "Restore factory settings" is performed instead of "Memory reset" in switch position "3" (MRES) of the mode selector.

Restore factory settings deletes all the project data on the CF card.

To avoid and unintentional/accidental deletion of the project data on the CF card, we recommend that the retain data be deleted via the Service selector switch.

See also

Setting SIMOTION D4x5 to the default settings (Page 253)

8.2.2 Removal and replacement of the SIMOTION D4x5

Removing the control unit

The control unit can be replaced only when the load power supply has been switched off. Therefore, switch off the power supply now.

How to remove the SIMOTION D4x5:

- 1. Switch off the power supply.
- 2. Remove the front cover and remove the CompactFlash card from the plug-in slot.
- 3. Disconnect the terminal block for the power supply.
- Disconnect the DRIVE-CLiQ connectors to the SINAMICS S120 modules, the connectors for the PROFIBUS DP interfaces (X126 and X136), and, if necessary, the Ethernet connectors to the X120 and X130 interfaces.
- 5. Disconnect the connectors to the digital inputs and outputs at interfaces X122 and X132.
- 6. Disconnect any option module which may be inserted (CBE30, TB30).
- 7. Depending on the mounting method, lift the control unit from the connection to the SINAMICS S120 drive assembly or remove the mounting screws of the control unit.

Installing a new module

Proceed as follows to install a new SIMOTION D4x5:

- 1. Remove the front cover from the new control unit.
- 2. Mount the new control unit.
- 3. Reconnect all connectors that were removed previously.

- 4. Connect the terminal block for the power supply.
- 5. Reattach the designated shielding for all cables.
- 6. Reinsert the original CompactFlash card into the plug-in slot.
- 7. Reattach the front cover and close it.
- 8. Switch on the power supply. The control unit is immediately ready to operate.

Replacing SIMOTION D4x5 modules without PC/PG

To enable a module replacement without a PG/PC, you must back up the current nonvolatile data to the CF card during operation.

The "_savePersistentMemoryData" system function allows the user program to save the content of the non-volatile data to the CF card. This ensures that the retain variables and the absolute encoder position are backed up to the CF card in the event that a spare part is fitted.

As an additional option, you can back up the non-volatile data by setting the service selector switch or using IT DIAG; for details, see the section titled Backing up diagnostic data and non-volatile data (Page 310).

Note

Non-volatile data that is not backed up to the CF card will be lost if a spare part is installed (in the event of a module defect). (For example, failing to back up the current values of the retain variables will result in them being lost and reset to their initial values.)

If an absolute encoder overflow occurs after "_savePersistentMemoryData", the actual position value will no longer be correct once the non-volatile data has been restored. In this case, homing (absolute encoder adjustment) must be repeated.

See also

Parts replacement for SIMOTION D4x5 (Page 267)

8.2.3 Replacing DRIVE-CLiQ components

Module replacement

DRIVE-CLiQ components can be replaced or reinserted during operation (without POWER OFF) or when the system is switched off.

Requirement

- The affected components are located at the end of the line.
- If an infeed is affected, the power units supplied by it do not function.

Procedure for "Removing a component"

- 1. Deactivate the affected component or the drive object.
- 2. Remove the DRIVE-CLiQ connector.
- 3. Remove the supply voltage of the component and uninstall the component.

Procedure for "Installing a component"

- 1. Install the component and reconnect the supply voltage.
- 2. Reconnect the DRIVE-CLiQ cable at the same location (port). The cable must have the same length as the old one.
- 3. Activate the affected component or drive object.



In order to replace this component, the power in the module must be switched off.

Parameters for topology comparator and component replacement

In the expert list, you can use CU parameter p9906 to specify how the electronic rating plates are compared for all the components of a control unit. The type of comparison can be changed subsequently for each individual component by using p9907/p9908 or right-clicking in the topology. All data on the electronic type plate is compared by default.

- If p9909 = 1, the serial number and the hardware version of the new replaced component will be transferred automatically from the actual topology to the target topology and then saved to non-volatile memory.
- For p9909 = 0, serial numbers and hardware versions are not automatically transferred.

Setting p9901 = 1 facilitates **spare parts / component replacement without tool support (as of SINAMICS V2.2)**. The new serial number of the spare part is automatically transferred from the actual topology to the setpoint topology and saved in non-volatile memory. Prerequisite is that the replaced components are of the same type and have the same order number, e.g. "6SL3055-0AA00-5BA2". The last or last two digits of the order number (depending on the component type) are not checked, as the HW version, for example, is encoded in these positions. This mechanism is also applied when several components are replaced.

Modified wiring following module replacement

In the default setting for the topology comparator, modified wiring configurations of DRIVE-CLiQ components (e.g. cross-exchange) cannot be accepted for safety reasons and a fault is generated.

If a cross-exchange of components is required (i.e. existing components are replaced with other existing components, and no spare parts are used), e.g. for troubleshooting purposes, the topology comparator must be reduced via parameter p9906, or preferably via p9907/p9908; alternatively, by right-clicking in the topology.

NOTICE

In this case, incorrect insertion of components is no longer monitored.

Automatic upgrading/downgrading (FW upgrade)

As of SINAMICS firmware version 2.5, the DRIVE-CLiQ components are automatically upgraded or downgraded to the version of the component firmware on the CF card. Components that cannot be downgraded to the component firmware version on the CF card (for example, old firmware on the CF card and new components on which the old firmware cannot be loaded) retain their firmware version. The resulting firmware version combinations are always functional.

Note

During an automatic FW upgrade, please read the messages and alarms in the SIMOTION SCOUT detail window.

The component version can be obtained from the CONTENT.TXT file in the main directory of the CF card.

Note

The update can take several minutes and its progress is tracked by corresponding messages appearing in the alarm window of SIMOTION SCOUT.

A firmware update on DRIVE-CLiQ components is indicated by the RDY LED flashing red and green:

- FW update running: RDY LED flashes slowly (0.5 Hz)
- FW update complete: RDY LED flashes quickly (2 Hz)

These flashing patterns are also displayed on the yellow RDY LED on the SIMOTION D/CX32, and indicate that a FW update has been carried out on components connected to the SIMOTION D/CX32 or that all components have completed the FW update.

Go offline once all the FW updates have been completed. POWER ON the upgraded/downgraded components.

The upgrade/downgrade function can be deactivated using the p7826 CU parameter in the expert list.

Additional references

You can find further information on this topic:

- In the SINAMICS S120 Commissioning Manual
- SINAMICS S120 Function Manual

8.2.4 Replacing the CompactFlash Card

If spare parts are being used, you must contact the Technical Support Center to convert the license key of the defective CF card to the new CF card. Proceed as described below to write your project to the new CF card:

- Changing the CompactFlash card (Page 295)
- Writing to a CompactFlash card (Page 296)

Detailed information about licensing can be found:

- In the SIMOTION SCOUT Configuration Manual
- As well as in the FAQ (http://support.automation.siemens.com/WW/view/en/36947932).

8.3 Adapting a project (Updating the project / Replacing the SIMOTION controller)

8.3.1 Overview

Overview

You will need to adapt the project if you want to replace the type (e.g. D425 -> D435) or version of the SIMOTION device in your existing project.

Procedure

The exact procedure for project adaptations depends on the scope of the target hardware and version changes.

An overview of the various applications can be found in Section **Service and maintenance** at Overview (Page 263).

8.3.2 Creating backup copies (project/CF)

Requirement

Before adapting the project, it is essential that you create the following backup copies:

- A backup copy of the project and
- A backup copy of the contents of the CF card, see Backing up the CF card data (Page 291)

8.3.3 Backing up user data (backup variables)

Overview

With the SCOUT functions "Back up variables" and "Restore variables", you have the option of backing up and restoring data that was changed during operation and only stored in the runtime system. This is necessary if a SIMOTION platform is changed or a version upgraded, for example.

The "Back up variables" function creates XML files which are stored in a folder of your choice.

The following types of data can be backed up:

- Retentive global device variables and unit variables, as well as TO retain data (as of V4.1), located in the SRAM or NVRAM depending on the controller
- Data saved with _saveUnitDataSet or _exportUnitDataSet and located on the CF card

Note

When performing an upgrade with a firmware version \geq V4.1, this function is only required for backing up and restoring unit data sets that have been created using _saveUnitDataSet.

Retain and unit data (saved with _exportUnitDataSet) remains valid even after a version upgrade.

Retain data can also be easily backed up to a memory card without the use of SIMOTION SCOUT. For this purpose, use:

- The _savePersistentMemoryData function or
- The service selector switch on the SIMOTION D4x5 or IT DIAG
- See also Diagnostic data and non-volatile data (Page 310).

Procedure

The backup of the user data must be performed **before** the upgrade of the SCOUT project. This is possible for a version upgrade with the "old" SCOUT version or the "new" SCOUT version.

The following is a description of the procedure with a "new" SCOUT.

1. Open the project.

When opening the project a window appears with a message that the project to be opened was created with another SCOUT version, as well as a prompt as to whether the upgrade should be performed.

Convert pr	oject [ws7s:61527]	×
1	The project exists in an older version (V4.1). To display the project data, the project must be converted to the current version V4.2.	
	OK Cancel Help	

Figure 8-2 Prompt as to whether the project should be upgraded

- 2. Confirm the prompt with "OK". The project is upgraded.
- 3. After the conversion another prompt appears as to whether the project should be opened write-protected. Confirm this prompt with "Yes" (open write-protected).

Open proje	ect [ws7s:61549]	
1	Should the project data be opened write-protected? If programs are changed in a converted project and then downloaded, this can result in the loss of retain and unit variables!	
	Yes No Help	

Figure 8-3 Prompt as to whether the project should be opened write-protected

Open write-protected means: The project remains consistent. The data is the same in the controller and in the project. Diagnostic functions (status, trace, etc.) can be executed directly. The project does not have to be loaded to the controller first.

Go online on the SIMOTION device (in STOP mode) and execute the **Save variables** SCOUT function. The retain variables (interface and implementation) and also the user files (saved with _saveUnitDataSet or _exportUnitDataSet) are saved to the PG/PC.

The project must then be closed.

If you are using a different PC or PG than that configured for the controller, an online connection is not possible.

Update the PG/PC assignment for this.

You can go directly to the PG/PC assignment via the 👜 button.

The SCOUT project can then be opened again write-protected --- online connection is now possible.

Additional references

For further information, see the SIMOTION SCOUT Configuration Manual.

8.3.4 Upgrading a user project to the new SCOUT version

Requirement

It is essential that a backup copy be made of the original project before the upgrade, because the data storage of the project is also upgraded during the upgrade. This ensures that you can always return to the original project if the upgrade fails (power interruptions, unexpected faults, maloperation, etc.).

Procedure

 When opening the project a window appears with a message that the project to be opened was created with another SCOUT version, as well as a prompt as to whether the upgrade should be performed. Confirm the prompt with "OK".

Convert pr	oject [ws75:61527]	×
1	The project exists in an older version (V4.1). To display the project data, the project must be converted to the current version V4.2.	
	OK Cancel Help	

Figure 8-4 Prompt as to whether the project should be upgraded

 After the conversion another prompt appears as to whether the project should be opened write-protected. Confirm this prompt with "No" for a version upgrade (do not open writeprotected).

Open proje	ect [ws7s:61549]	×		
♪	Should the project data be opened write-protected?			
	If programs are changed in a converted project and then downloaded, this can result in the loss of retain and unit variables!			
	Yes No Help			

Do not open write-protected means:

The project can be edited. The data in the controller and in the project is not consistent after going online. Diagnostic functions cannot be executed directly. The project must be loaded to the controller first.

Figure 8-5 Prompt as to whether the project should be opened write-protected

Open write-protected:

The project remains consistent. The data is the same in the controller and in the project. Diagnostic functions (status, trace, etc.) can be executed directly. The project does not have to be loaded to the controller first.

Note

A project that was last edited with a higher SCOUT version cannot be opened by a SCOUT with a lower version. However, the project with the more current SCOUT version can first be converted to the required software version (command: "Project" > "Save in old project format"). The project can then be opened with the lower SCOUT version. However, debug information (e.g. for program status) is no longer available.

8.3.5 Platform replacement via XML export/import

Overview

A platform replacement is always required when an existing project is to be used for another SIMOTION platform. The platform replacement is always performed via an XML export/import.

The following devices can be interchanged via a platform replacement:

- Replacement between SIMOTION C, P and D (e.g. C240 ⇒ D445-2 DP/PN)
- Replacement between D410 and D4x5/D4x5-2 (e.g. D410 ⇒ D445-2 DP/PN)
- Replacement between SIMOTION D (SINAMICS S120 Integrated) ⇒ SIMOTION D (SINAMICS SM150 Integrated)

Platform replacement during project downgrades:

It is not possible to downgrade to a lower SINAMICS version. However, it is possible to transfer project data by means of an XML export/import.

Preparations

Before the platform replacement can be performed, preliminary work may be necessary in the existing project.

If a D4x5 is to be imported into a D410, then only the permitted quantity structure of the D410 may be configured in the D4x5. This applies for all components, e.g. not only an infeed, but also the permissible power units.

A D4x5 with CU adapter and PM340 can be imported into a D410 when the CU adapter is connected to port 0. Otherwise, the topology will be destroyed.

Generally, the success of an import always also depends on the specific configurations of the drive units, and whether the configuration is possible for the device to which the import is to be performed. Also note any error messages that may occur.

Procedure

Proceed as follows:

1. In the project navigator of SIMOTION SCOUT, right-click the SIMOTION controller that is to be replaced.

Select "Expert" > "Save project and export object" in the context menu. "Save project and export object" exports selected data of the selected object in XML format. This data export can then be reimported into other projects. The entire project is not exported, only the data of the selected object (e.g. only the D4x5 or only the SINAMICS Integrated)

- 2. Specify the desired path and start the XML export.
- 3. When the export has been performed error-free, delete the device from the project and confirm the prompt.
- Insert the desired platform as new device in the project navigator of SIMOTION SCOUT. With the selection of the device, you also define the SIMOTION version, and with a SIMOTION D, also the SINAMICS version.
- 5. Import the data of the original platform into the new device. To do this, right-click the new device and select "Expert" > "Import object" in the context menu.
- 6. Select the location where the XML export data is to be stored and start the import. Confirm the prompt to continue with the import.

Confirm the message with regard to the import of a "non-compatible type" with "OK".

8.3.6 Preparing the device replacement

Overview

The device replacement process differs from the platform replacement process in that it is really easy to accept project data during device replacement. The device replacement is performed via **HW Config**, whereas an **XML export/import** is required for a platform replacement.

A device replacement is only possible within SIMOTION D.

The following devices can be interchanged:

- Replacement between different performance classes (e.g. D425 ⇔ D435)
- Replacement between generations (D4x5 \Rightarrow D4x5-2)
- Replacement between variants (D410 DP ⇔ D410 PN)
- Replacement between SIMOTION, SINAMICS and/or PROFINET version (e.g. D425 V4.1 PN V2.1 SINAMICS S120 V2.5 ⇒ D425 V4.2 PN V2.2 SINAMICS S120 V2.6.2).

One SIMOTION D can only be replaced with another SIMOTION D if the SINAMICS version involved is the same or higher. It is not possible to downgrade to a lower SINAMICS version.

Preparation

Before the device replacement can be performed, it is recommended that preliminary work be performed in the existing project. The existing project must be adapted so that it can be mapped to the new device during the device replacement.

Examples:

1. Number of DRIVE-CLiQ interfaces

If the replacement is to a device with fewer DRIVE-CLiQ interfaces, then the ports that are no longer available must be rewired before the device replacement (double-click "Topology" in the project navigator). Components on DRIVE-CLiQ ports that are no longer available are moved to the component archive during the device replacement. Example:

Replacement of D445-1 (six DRIVE-CLiQ ports) with D435 (four DRIVE-CLiQ ports) \rightarrow ports X104 and X105 are no longer available.

Procedure for CX32

If a CX32 is to be moved to another port, this is only possible via HW Config. Note the dependency between "DRIVE-CLiQ port" and "Address on the PROFIBUS Integrated" in Section Preparing for configuration (Page 176).

2. Number of CX32s

If the replacement is with a D4x5 that only supports a small number of CX32 modules, then a device replacement in **HW Config** is not possible.

- In this case, the CX32 must be replaced by a SINAMICS S120 CU320/CU320-2.
- PROFINET interface
 If a D4x5 with CBE30 is replaced by a D4x5-2 DP/PN with onboard PROFINET interface,
 then the number of PROFINET ports is reduced from four to three.

Components on port 4 have to be rewired

4. Retrofitting to V4.1

If a SIMOTION D4x5 is downgraded by replacing a device in HW Config, you must take into account the fact that symbolic assignments are only available as of version V4.2. If symbolic assignments are used and, for example, a D4x5 V4.2/SINAMICS V2.6.2 is downgraded to D4x5 V4.1/SINAMICS V2.6.2, "communication for symbolic assignment" must be set up prior to replacing the device in HW Config. This sets up the required addresses.

See also Section Communication for symbolic assignment setup (Page 216).

TIP for synchronous grouping

If you use device-dependent ST libraries, then the upgrade can be accelerated through the following procedure:

- Upgrade the device version for all devices that participate in the synchronous grouping in the ST libraries (example: Change D445 V4.1 to D445-2 V4.2). See also Section Upgrading a library (Page 283).
- 2. Save the project and close it in SIMOTION SCOUT.
- 3. Perform the module replacement for all devices of the synchronous grouping in **HW Config** for this project and then save.
- 4. Open the project in SIMOTION SCOUT. The entire synchronous grouping is now completely upgraded.

8.3.7 Device replacement in HW Config

Procedure

- 1. Double-click the SIMOTION device to be replaced in the project navigator in SIMOTION SCOUT. **HW Config** opens.
- 2. Open the "SIMOTION Drive-based" folder in the hardware catalog.

Note

SIMOTION D is modeled as a compact device in **HW Config**. When modules are being replaced, this means the new module must be moved to the header of the module rack shown and **not to slot 2**. Please make sure that you do not delete the D4x5 rack!

When you move the new module to the rack header using drag-and-drop, the old module will be replaced. Alternatively, you can:

- Select the rack header and double-click the new module in the module catalog to replace the previous module, or
- Right-click the rack header and select "Replace Object"
- 3. Move the new module to the top field of the module rack using drag-and-drop.
- 4. Confirm the dialog that appears with "Yes" to replace the SIMOTION device. The module is replaced.
- 5. Accept the changes made to the hardware configuration with "Station" > "Save and compile".
- 6. Close HW Config.

Note

As of SIMOTION SCOUT V4.2, the following actions are performed automatically by the engineering system during the module replacement (if required):

- Upgrade of the technology packages (TPs)
- Automatic upgrade of the SINAMICS Integrated
- Automatic upgrade of all connected CX32

The upgraded data is transferred to the project and the entire project saved.

If the module hardware changes (e.g. a D425 is replaced with a D435), proceed as described in Section Removal and replacement of the SIMOTION D4x5 (Page 268).

8.3.8 Upgrading technology packages

Overview

The SIMOTION technology packages (e.g. TP CAM, TP PATH, DCBlib) are available in various versions.

You can only use the functions of the technology objects selected if the technology objects are available in the target system. You can select the technology packages and their version for each SIMOTION device. Each version of SIMOTION SCOUT has a kernel (FW version) for the SIMOTION CPU and an appropriate technology package.

TPs during upgrades

Device replacement (in **HW Config**), platform replacement (XML export/import), or even upgrades may cause versions of SIMOTION technology packages (TPs), which are assigned to individual technology objects (TOs), to change.

- The TP version may change when the main version is changed. The TP version depends on the relevant main version in all cases; it may, however, remain unchanged through a number of main versions.
- If service packs and hotfixes are installed, there may even be a selection of TP product versions available for the same TP version

The TP version is automatically upgraded **during device replacement (in HW Config)**. If the TP version changes and there are several product versions available for the new TP version, the latest product version is set automatically. If another product version is preferred, this must be set manually (e.g. selection of V 4.1.5.3).

With a platform replacement (XML export/import), the required technology package along with the TP version and, if necessary, the product version have to be selected manually after the import.

When a SIMOTION CPU is inserted, the TP CAM (latest TP version and product version) is preset per default.

Special displays in the "version" field

- "Select" means that no TP product version has been selected; this state occurs when older projects, in which the selection of a specific product version was not supported, are upgraded. If the project is loaded to the CPU without making a selection, the latest available technology package is loaded automatically.
- "---" means that no version can be determined (e.g. for the TP DCBlib or for older CPU versions < V4.1). If no version can be determined, you must select "---".

Selecting the TP product version

The desired technology package is selected with fine granularity in SIMOTION SCOUT at "Target device" > "Select technology packages ...".

Select Technology Packages				? ×
Select technology packages for D445:				
TP name		TP version	Product vers	ion
TPdcblib_SIMOTION_4_1_5		V2.0		•
DCBADM		V4.1	V4.1.5.6	-
TControl		V4.0	V4.1.5.6	-
CAM_EXT		V4.1	V4.1.5.6	-
		V4.1	V4.1.5.6	-
CAM		V4.1	V4.1.5.6	-
			V4.1.1.0	
			V4.1.1.11	
			V4.1.1.6	
The following technology objects could not be integr	ated due to		V4.1.2.0	
The following technology objects could not be integr			V4.1.2.3	
Incorrect version	Missing to:	hology package	V4153	
	- missing tet	сппоюду раскаде	-V4.1.5.6	
,				
	_			
ОК	Cance	el 📔	Help	
	·			

Figure 8-6 Select technology packages

Note

Device diagnostics can provide information on which technology package product version has been loaded to a CPU.

Loading technology packages to the target device

Technology packages are only loaded to the target device if no technology package has been loaded so far or if "Load to file system" is executed.

If a technology package version changes, the technology package must be explicitly reloaded to the target device. Proceed as follows:

- 1. Select "Download project to target system" in SIMOTION SCOUT.
- Select the "Replace product versions of the technology packages" option and confirm with "OK".

For further information, please refer to the online help for SIMOTION SCOUT.

See also

Deleting user data from CF card (Page 252)

8.3.9 Upgrading the device version of SINAMICS S120 control units

Overview

You can upgrade the device versions of SINAMICS S120 control units that are connected to the SIMOTION D via PROFIBUS or PROFINET in the SIMOTION SCOUT. The SINAMICS version can only ever be upgraded in a project; it cannot be downgraded.

Note

During the device replacement in HW Config, the SINAMICS version

- Of the SINAMICS Integrated of the SIMOTION D4x5 as well as
- The connected CX32 controller extensions

are also upgraded automatically.

A CX32 always has the same SINAMICS version as the SINAMICS Integrated. During the module replacement in **HW Config**, the SIMOTION **and the SINAMICS version** is always defined with the selection of a D4x5 module.

If a SINAMICS S120 control unit is connected via PROFIBUS or PROFINET, the SINAMICS version can be selected independently of the SINAMICS Integrated version.

Procedure

To upgrade a SINAMICS drive unit:

- 1. Right-click the relevant device, e.g. the SINAMICS S120 CU320-2 DP.
- 2. Select "Target device" > "Upgrade device version/characteristic" in the context menu.

The "Upgrade Device Version/Characteristic" dialog box is displayed, listing all available firmware versions.

Upgrade Device Version/Characteristic		×
Current device characteristic and version	SINAMICS \$120 CU320-2 DP V4.3.1	
Available device characteristics:	SINAMICS S120 CU320-2 DP]
Available device versions:	V4.3.2 V4.4	
Upgrade	Cancel Help]
		_

Figure 8-7 Upgrading the device version

3. Select the desired device version/characteristic and click "Upgrade".

This upgrades the SINAMICS S120 control unit.

8.3.10 Upgrading a library

Depending on the configured properties of the libraries used in the project (devicedependent or device-independent), an upgrade of the libraries may be required if the SIMOTION device or the device version changes.

- 1. Open the LIBRARY directory in the project navigator.
- 2. Select a library, right-click to open the context menu, and select "Properties...."
- 3. Select the "TPs/TOs" tab in the "Properties" window.
- Select the SIMOTION device and the technology packages for which the library is to be valid.
- 5. Close the dialog with "OK".

Note

Please also observe the information on device-dependencies in the SIMOTION SCOUT online help.

8.3.11 Save project, compile and check consistency

Procedure

- 1. Execute "Save and recompile all" ("Project" > "Save and recompile all" menu).
- 2. Then perform a consistency check ("Project" > "Check consistency" menu).
- 3. If error messages occur, correct these and repeat the operation.

Note

Note the difference between

- "Save and recompile all" and
- "Save and compile changes"

Save and recompile all

All sources of the entire project are recompiled with this command.

The command is suitable if you are quite sure that all the old data from older SCOUT versions should be removed and replaced with new compilation results.

Use this command if you specifically want to convert a project from an earlier SCOUT version to a newer version. In this way, you take over all error corrections and optimizations.

Save and compile changes

On this command, the whole project is searched for changes. Therefore only the changes are compiled. Use this command for day-to-day operations within a SCOUT version.

8.4 Performing a firmware and project update

8.4.1 Upgrading the CompactFlash Card's boot loader

Upgrading the SIMOTION D may also render it necessary to upgrade the boot loader of the CompactFlash card.

Detailed information on the compatibility relationships for the CF card, boot loader version, SIMOTION D hardware and SIMOTION firmware version can be found in the software compatibility list. This list is available both in the documentation supplied on the SIMOTION SCOUT DVD (\1_Important\English\Compatibility\...) and on the Internet at (http://support.automation.siemens.com/WW/view/en/18857317).

8.4.2 Update - preparatory measures

Upgrading the SIMOTION D

The actions described in this section also apply to downgrading to an older version.

Various options are available for performing a firmware and/or project upgrade on the SIMOTION D.

- Update via IT DIAG (Page 286)
- Upgrade via device update tool (upgrading SIMOTION devices) (Page 286)
- Upgrade via CF card (Page 291)

Note

Upgrading using the device update tool offers a number of advantages (keeping retain data, option of downgrading, no license key handling, etc.).

We therefore recommend using this method for firmware and/or project upgrades.

Requirement (firmware upgrade)

You can find the latest firmware for SIMOTION D:

- On the SIMOTION SCOUT DVDs (e.g. at ...\3_D4xx\Firmware\V4.2\....)
- at Internet address (http://support.automation.siemens.com/WW/view/en/31045047)

Upgrading the SIMOTION D automatically upgrades the firmware of all connected SINAMICS DRIVE-CLiQ components.

Note

Observe the information in the the Read Me files and the upgrade instructions included in the scope of delivery of new SIMOTION versions.

Use only CF cards that have been released for SIMOTION D and have an appropriate and correct boot loader version.

You can find the compatibility relationships in the SIMOTION SCOUT Add-Ons "software products" compatibility list, as well as at Internet address (http://support.automation.siemens.com/WW/view/en/18857317).

NOTICE

The upgrade operation deletes all project data and parameters from the CF card!

Requirement (project upgrade)

You have upgraded your project and, if necessary, adapted the device type and device version, see Section Adapting a project (Updating the project / Replacing the SIMOTION controller) (Page 272).

8.4.3 Update via IT DIAG

The SIMOTION D features an integrated Web server.

In addition to customized Web sites and comprehensive device/diagnostic information, one of the options that IT DIAG offers is performing firmware and project upgrades using a standard PC with Internet Explorer.

As of firmware version V4.2, it is no longer necessary to purchase licenses for SIMOTION IT DIAG and SIMOTION OPC-XML.

Note

D410, D4x5, and D4xx firmware ZIP archives are available for SIMOTION D. The firmware in D4xx archives will run on SIMOTION D410 and SIMOTION D4x5. However, it cannot be loaded with IT DIAG if the CF card contains a firmware version < V4.1 SP2. In this case you should use the D410 or D4x5 firmware archive.

Detailed information can be found in the *SIMOTION IT Ethernet-Based HMI and Diagnostic Functions* Diagnostics Manual.

See also

Adapting a project (Updating the project / Replacing the SIMOTION controller) (Page 272)

8.4.4 Upgrade via device update tool (upgrading SIMOTION devices)

Overview

As of SIMOTION V4.1 SP2, SIMOTION D control units and projects can be upgraded using previously created upgrade data.

Performing an upgrade using upgrade data has the following advantages:

- User-friendly creation of upgrade data via SIMOTION SCOUT with the aid of a wizard (at the machine manufacturer's site)
- SIMOTION devices can be upgraded by the machine operator without the SIMOTION SCOUT Engineering System.
- The machine manufacturer can conveniently send upgrade data via e-mail or post to the machine operator.

- There is no need to use license keys, as licenses are retained.
- Retain data and unit data is retained when upgrades are performed, even across versions.
- An upgrade which has been imported can be discarded again, and the previous configuration restored.
- You can update either a single SIMOTION device or multiple devices from one or more SIMOTION projects.
- It is possible to upgrade parts of a configuration only (e.g. Technology Packages only, firmware only, project only, etc.).

Upgrade data is created by the application engineer at the machine manufacturer's premises using SIMOTION SCOUT. The upgrade data can then be handled flexibly depending on both the SIMOTION device in question (SIMOTION C, D, or P) and the customer requirements:

- Creating upgrade data and then copying it to a storage or upgrade medium:
 - CF card
 - USB stick or
 - IT DIAG file
- Alternatively, the upgrade data can be created and stored in an archive on the PC, with a view to importing it to an upgrade medium suitable for SIMOTION devices at a later point.
- The process of importing the data to an upgrade medium can be performed at the machine manufacturer's premises; alternatively, if the upgrade archive has been transferred to the machine operator, the service engineer can do this on-site.
- The service engineer imports the upgrade data on an operator-guided basis (without any involvement by the application engineer) to the SIMOTION device(s), and upgrades the SIMOTION devices in the process (SIMOTION SCOUT is not required on-site).

The following describes how to upgrade a SIMOTION D with a USB stick. This assumes you have a USB stick containing the appropriate upgrade data.

Requirement

- You have a USB stick containing the upgrade data.
- You have a SIMOTION D module with the required HW version.

The following hardware is required in order to upgrade a SIMOTION D4x5 using a USB stick:

Module	Order No.	Minimum hardware release required ¹⁾
SIMOTION D425	6AU1 425-0AA00-0AA0F	F ²⁾
SIMOTION D435	6AU1 435-0AA00-0AA0	Upgrade via USB stick not supported
SIMOTION D435	6AU1 435-0AA00-0AA1	F ²⁾

Table 8-2 Hardware required for USB stick upgrades

Module	Order No.	Minimum hardware release required ¹⁾
SIMOTION D445	6AU1 445-0AA00-0AA0	A
SIMOTION D445-1	6AU1 445-0AA00-0AA1	A

¹⁾ The HW version is listed on the SIMOTION D type plates.

²⁾ Modules with HW version C to E can be upgraded (upgrade to BIOS \geq V00.00.04.00).

Required BIOS version

With SIMOTION D425/D435, a BIOS version of at least V00.00.04.00 is required for USB support. Modules as of hardware version "F" are supplied with a corresponding BIOS version. A BIOS upgrade can be conducted on SIMOTION D425/D435 modules with a BIOS version < V00.00.04.00. The BIOS version is shown in the device diagnostics in SIMOTION SCOUT.

Proceed as follows to do this:

- 1. Switch the module off and insert a CF card with SIMOTION D4x5 firmware version V4.1 SP2 or higher.
- 2. Turn the left rotary switch (SIM/NCK) to switch position C.
- Switch the module on and wait until the BIOS upgrade has been carried out. The BIOS upgrade is completed when the 7-segment- display shows "5" (RUN LED flashes green at 2 Hz, RDY LED lights up red).
- 4. Switch the module off and reset the rotary switch to "0".

NOTICE

A BIOS upgrade must not be interrupted under any circumstances. With this in mind, do not switch the module off until the BIOS upgrade is complete. A damaged BIOS will require expensive repair work to be carried out at the plant.

5. A successful BIOS upgrade is also displayed in the diagnostic buffer at the next powerup.

Procedure

When using a USB stick to perform an upgrade, proceed as follows:

- 1. Check the position of the service selector switch (left rotary switch SIM/NCK). The switch position must be at "0".
- 2. Insert the USB stick into one of the two USB interfaces on the activated D4x5 (only one USB stick may be inserted).
- 3. Switch the device OFF/ON or reset it using the RESET button.
4. SIMOTION D4x5 will now begin copying the data from the USB stick to the CF card. The copying procedure begins with some LED status changes until finally a yellow/green flashing RDY LED is displayed (0.5 Hz). In the end phase of the upgrade, the RDY LED has longer steady green or yellow phases (< 10 s).</p>

Once copying is complete, the RDY LED will change to

- "Steady green" (only when the RDY-LED is constantly green for > 10 s, has the copying procedure been completed successfully)
- "Steady red" if copying was not successful
- 5. Switch the D4x5 off and remove the USB stick.
- 6. Switch the D4x5 back on. The D4x5 now begins with the actual upgrade. The SF LED flashes green (0.5 Hz) during the upgrade. The procedure can take several minutes.
- 7. Observe the green flashing of the SF LED.
 - As soon as the upgrade procedure has been completed successfully, the SF LED goes out.

The device then boots up automatically in the upgraded configuration (SF LED display then depends on the operating mode of the device).

- If the upgrade procedure was not successful, the SF LED flickers red (10 Hz).

If the upgrade has not been successful "from the point of view of the application" (for example, the machine is not behaving as desired), it can be undone as follows:

- 1. Switch the D4x5 off.
- 2. Turn the left rotary switch (SIM/NCK) to position "B".
- 3. Switch the D4x5 back on.

The system restores the data saved during the upgrade. The data from the upgrade process will be deleted.

- The restoration is indicated by a green flashing SF LED (0.5 Hz) and can take several minutes. When the flashing code is displayed, immediately reset the Service selector switch to "0".
- 5. Observe the flashing of the SF LED.
 - As soon as the restore procedure has been completed successfully, the SF LED goes out.

The device then boots up automatically in the restored configuration. (SF LED display then depends on the respective mode of the device.)

If the restore procedure was not successful, the SF LED flickers red (10 Hz).

Note

If the Service selector switch is not reset or not reset in good time to "0", this results in fault state "Service selector switch is still set to restore" (SF LED flickers red at 10 Hz). In this case, switch the D4x5 off, reset the Service selector switch and switch the D4x5 on again. If the restoration was otherwise successful, the D4x5 boots up with the restored configuration.

Note

In the case of a CPU upgrade via USB stick the SIMOTION D4x5 is booted from the USB stick. A bootable USB stick must, therefore, be used. Due to the rapid developments within the market for USB sticks, it is not possible to recommend any specific devices. SIMATIC USB sticks are an exception to this rule. For more information, see Available on the Internet at

(http://support.automation.siemens.com/WW/view/en/32580863).

Note

If the firmware for SIMOTION D is being upgraded or downgraded, the component firmware will also be upgraded or downgraded automatically depending on the firmware version on the CF card and the firmware version on the SINAMICS components (DRIVE-CLiQ components, CBE30, PM340, etc.).

The upgrade procedure can take several minutes and is indicated by LED displays.

A firmware update on DRIVE-CLiQ components is indicated by the RDY LED flashing red and green:

- FW upgrade running: RDY LED flashing slowly (0.5 Hz)
- FW upgrade complete: RDY LED flashing quickly (2 Hz)

These flashing patterns are also displayed on the yellow RDY LED on the SIMOTION D/CX32, and indicate that a FW update has been carried out on components connected to the SIMOTION D/CX32 or that all components have completed the FW update.

Once the FW upgrade is complete on all components, the components that have been upgraded/downgraded must be powered up.

Requirement

You have a USB stick containing the upgrade data.

Additional references

Detailed information on upgrading devices can be found in the *Upgrading SIMOTION Devices* Operating Instructions.

8.4.5 Upgrade via CF card

8.4.5.1 Backup of the CF card data

Backing up licenses, retain data, and user data

Prior to upgrading/downgrading, as a precaution we would generally recommend backing up the entire content of the CF card to the PC/PG using the card adapter and Windows Explorer.

How you should proceed when it comes to backing up and subsequently restoring data on the CF card depends on whether licenses and/or other retain data and user data which will be required again after the upgrade/downgrade are located on the CF card.

Scenario 1: If the CF card contains no licenses and no retain data or user data which will be required after the upgrade/downgrade

You do not need to take any steps in this case. Delete the content of the CF card and upgrade the firmware as described.

Scenario 2: If the CF card contains licenses (e.g. axis licenses)

Before loading the new firmware, back up the "KEYS" directory to your PC. This can then be copied back to the CF card once you have installed the new firmware.

Note

The license key is stored in the "KEYS" directory on the CF card. When the SIMOTION device starts up for the first time (as of firmware version V4.1), the license key is saved in the boot sector of the CF card.

A license key saved in the boot sector cannot be deleted by means of a user operation; nor can it be deleted by formatting the CF card or rewriting the boot loader.

If the Keys.txt file is no longer present on the CF card (because the "KEYS" directory has been deleted, for example), it will be written again from the boot sector to the "KEYS" directory while the SIMOTION device is starting up. The license key can be changed at any time (by relicensing, for example). When the device is next started up, the license key will be saved in the boot sector again.

In the event of the loss of a license key, a copy can be obtained via the Web License Manager at the following Internet address (<u>http://www.siemens.com/automation/license</u>). You will need the HW serial number printed on the CF card. In the Web License Manager, you have the option of displaying the associated license key.

Scenario 3: If the CF card contains retain data / user data which will be required after the upgrade/downgrade

If you are using your application to back up data to the CF card, you must back this up before upgrading the new firmware.

Example:

- Backing up retain data (non-volatile data saved with _savePersistentMemoryData):
 - user\simotion\pmemory.xml
- Backing up IT DIAG user files, settings (e.g. trace.xml), task trace data, log files, and Java files (classes, archives, user file system, etc.), stored in the following directories:
 - user\simotion\hmicfg
 - user\simotion\hmi
- Backing up configuration data for modular machines in conjunction with the _activateConfiguration system function, stored in the following directory:
 - install\simotion
- Backing up unit data (data saved on the CF card using _saveUnitDataSet/_exportUnitDataSet), stored in the following directory:
 - user\simotion\user dir\<unitname>

Note

When a version is changed, you must use the "Back up variables" function to back up data saved using _saveUnitDataSet or _exportUnitDataSet in a way that is not dependent on the version. You then have the option of restoring them using "Restore variables".

When performing an upgrade with a firmware version \geq V4.1, these two functions are only required for backing up and restoring unit data sets that have been created using _saveUnitDataSet.

Retain and unit data (saved with _exportUnitDataSet) remains valid even after a version upgrade.

8.4.5.2 Firmware upgrade via CF card

Procedure

Proceed as follows to perform the upgrade:

- 1. Switch off the power supply to the D4x5.
- Remove the CF card from the SIMOTION D4x5 and insert it into the CF card adapter on your PC.
- 3. Open Windows Explorer. The CF card must be visible as a removable data carrier in the Windows Explorer under an arbitrary drive letter.

- 4. If necessary, back up the licenses, retain data, and user data on the CF card to your PC (see Section Backup of the CF card data (Page 291)).
- 5. Delete all the data from the CF card.
- 6. Unzip the firmware file to the CF card using a ZIP file utility such as WinZip. Always maintain the file structure when setting up the decompression tool.
- 7. Copy the data saved in step 4 back to the appropriate folder structure on the CF card.
- 8. Remove the CF card from the CF card adapter on your PG/PC.
- 9. Insert the CF card into the D4x5.
- 10.Switch on the power supply for the D4x5. The new firmware is loaded from the CF card to the SIMOTION D4x5.

8.4.5.3 Upgrading SINAMICS

Depending on the settings, the SINAMICS components are also automatically upgraded to the component version of the CF card with a firmware upgrade of the SIMOTION D.

The component version can be obtained from the CONTENT.TXT file in the main directory of the CF card.

Upgrading the firmware of SINAMICS components automatically

When starting up, the system automatically upgrades or downgrades all DRIVE-CLiQ components to the version of the component firmware on the CF card. Components that cannot be downgraded to the component firmware version on the CF card (e.g. old firmware on the CF card and new components to which the old firmware cannot be loaded) retain their firmware version. The resulting firmware version combinations are always functional.

Note

The components' firmware is upgraded or downgraded automatically based on the FW version on the CF card and the FW version on the SINAMICS components (DRIVE-CLiQ components, CBE30, PM340, etc.).

The update can take several minutes and its progress is tracked by corresponding messages appearing in the alarm window of SIMOTION SCOUT.

A firmware update on DRIVE-CLiQ components is indicated by the RDY LED flashing red and green:

- FW upgrade running: RDY LED flashes slowly (0.5 Hz)
- FW upgrade complete: RDY LED flashes quickly (2 Hz)

These flashing patterns are also displayed on the yellow RDY LED on the SIMOTION D/CX32, and indicate that a FW update has been carried out on components connected to the SIMOTION D/CX32 or that all components have completed the FW update.

Go offline once all the FW upgrades have been completed. POWER ON the upgraded/downgraded components.

Upgrading the firmware of the SINAMICS components

The SINAMICS components' firmware is upgraded automatically, depending on the setting of parameter p7826.

- p7826 = 0: Upgrade/downgrade deactivated (factory setting)
- p7826 = 1: Upgrade and downgrade
- p7826 = 2: Upgrade only

CAUTION

The automatic FW upgrade via p7826 = 1 (upgrade and downgrade) must not be deactivated when using Safety Integrated.

If you are upgrading the firmware manually, proceed as follows:

- 1. Select the SINAMICS component in the project navigator, e.g. SINAMICS Integrated.
- 2. Double-click "Overview" in the project navigator.

The "SINAMICS_Integrated - Overview" dialog box opens with a list of available drive objects.

- 3. Click "Version overview" to open the list of connected SINAMICS components.
- 4. Go online and select the devices whose firmware you wish to upgrade.

The list displays the current firmware version of the devices.

- 5. Click "Firmware upgrade" to download the new firmware to the devices. To do so, you must select all components whose firmware is to be upgraded.
- 6. When the firmware upgrade is complete, switch the 24 V power supply off and back on again. The device is now ready for operation.

Note

The SINAMICS components must be configured for a firmware upgrade to take place. The firmware cannot be upgraded if the components have not been configured.

You can also upgrade the firmware using the expert list. See the *SINAMICS S120* Commissioning Manual for a description of how to do this.

8.4.5.4 Loading a project to the target system

Once all the changes required for upgrading your project have been made, you must download the project to the SIMOTION D4x5. You have recompiled the project and checked it for consistency. See Section Saving the project and checking the consistency (Page 284).

Requirement

The firmware required is located on the CF card; for information, see Section Firmware upgrade using a CF card.

8.5 SIMOTION Compact Flash card

Procedure

- 1. Save and compile the project.
- 2. Click "Connect to selected target systems" to establish a connection to the target system.
- 3. Execute "Download project to target system" and then "Copy RAM to ROM" to download the upgraded project to the CF card as well.
- 4. Because of the automatic follow-up configuration in the SINAMICS Integrated drive, you must now execute "Load CPU / drive unit to PG".
- 5. Save the project.

Note

When upgrading SINAMICS drive units (e.g. SINAMICS Integrated) only the p parameters (setting parameters) are loaded into the upgraded project. The r parameters (monitoring parameters) are not loaded. The r parameters in the drive unit are derived or calculated from an automatic subsequent parameterization and must therefore be uploaded to the project. To do this, execute "Load CPU/drive unit to PG". If the upload is not performed, this can lead to inconsistencies in the drive parameterization dialog boxes.

8.5 SIMOTION Compact Flash card

8.5.1 Changing the CompactFlash Card

Requirement

The CF card may only be unplugged and plugged in when the system is switched off (zero current)! The SIMOTION D4x5 is in a de-energized state when all the LEDs are OFF.

Procedure

To change the CF card, proceed as follows:

- 1. Switch off the power supply.
- 2. Remove the CF card from the plug-in slot of the control unit.

8.5 SIMOTION Compact Flash card

3. Gently insert the new CF card into the empty plug-in slot until it clicks into place. The direction of insertion of the CF card is indicated by an arrow located on both the plug-in slot and the CF card.

When properly installed, the card does not extend beyond the housing of the SIMOTION D4x5.

4. Switch the power supply on again.

8.5.2 Writing to the the CompactFlash card

Overview

You can write to the CF card by:

Writing to a CF card inserted into a SIMOTION D

This function requires the connection to be established between the PG/PC and the module.

Writing to a CF card without a SIMOTION D module

For this function, you need a CF card adapter.

Note

The CF card always comes formatted. It contains the SIMOTION Kernel (SIMOTION D firmware).

To ensure that the CF card functions properly, the card must not be repartitioned.

Writing to a CF card inserted into a SIMOTION D

The CF card can be used to store technology packages and user data (programs, configuration data and parameter assignments) from the "volatile data" area on the CF card. Proceed as follows:

- 1. Establish the connection between the SIMOTION D and the PG/PC.
- In SIMOTION SCOUT, the CF card is written to by means of the "Copy RAM to ROM" menu command.

Writing to a CF card without a SIMOTION D module

With a suitable memory card adapter, you can write to the CF card directly via a PG/PC. Always save your project data to the CF card using the PG/PC before you upgrade the SIMOTION firmware, for example.

Note

Files that have been written to the CF card with "Copy RAM to ROM" in SIMOTION SCOUT must not be modified or deleted with Windows. This can corrupt the project.

Service and maintenance

8.5 SIMOTION Compact Flash card

8.5.3 Formatting the CompactFlash card

You can format the CF card, for example, if it is corrupt. Proceed as follows:

- 1. Insert the CompactFlash Card into a CompactFlash Card adapter connected to your PG/PC.
- 2. Format the CF card in Windows (FAT or FAT16 file system).
- 3. If the boot sector of the CF card is also defective, you will have to rewrite the bootloader.

NOTICE

The CF card must only be formatted with FAT or FAT16, and must not be formatted with FAT32 or NTFS.

See also

Bootloader on the CompactFlash card (Page 297)

8.5.4 Bootloader on the CompactFlash card

Writing a boot loader

A boot loader may need to be written in the following situations:

- When a new boot loader is required for the SIMOTION D firmware version used
- When a new boot loader is required for the SIMOTION D hardware version used
- When the boot loader is defective.

The boot loader version can be read out using the SIMOTION SCOUT device diagnostics. If this is not possible, the boot loader version may be incorrect. Possible description of error: All eight LEDs light up yellow.

In this case, replace the boot loader version with the current version.

Use the "Options > Write boot sector..." function to write the boot loader version in the SIMOTION SCOUT to the CF card.

Note

Up to and including V4.2:

You require PG/PC administrator rights to write to the boot sector. If you do not have administrator rights on your PG/PC, an administrator can enter an administrator login for you to use this function under "Options" > "Settings" > "Rights".

8.5 SIMOTION Compact Flash card

Detailed information on the compatibility relationships for the CF card, boot loader version, SIMOTION D hardware and SIMOTION firmware version can be found in the software compatibility list. This list is available both in the documentation supplied on the SIMOTION SCOUT DVD (\1_Important\English\Compatibility\...) and on the Internet at (http://support.automation.siemens.com/WW/view/en/18857317).

8.5.5 Recommended method for dealing with CF cards

Handling CF cards correctly

Please note the following when handling the CF card:

- The CF card may only be inserted or removed when the system is de-energized.
- CF cards are not designed to be rewritten as many times as the user wishes.

With this in mind, you should avoid writing user data from the application to the CF card cyclically. Depending on the system, a write operation from the application may trigger one or more write operations on the CF card. Therefore, we recommend you adopt a conservative approach in terms of the number of writing processes. In other words, do not perform more than 100,000 write access instances from the user program over the estimated service life of the application.

Switching off the SIMOTION D Control Unit during write accesses to the CF card must be avoided at all costs (examples of write accesses to the CF card: "Copy RAM to ROM", savePersistentMemoryData, _saveUnitDataSet, _exportUnitDataSet, etc.). In the worst case scenario, switching off the SIMOTION D Control Unit during write access can damage the file system on the CF card. In this case, the CF card must be reformatted and the firmware/user data reloaded. During this process the licenses remain on the CF card.

8.5.6 Card reader for CF cards

Because of the quickly changing market and the large differences in the quality of card readers, no specific recommendation can be made (except for the following card reader).

If problems occur identifying the CF card, this may be due to an incorrect power up of the card reader.

Designation and ordering data

Card reader for CF/SD memory media, with USB connection Order number: 6FC5 335-0AA00-0AA0

Diagnostics

9.1 Diagnostics via LED displays

Arrangement of LED displays

The front panel of the SIMOTION D4x5 has eight LED displays arranged in two rows of four. There is also a 7-segment display below the blanking cover.



Figure 9-1 7-segment and LED displays on the D4x5

Diagnostics

9.1 Diagnostics via LED displays

LED status key

The LED displays indicate the different operating modes and any errors occurring on the SIMOTION D4x5. They do so by illuminating, flashing, or flickering in different colors.

The following table provides an overview of all occurring LED display combinations.

Meaning of the characters/symbols used:

- 1 = LED on
- 0 = LED off
- 0.5/1 = flashing LED (0.5 Hz)
- 2/1 = flashing LED (2 Hz)
- Λ = flickering LED
- x = LED can light up

9.1.1 SIMOTION D4x5 and SINAMICS Integrated displays

9.1 Diagnostics via LED displays

LED displays

Every LED can illuminate in yellow, red, or green. In the following table, the color of the LED is indicated along with the illumination status.

Table 9-1 LED displays

Meaning	LED display							
	RDY	RUN	STOP	SU/PF	SF	DP1	DP2	OPT
Power-up	1	1	1	1	1	1	1	1
	(yellow)	(yellow)	(yellow)	(yellow)	(yellow)	(yellow)	(yellow)	(yellow)
Power-up of the D4x5 without CF card or with CF card without valid operating system (the boot loader may be defective).	1 (yellow)	1 (yellow)	1 (yellow)	1 (yellow)	1 (yellow)	1 (yellow)	1 (yellow)	1 (yellow)
Incorrect firmware (e.g. D4x5-2)	x	2/1 (yellow)	2/1 (yellow)	2/1 (yellow)	2/1 (yellow)	2/1 (yellow)	2/1 (yellow)	x
CF card has begun to boot, however, an error has occurred (faulty FW).	0.5/1 (red)	0	0	0	0	0	0	0
BIOS update	Λ (red)	x	х	x	x	х	x	x
D4x5 is ready to operate: SIMOTION task system is running, and SINAMICS Integrated is ready to operate	1 (green)	x	x	x	x	x	x	x
Read or write access to CF card	∧ (yellow)	x	x	x	x	x	x	x
RUN	х	1 (green)	0	0	x	x	x	x
Transition from RUN - STOPU	х	1 (green)	0	2/1 (yellow)	x	x	x	x
Transition from STOPU - RUN	x	2/1 (green)	0	1 (yellow)	x	x	x	x
STOPU	x	0	0	1 (yellow)	x	x	x	x
Service mode (axis control panel / measuring function)	x	2/1 (green)	0	2/1 (yellow)	x	x	x	x
Transition from STOPU - STOP	x	0	2/1 (yellow)	1 (yellow)	x	x	x	x
STOP	x	0	1 (yellow)	0	x	x	x	x
Transition from STOP - STOPU	x	0	1 (yellow)	2/1 (yellow)	x	x	х	x
Request for memory reset by the D4x5 itself or via the mode selector	x	0	0.5/1 (yellow)	0	х	х	х	x
Overall reset in progress active ¹⁾	х	0	0	0	0	0	0	0
Memory reset completed	x	0	1 (yellow)	0	0	0	0	0
An interrupt that can be acknowledged (alarm, message, note) is pending	x	x	x	х	1 (red)	x	x	x

Diagnostics

9.1 Diagnostics via LED displays

Meaning	LED display							
	RDY	RUN	STOP	SU/PF	SF	DP1	DP2	OPT
"FAULT" state	٨	٨	٨	٨	٨	٨	٨	٨
(7-segment display shows "F"). For details, see "7-segment display" and "Special operating modes"	(red)	(red)	(red)	(red)	(red)	(red)	(red)	(red)
HOLD mode	x	0.5/1	1	1	x	x	x	x
SIMOTION switches to HOLD mode as soon as the program comes to a breakpoint. When the program leaves the breakpoint, SIMOTION switches out of HOLD mode	^	(green)	(yellow)	(yellow)	~			~
"RESET" state	2/1	x	х	x	x	x	x	x
(7-segment display shows "8") For details, see "7-segment display" and "Special operating modes"	(red/yell ow)							
Incompatible hardware; SIMOTION Kernel is no longer operating with complete functionality on the hardware being used	1 (yellow)	1 (red)	x	x	x	x	x	x
Underlicensing of technology/ option objects	x	x	x	x	0.5/1 (red)	x	x	x
SINAMICS Integrated		-	-	-	-	-	-	-
Firmware initialization	1 (yellow)	x	x	x	x	x	x	0
Module identification (identification via LED) selected via SCOUT or with p124[0]=1.	1 (yellow)	x	x	x	x	x	x	x
Commissioning/reset	0.5/1 (green)	x	x	x	x	x	x	0
SINAMICS Integrated is ready for operation and cyclic DRIVE-CLiQ communication is taking place.	1 (green)	x	x	x	x	x	x	x
General SINAMICS Integrated error (check parameterization/configuration)	2/1 (red)	x	x	x	x	x	x	x
SINAMICS Integrated has not powered up (SINAMICS firmware not available or faulty), or a fault has occurred	1 (red)	x	x	x	x	0	0	x
Read or write access to CF card	∧ (yellow)	x	x	x	x	x	x	x
Upgrade/downgrade of DRIVE-CLiQ components running	0.5/1 (yellow)	x	x	x	x	x	x	x
The upgrade/downgrade of DRIVE-CLiQ components is completed (power OFF/ON of the upgraded/downgraded devices is necessary)	2/1 (yellow)	x	x	x	x	x	x	x
PROFIBUS DP interfaces as master								
No parameter assignment available	x	x	х	х	x	0	0	х

Diagnostics

Meaning	LED display							
	RDY	RUN	STOP	SU/PF	SF	DP1	DP2	OPT
At least one slave is missing.	x	x	x	x	x	1 (red)	1 (red)	x
Bus status "Clear"	x	x	x	x	x	0.5/1 (green)	0.5/1 (green)	x
Bus status "Operate"	x	x	x	x	x	1 (green)	1 (green)	x
PROFIBUS DP interfaces as i-slave			•	·				
No parameter assignment available	x	x	x	x	x	0	0	x
No parameter assignment master available	x	x	x	x	x	1 (red)	1 (red)	x
Bus status "Clear"	x	x	x	x	x	0.5/1 (green)	0.5/1 (green)	x
Bus status "Operate"	x	x	x	x	x	1 (green)	1 (green)	x
PROFINET IO interface (CBE30, X1400)	•							•
No CBE30 connected	x	x	x	x	x	x	x	0
CBE30 runs error-free	x	x	x	x	x	x	x	1 (green)
Bus error (CBE30):	х	x	x	х	х	x	x	2/1
• Failure of a connected I/O device.								(red)
• At least one of the assigned I/O devices cannot be addressed.								
Incorrect or no configuration.								
Firmware downloaded	x	x	x	x	x	x	x	2/1 (green)
Firmware download faulty	x	x	x	x	x	x	x	0.5/1 (red)
Upgrading SIMOTION devices (device up	date tool)		•	•	1			
Upgrade/downgrade running	x	x	x	x	0.5/1 (green)	x	x	x
Upgrade/downgrade completed with error	x	x	x	x	∧ (red)	x	x	x
Upgrade/downgrade completed without error ³⁾	x	x	x	x	0 4)	x	x	x
Upgrade data is being copied from USB stick to CF card	0.5/1 (yellow/ green)	x	x	x	x	x	x	x
Booting is not possible from the used USB stick	0.5/1 (yellow) min. 10 s	x	x	x	x	x	x	x
Upgrade data copying from USB stick to CF card completed with error	∧ (red)	x	x	x	x	x	x	x

Diagnostics

9.1 Diagnostics via LED displays

Meaning	LED disp	LED display						
	RDY	RUN	STOP	SU/PF	SF	DP1	DP2	OPT
Upgrade data copying from USB stick to CF card completed without error	1 (green), min. 10 s ²⁾	x	x	x	x	x	x	x
Backing up diagnostics data and non-vola	tile data							
Backing up diagnostic data and non- volatile data (backup running)	x	x	∧ (yellow)	∧ (yellow)	x	x	x	x
Backing up diagnostic data and non- volatile data (backup completed)	x	∧ (green)	x	x	x	x	x	x

The RDY LED of the SIMOTION D4x5 does not flash yellow/green as in the case of CUs, but instead lights up yellow constantly.

¹⁾ The LED state appears only very briefly due to the speed at which the "overall reset" is completed. The modules then power up (the STOP LED flashes yellow at 2 Hz).

- ²⁾ The copying procedure is completed when the SF LED is steady green for at least 10 s
- ³⁾ The upgrade or downgrade has been completed when the SF LED goes out. The device then boots up automatically in the upgraded or downgraded configuration (SF LED display then depends on the operating mode of the device).

Additional references

More detailed information can be found in the *Upgrading SIMOTION Devices Operating Instructions.*

7-segment display

The 7-segment display provides further status information in addition to the LED displays.

State	Meaning
8	Module in the RESET state (RESET button pressed; overtemperature; faulty/disconnected fan/battery module)
F	F state (FAULT) In the F state, the CPU of the D4x5 is in HOLD mode, i.e. no software is running (D4x5 operating system is stopped)
6	SIMOTION D has powered up
Flashing point	Communication is taking place between SIMOTION and SINAMICS Integrated

Table 9- 2States of the 7-segment display

Special operating modes

The following "special operating modes" are displayed via the status LEDs and the 7-segment display.

F state (FAULT)

In the F state, the CPU of the D4x5 is in HOLD mode, i.e. no software is running (D4x5 operating system is stopped).

The state occurs for faults to which the D4x5 operating system cannot react (e.g. when the max. module temperature has been excessively exceeded).

The state is displayed as follows:

- All LEDs flicker red and
- The 7-segment display shows "F"

Possible measures:

- Check the CF card
- Perform a commissioning again
- Correct any overtemperature
- Replace the D4x5

The state can only be exited by switching the D4x5 off and on.

RESET state (permanent RESET)

In the RESET state, the CPU of the D4x5 is in a permanent RESET, i.e.

- No software is running (D4x5 operating system is stopped) and
- The hardware is in a state that produces less power loss

The state is displayed as follows:

- The RDY LED flashes red/yellow at 2 Hz
- The 7-segment display shows "8"

Possible measures:

- Correct any overtemperature
- Ensure that the 24 V supply is stable without any power dips
- Connect a fan/battery module (only on modules that require this)

The state can only be exited by switching the D4x5 off and on.

9.1 Diagnostics via LED displays

9.1.2 LED displays of the PROFINET interface

Position of the PN interface of the CBE30



Figure 9-2 CBE30 front view

LED displays

Name	Color	State	Meaning				
LINK	Green	On	A different device is connected to port x and a physical connection exists.				
ACT	Yellow	Flashing	Data is being received or sent at port x.				
Fault	red	Off	PROFINET interface is operating without error; the data exchange to all configured I/O devices is running.				
		On	PROFINET interface bus fault				
			No physical connection to a subnet/switch.				
			Incorrect transmission rate				
			Full duplex transmission is not activated				
		Flashing	Failure of a connected I/O device				
		(2 Hz)	• At least one of the assigned I/O devices cannot be addressed.				
			Incorrect or no configuration.				

Table 9-3 Meaning of the LED displays

Diagnostics

9.1 Diagnostics via LED displays

Name	Color	State	Meaning
SYNC ¹⁾	Green	Off	The PROFINET interface has not synchronized yet to the send cycle clock of PROFINET IO with IRT, or PROFINET IO with IRT has not been configured (e.g. only PROFINET IO with RT or TCP/IP communication).
			If IRT has been configured for SIMOTION, the PROFINET interface generates a local substitute cycle clock as long as there is no synchronization to the send cycle clock of PROFINET IO with IRT: SIMOTION task system has synchronized to the local substitute cycle clock of the PROFINET interface. SINAMICS Integrated and external isochronous DP interfaces are synchronized to the local substitute cycle clock of the PROFINET interface.
		On	The PROFINET interface has synchronized to the send cycle clock of PROFINET IO with IRT
			If IRT data has been configured for SIMOTION, then the following applies: The task system of SIMOTION has synchronized to the send cycle clock of PROFINET IO with IRT. SINAMICS Integrated and external isochronous DP interfaces are synchronized to the send cycle clock of PROFINET IO with IRT.
		Flashing (2 Hz)	The PROFINET interface has synchronized to the send cycle clock of PROFINET IO with IRT
			If IRT data has been configured for SIMOTION, then the following applies: The task system of SIMOTION has synchronized to the send cycle
			clock of PROFINET IO with IRT. SINAMICS Integrated and external isochronous DP interfaces are not yet synchronized to the send cycle clock of PROFINET IO with IRT.

¹⁾ If no IRT has been configured, then generally no synchronization will be made to the send cycle clock. LED is off.

9.1.3 LED displays of the Ethernet interface

The Ethernet ports are equipped with LEDs to display Link and Activity.

LED	State	Meaning	
LINK (upper LED)	OFF	No or faulty connection	
	Lights up green	Transfer rate 10 or 100 Mbit/s:	
		A different device is connected to port x and a physical connection exists.	
ACT (lower LED)	OFF	No LAN connection	
	Flickers yellow	LAN connection Data is being received or sent at port x	

Table 9-4 State of the Link and Activity LEDs

9.1 Diagnostics via LED displays

9.1.4 LED displays of the CX32 controller extension

The different states that occur during power-up are indicated by the LEDs on the CX32 controller extension.

- The duration of the individual states varies.
- If an error occurs, the power-up is terminated and the cause is indicated accordingly via the LEDs.
- At the end of an error-free power-up, all LEDs are switched off briefly.
- After power-up, the LEDs are controlled via the loaded software.

9.1.4.1 Behavior of the LEDs during booting of the CX32

LED		State	Comment			
RDY	DP1					
Red	Red	Reset	Hardware reset			
Red, 2 Hz	Red	Error	 D4x5 CompactFlash card not inserted or Load software 2 has not been installed on the D4x5 CompactFlash card or is defective. 			

Table 9-5 Load software 1

Table 9- 6Load software 2

LED		State	Comment		
RDY	DP1				
Off	Red	Loaded	-		
Off	Yellow	Running	_		
Off	Red, 2 Hz	Error file	Software on the D4x5 CompactFlash card is incomplete or defective.		
Off	Red, 0.5 Hz	Error CRC	CRC faulty.		
Off	Off	FW loaded	-		

Table 9-7 Firmware

LED		State	Comment		
RDY	DP1				
Off	Off	Initializing	-		
Alternating	Alternating	Running	See the table below		

9.1.4.2 Behavior of the LEDs after booting of the CX32

Behavior of the LEDs after booting

Table 9-8	Control unit -	description	of the LEDs	s after booting
	oon and	accomption		and booting

LED	Color	State	Description, cause	Remedy	
RDY (READY)	-	OFF	Electronics power supply is missing or outside permissible tolerance range	-	
	Green	Continuous light	The component is ready and cyclic DRIVE-CLiQ communication takes place or the CX32 waits for initial commissioning	-	
		2 Hz flashing light	Writing to the memory card	-	
	Red	Continuous light	At least one fault is present in this component	Remedy and acknowledge fault	
		2 Hz flashing light	Boot error	Check whether the D4x5 CompactFlash card is inserted correctly Replace the D4x5 CompactFlash card Replace the CX32 Perform POWER ON	
	Green/ red	0.5 Hz flashing light	CX32 is ready for operation. However, software licenses are missing	Obtain licenses	
	Yellow	Continuous light	System booting and DRIVE-CLiQ communication is being established	-	
		0.5 Hz flashing light	Firmware update of the connected DRIVE-CLiQ components running	-	
		2 Hz flashing light	Firmware update is complete for components. Wait for POWER ON for the components in question	Turn POWER ON for the components in question	
	Green/ yellow or red/ yellow	1 Hz flashing light	Detection of the components via LED is activated (p0124[0]). Note: Both options depend on the LED status when activated via p0124[0] = 1	-	
DP1 PROFIdrive cyclic operation	-	Red	Cyclic communication is not (yet) running. Note: The PROFIdrive is ready for communication when the CX32 is ready for operation (see RDY LED)	-	
	Green	Continuous light	Cyclic communication is taking place.	-	

LED	Color	State	Description, cause	Remedy
		0.5 Hz flashing light	 Full cyclic communication has not yet taken place. Possible causes: D4x5 does not transfer any setpoints During isochronous operation, no global control (GC) or a faulty global control (GC) is transferred by the D4x5 	_
	Red	Continuous light	Cyclic communication has been interrupted.	Remedy fault
	Yellow	2 Hz flashing light	Firmware checksum error (CRC error)	Check whether the memory card is inserted correctly Replace the memory card Replace the CX32 Perform POWER ON

9.2 Diagnostic data and non-volatile data

9.2.1 Overview

As of V4.1 SP2, and without the need for the SCOUT engineering system, you can use simple operations (e.g. setting switches) to:

- Back up diagnostic data, including non-volatile data (retain data) to the CF card; for information, see Section Backing up diagnostic data and non-volatile data (Page 310).
- Back up HTML pages (including the most up-to-date content) to the CF card for diagnostic purposes; for information, see Section Diagnostics via HTML pages (Page 315)
- Restore backed-up non-volatile data (retain data); for information, see Section Deleting/restoring non-volatile data (Page 317)

9.2.2 Backing up diagnostic data and non-volatile data

9.2.2.1 Diagnostic data

Following a fault on a SIMOTION device, diagnostic data (e.g. diagnostic buffer content, upto-date content of websites, etc.) can provide important information on the cause of the fault. For this purpose, such data can be backed up to the CompactFlash Card using a simple operation (e.g. by setting a switch on the D4x5).

You then have the following options for the diagnostic data:

- You can retrieve it from the CompactFlash Card using a card reader
- You can download it using IT DIAG or FTP

You can also use it for diagnostic purposes or provide it to technical support for evaluation purposes.

Various options are available to you for backing up diagnostic data:

- Backup during operation (in STOP/STOPU/RUN mode); for information, see the section titled Procedure: "Backup during operation" (Page 311)
 - Using IT DIAG;
 - IT DIAG also offers the option of retrieving diagnostic data online
 - Using a service selector switch
- Backup while the module is powering up; for information, see the section titled Procedure: "Backup during power-up" (Page 312).
 - Using a service selector switch
 - Controlling diagnostic data creation using an INI file stored on the CompactFlash Card

9.2.2.2 Non-volatile data (retain data)

In addition to diagnostic data, non-volatile data (retain data) is saved on the CompactFlash Card. You can use these in situations where the non-volatile data has not been saved on the CompactFlash Card using the _savePersistentMemoryData system function, and you wish to restore the non-volatile data after a CPU has been replaced.

Note

While the non-volatile data are stored as a "PMEMORY.XML" backup file in the "...USER/SIMOTION" directory using the _savePersistentMemoryData system function, backing up diagnostic data and non-volatile data involves storing data in the "...USER\SIMOTION\HMI\SYSLOG\DIAG directory.

9.2.2.3 Procedure for backing up during operation

Procedure

The advantage of backing up diagnostic data and non-volatile data during operation is that enhanced diagnostic information is available via HTML pages and TO alarm information.

Data is backed up:

- With IT DIAG by selecting "Diagnostics > Diagnostics Files"; for information, see Section Backing up diagnostic data and non-volatile data with IT DIAG (Page 318)
- Using the service selector switch (see the description below)

Service selector switch

To back up diagnostic data and non-volatile data using a service selector switch, proceed as follows:

 Set the service selector switch to "Diagnostics" (position "D"). The positions of the mode switch are not relevant (i.e. the set operating mode remains

unchanged). The diagnostic data and non-volatile data can be created in STOP, STOPU, and RUN modes.



Figure 9-3 Mode switch and service selector switch

- 2. The diagnostic data and non-volatile data is backed up to the CF card. The backup process is indicated by the status LEDs as shown in the following table:
- 3. Once the backup is complete, switch the D4x5 off.
- 4. Remove the CF card and reset the service selector switch to its original setting.

Table 9-9 LED displays during backup process

Status	LED displays on the D4x5
Backup in progress	STOP LED and SU/PF LED flicker yellow
Backup complete	RUN LED flickers green

9.2.2.4 Procedure for backing up during startup

Procedure

Backing up diagnostic data and non-volatile data during startup provides you with diagnostic information without HTML pages / TO alarm information.

Backing up during startup is particularly advisable for SIMOTION devices that are not run capable or have crashed.

Diagnostic data and non-volatile data is backed up

- Using a service selector switch or
- Using an INI file saved on the CF card

The procedure for each is described below.

Service selector switch

Data is backed up using a service selector switch as follows:

 Set the service selector switch to "Diagnostics" (position D). The positions of the mode selector switch are not relevant (i.e. the set operating mode remains unchanged).



Figure 9-4 Mode switch and service selector switch

- 2. Switch the D4x5 off and back on again.
- 3. Wait for the device to power up.

The diagnostics data and non-volatile data is backed up to the CF card during startup, provided that this is still possible and is not prevented by HW defects, for example. Note the LED displays as shown in the following table.

- 4. Once the backup is complete, switch the D4x5 off.
- 5. Remove the CF card and reset the service selector switch to its original setting.

Table 9-10 LED displays during backup process

Status	LED displays on the D4x5		
Backup in progress	STOP LED and SU/PF LED flicker yellow		
Backup complete	RUN LED flickers green		

INI file in the main CF card directory

- 1. Use a text editor (such as Notepad) to create a file called simotion.ini
- 2. Add the following text: **DIAG_FILES=1** You must use a text editor and may not use any formatting in the text.
- 3. Copy the simotion.ini file to the main CF card directory.
- 4. Insert the CF card into the module, which is switched off.
- 5. Switch the D4x5 on and allow the SIMOTION device to power up. The diagnostic data and the non-volatile data will be backed up to the data carrier during power-up if this is still possible and is not prevented by HW defects, for example. Note the LED displays as shown in the following table.
- 6. Once the backup is complete, switch off the SIMOTION device.
- 7. Remove the CF card.

Status	LED displays on the D4x5		
Backup in progress	STOP LED and SU/PF LED flicker yellow		
Backup complete	RUN LED flickers green		

NOTICE

To suppress startup in diagnostics mode again, you must delete the simotion.ini file from the CF card.

9.2.2.5 Storing data

Storing diagnostic data and non-volatile data

You can find diagnostic data and non-volatile data on the CompactFlash Card in the \USER\SIMOTION\HMI\SYSLOG\DIAG directory.

Copy these data and transfer them to technical support on request. A standard card reader can be used to transfer the diagnostic data the CompactFlash Card via standard IT DIAG sites or FTP.

The following data are stored:

File	Application		
DIAGBUF.TXT	Diagnostic buffer in a simple text format:		
	Numerical values; no specific plain text. A text editor is used for evaluation purposes.		
PMEMORY.XML	Non-volatile data (retain data)		
	Operator input can be used to restore the non-volatile data saved after a CPU has been replaced. (For information, see the section titled Restoring non-volatile data (Page 317)).		
TOALARMS.TXT	Text file containing the pending TO alarms. Only TO IDs, alarm numbers, and associated HEX values.		
	Note: The TO alarms are only created if diagnostic data have been created during operation (STOP/STOPU/RUN).		
Website	If the diagnostic data is backed up, the URLs are requested from the text file (DIAGURLS.TXT) and stored as websites together with their content. (For information, see the section titled Diagnostics for websites (Page 315)).		
	Note: Note:The websites are only stored if diagnostic data are created during operation (STOP/STOPU/RUN).		
Other files	All other files stored in the directory are only of relevance to technical support.		

Table 9-12 Diagnostic data on the CompactFlash Card

Note

Use websites if you wish to back up diagnostic data in plain-text format. Websites enable user-friendly diagnostics. In addition to the standard IT DIAG diagnostics sites, you have the option of creating your own websites (e.g. for the axis status or for machine diagnostics). Customized diagnostics sites are particularly suitable for application problems, as you can define the contents yourself.

9.2.3 Diagnostics via websites

In the "DIAGURLS.TXT" text file, found in the ...\USER\SIMOTION\HMI\SYSLOG\DIAG directory, you can specify HTML files whose status is to be stored on the CF card when diagnostic data is created during operation. (For example, "devinfo.mcs" must be entered for the "devinfo.htm" HTML page.)

Since the pages in question are stored together with their most up-to-date contents, this enables the latest status information regarding the SIMOTION device, as well as the machine/system, from the point at which diagnostic data were created (e.g. when the service selector switch was activated) to be archived.

In addition to the standard IT DIAG diagnostics pages, it is possible to store customized sites. Information on creating pages of this type can be found in, for example, Utilities & Applications.

Diagnostics

9.2 Diagnostic data and non-volatile data

-1	SIEN	IENS						Watch	Overview	Copy Link
	Conne	cted device	e nam	e: D44	5			١T	nu Sep 02 01	7:12:04 2010
SIMOTION D445	Messa	ages & Log	js							Refresh
▶ Home	Diag buffe	er Diag buffe	r drive	Alarms	Alarms drive	Alarm buffer	Syslog	Userlog	J	
									🗖 Show	Hex Values
Device Info	Nr	Time	Date	E	/ent					_
	1 0	07:09:49.198	02.09	.10 Or	ne or more runtii	ne software lice	inses mis	ssing		
► Diagnostics	2 0	07:07:01.780	02.09	.10 Oj	perating mode F	UN reached				
P Diagnostics	3 0	07:07:01.744	02.09	.10 Oj	perating mode tr	ansition from S ⁻	TARTUP I	to RUN: S	Start	
	4 0	07:07:01.744	02.09	.10 Oj	perating mode S	TARTUP reache	ed			
▶ messages&Logs	5 0	07:07:01.723	02.09	.10 Oj	perating mode tr	ansition from S ⁻	TOP_U to	STARTU	JP: Start	
	6 (07:07:01.690	02.09	.10 0	perating mode S	TOP_U reached	1 			
Machine Overview	7 0	07:07:01.678	02.09	.10 Op	perating mode tr	ansition from S	TOP to ST	FOP_U: S	tart	
	8 (17:00:56.242	02.09	.10 PF	ROFIBUS DP 3:	Station return, n	ode 3			
► Manage Config	9 (17:00:49.426	02.09	.10 0	perating mode 9	TOP reached				
	10 L	17:00:47.425	02.09	.10 0:	ser programm b	eing loaded, mo)de: 3			•
▶ Settings										
► Files										
► User's Area										

Figure 9-5 Diagnostics buffer with generated diagnostic data

The following points must be noted for the DIAGURLS.TXT file:

- A DIAGURLS.TXT file containing the standard IT DIAG pages is automatically created if you have not stored your own DIAGURLS.TXT file.
- Standard IT DIAG pages are entered "without" a path specification (e.g. "devinfo.mcs" for the standard IT DIAG site "devinfo.htm").
- Customized IT DIAG pages (such as "user.htm") in the \USER\SIMOTION\HMI\FILES directory on the CF card must contain the FILES/ path specification.
- If you have created subfolders (e.g. "myfolder" in the FILES directory), these must also appear in the path.
- Only one file name may be used per line.
- Empty lines are not permitted (an empty line will be interpreted as the end of the list).

- No distinction is made between upper-case and lower-case letters.
- It does not matter whether you use "\" or "/" in the path name.

DIAGURLS.TXT - Notepad	
<u>File Edit Format View Help</u>	
alarms.mcs alarmsdrv.mcs alarmbuf.mcs devinfo.mcs diagbuff.mcs diagbuffdrv.mcs diagnost.mcs ipconfig.mcs mempool.mcs start.mcs taskrunt.mcs	IT DIAG Standard pages
files\user.mcs FILES/myfolder/user.mcs	IT DIAG User pages
Figure 9-6 Depiction of DIAG	URLS.TXT editor

Additional references

For detailed information about IT DIAG device and diagnostic information, see the *SIMOTION IT Ethernet-Based HMI and Diagnostic Functions* Diagnostics Manual.

9.2.4 Deleting/restoring non-volatile data

Requirement

The diagnostic data and non-volatile data has been backed up to the CF card; for information, see Section Backing up diagnostic data and non-volatile data (Page 310).

Procedure

To restore non-volatile data after a CPU has been replaced, proceed as follows:

- 1. Insert the CF card into the new D4x5 (which must be switched off).
- 2. Set the service selector switch to the "Delete/restore non-volatile data" setting (switch position "1").

The positions of the mode selector are not relevant (i.e. the set operating mode remains unchanged).



Figure 9-7 Switch position 1 for deleting/restoring non-volatile data

 Allow the D4x5 to power up; the non-volatile data is first deleted and then restored while this is taking place.
 If there is a file called "PMEMORY.XML" in the "USER/SIMOTION" directory on the CompactElash Card, this will be restored (rather than the "PMEMORY XML" file saved

CompactFlash Card, this will be restored (rather than the "PMEMORY.XML" file saved using diagnostics in directory \USER\SIMOTION\HMI\SYSLOG\DIAG). The order of priority for restoration is as follows:

- /USER/SIMOTION/PMEMORY.XML
- /USER/SIMOTION/PMEMORY.BAK
- /USER/SIMOTION/HMI/SYSLOG/DIAG/PMEMORY.XML

Note

When the "Delete/restore non-volatile data" switch position is selected, the nonvolatile data of the D4x5 is first deleted and then restored by means of the PMEMORY backup file.

- 4. Once the D4x5 has powered up, switch it off.
- 5. Reset the service selector switch to its original setting.
- 6. Switch the D4x5 back on.

9.2.5 Backing up diagnostic data and non-volatile data using IT DIAG

SIMOTION devices feature pre-configured, standard IT DIAG pages. These pages can be displayed via Ethernet using a commercially available browser. Additionally, you have the option of creating your own HTML pages and incorporating service and diagnostic information.

You can also use IT DIAG to back up diagnostic data and non-volatile data. IT DIAG is opened by entering the IP address of the SIMOTION device in the address bar of the browser; e.g. http://169.254.11.22

This opens the IT DIAG start screen. To back up diagnostic data and non-volatile data, call up the "Diagnostic files" page from the "Diagnostics" menu.

_1	SIEMENS Watch Overview CopyLin	ık
20	Connected device name: D445 Thu Sep 02 07:22:15 2	010
SIMOTION D445	Diagnostics	;h
► Home	Diagnostics Task runtime Service overview Watch Trace Tasktrace Diagnostic files	
 Device Info Diagnostics 	Create general diagnostic files This function will create several diagnostic information files and save them to memory card of the SIMOTION device under folder SYSLOG/DIAG.	
► Messages&Logs		
► Machine Overview		_
► Manage Config	HTML - diagnostic files	
► Settings	SYSLOG/DIAG. To customize the list of files, please edit file "DIAGURLS.TXT" in the same folder.	
▶ Files	Create html diagfiles	
► User's Area		
	Get diagnostic files After pressing button "Zip all diagfiles", all diagnostic information files (general and HTML) which are present on the memory card of the SIMOTION device will be zipped into a file called "DIAGARCHIVE.ZIP". Download the file by pressing button "Get diagarchive". Get diagarchive	
	Delete diagnostic files This function will delete all diagnostic information files (general and html) which are present on the memory card of the SIMOTION device under folder SYSLOG/DIAG. Delete all diagfiles	-

Figure 9-8 IT DIAG

9.3 Additional service and diagnostics options

Button	Function
Create general diagfiles	This button saves diagnostic data and non-volatile data in the\USER\SIMOTION\HMI\SYSLOG\DIAG directory. HTML files used for diagnostics purposes are not saved.
Create html diagfiles	This button is used to save diagnostics HTML pages on the data carrier. It should be noted that only those pages that are listed in the DIAGURLS.TXT file in directory\USER\SIMOTION\HMI\SYSLOG\DIAG are backed up, see Section Backing up diagnostic data and non-volatile data (Page 310).
Zip all diagfiles	The "zip all Diagfiles" button enables you to compress diagnostics files. This stores all files and folders in a ZIP file in directory\USER\SIMOTION\HMI\SYSLOG\DIAG, while retaining the folder structure.
Get diagarchive	This button is used to save the ZIP archive to connected programming devices/PCs.
Delete all diagfiles	This button is used to delete all data stored in the\USER\SIMOTION\HMI\SYSLOG\DIAG directory; the directory itself is not removed, however.

Table 9-13 Functions on the "Diagnostic files" HTML page

You can find diagnostic data and non-volatile data on the CF card in the following directory: \USER\SIMOTION\HMI\SYSLOG\DIAG

Additional references

Detailed information can be found in the *SIMOTION IT Ethernet-Based HMI and Diagnostic Functions* Diagnostics Manual.

9.3 Additional service and diagnostics options

9.3.1 SIMOTION Task Profiler application

The SIMOTION Task Profiler is a dedicated application installed parallel to SIMOTION SCOUT during SIMOTION SCOUT setup. The Task Profiler can be called in online mode using device diagnostics in SIMOTION SCOUT or the Windows application. In the event of a malfunction or error, the Task Trace data can be written to a directory or the CompactFlash Card. They can then be processed using the Task Trace Viewer.

Additional references

For detailed information, refer to the SIMOTION Task Trace Function Manual.

9.3 Additional service and diagnostics options

9.3.2 Diagnostics using IT DIAG

The SIMOTION D features an integrated Web server.

In addition to customized Web pages and the option of performing firmware and project updates, IT DIAG provides comprehensive device and diagnostic information that can be called up using a standard PC with Internet Explorer.

As of firmware version V4.2, it is no longer necessary to purchase licenses for SIMOTION IT DIAG and SIMOTION OPC-XML.

Additional references

Detailed information can be found in the *SIMOTION IT Ethernet-Based HMI and Diagnostic Functions* Diagnostics Manual.

```
Diagnostics
```

9.3 Additional service and diagnostics options

Configuration of drive-related I/Os (without symbolic assignment)

Further information and programming examples for configuring drive-related I/Os without symbolic assignment can be found

- On the Internet at http://support.automation.siemens.com/WW/view/en/29063656 (http://support.automation.siemens.com/WW/view/en/29063656)
- In SIMOTION Utilities & Applications

SIMOTION Utilities & Applications is part of the scope of delivery of SIMOTION SCOUT.

The configuration of **local measuring inputs** is fundamentally different to the configuration of **global measuring inputs**.

The assignment of the local measuring inputs is permanently related to the hardware of the control unit and is performed

- On the drive side via the drive expert list and
- During the configuration of the TO measuringInput via the measuring input number

Local and global measuring inputs have different properties. Detailed information on the differences can be found in the appendix, in Section Local and global measuring inputs (Page 323)

Information on the configuration can be found

- For global measuring inputs (with symbolic assignment) in Section Configuration of global measuring inputs (Page 230)
- For local measuring inputs in the appendix, in Section Configuration of local measuring inputs (Page 325)

A.1 Local and global measuring inputs

Local and global measuring inputs

Depending on the used hardware platform, the following local and global measuring inputs are available for the measuring tasks:

- Local measuring inputs are axis-related and implemented in the SINAMICS drive. The actual position value is measured.
- **Global measuring inputs** can be freely assigned to the axes and add an internal time stamp to the measurement result for more precise determination of the axis positions.

The term "central measuring input" is also used within the context of drives.

A.1 Local and global measuring inputs

	Local measuring input	Global measuring input
Hardware supported	D410, D4x5, D4x5-2 (terminal X122/X132), CX32, CX32-2, CU310, CU320, CU320-2	TM15, TM17 High Feature, D410, D4x5, D4x5-2 (terminal X122, X132, X142), CX32, CX32-2, CU310, CU320, CU320-2
Measurement operation	With a signal edge at the relevant input, the current actual values of an encoder connected to a control unit are measured with positioning accuracy to determine lengths and distances.	With a signal edge at the relevant input, the current actual values of one or more encoders are measured using time stamp functionality with positioning accuracy in order to provide information for determining lengths and distances (possible with any encoders included in the project).
Configuration of the TO measuringInput in the SIMOTION SCOUT	The assignment of inputs is always permanent depending on the hardware of the control unit and is performed during the configuration of the TO measuringInput using the measuring input number.	The assignment of inputs is not fixed depending on the hardware and is performed during the configuration of the TO measuring input by means of symbolic assignment or the hardware address.
TO measuringInput setting: Single measurement (Measurement jobs must be issued individually for each measurement. Several interpolation cycle clocks lie between two measurements.)	Yes	Yes
TO measuringInput setting: Cyclic measuring (Measuring is activated just once and runs cyclically until deactivated.)	No	Yes D410, D4x5, D4x5-2 (terminal X122, X132), CX32, CX32-2, CU310, CU320, CU320-2:
		The minimum interval between two measurements is three servo cycle clocks (max. two edges per measurement).
		D4x5-2 (terminal X142), TM17 High Feature:
		The minimum interval between two measurements is one servo cycle clock (max. two edges per measurement).
		IM15: No cyclic measurement available
Use of multiple TO measuringInputs on one axis/encoder, whereby these can be active concurrently.	No	Yes
Listening TO measuringInput	No	Yes
Measuring on virtual axes	No	Yes
Measuring on axes attached to a different drive unit	No	Yes

Table A- 1	Comparison of lo	cal and global	measuring inputs
------------	------------------	----------------	------------------

SIMOTION Utilities & Applications includes, for example, a tool to estimate:
- The time between a measurement job being initiated and it being effective in the drive
- The minimum time between two measurement jobs

SIMOTION Utilities & Applications is part of the scope of delivery of SIMOTION SCOUT.

Table A-2 Measuring inputs - overview of quantity structures and functionality

	Maximum available quantity structure					
	D410, CU310, CX32	D4x5, CU320	CX32-2	D4x5-2 - X122/X132 - X142	TM15	TM17 High Feature
Maximum number of measuring input inputs	3	6	4	- 8 - 8	24	16
Can be configured as a local measuring input	x	x	x	- 8 - 0	-	-
Can be configured as a global measuring input	x	x	x	- 8 - 8	x	x

A.2 Configuring local measuring inputs

Configuring local measuring inputs

Local measuring inputs are always permanently assigned to an axis (drive). They are configured separately for each drive. The drive and the measuring input input must always be located on the same control unit. The measurement results are transferred using the axis message frame in accordance with the PROFIdrive profile. Message frame 39x does not need to be configured for local measuring inputs.

The settings for the use of the local measuring inputs must be made in the expert list.

In order to use an I/O terminal on a D4x5, CX32 or SINAMICS control unit as measuring input input, proceed as follows:

- 1. Double-click the "Inputs/outputs" entry below the control unit in the project navigator.
- 2. Click the "Bidirectional digital inputs/outputs" tab.
- 3. In this tab, configure the required I/O terminal as input. The configuration can also be set channel-granular on the p728 parameter using the expert list of the control unit.

Specification of the measuring input input terminal must be made in the expert list of the respective drive for local measuring inputs.

A.2 Configuring local measuring inputs

	Parameters in the expert list of the drive	Parameterization as	
		D4x5, CU320	CX32, CU310
Specification of the input terminal of the measuring input in the expert list of the drive	p488[0] (measuring input 1 input terminal, encoder 1)	DI/DO 9 or DI/DO 10 or DI/DO 11 or DI/DO 13 or DI/DO 14 or DI/DO 15	DI/DO 9 or DI/DO 10 or DI/DO 11
	p488[1] (measuring input 1 input terminal, encoder 2) p488[2] (measuring input 1 input terminal, encoder 3)		
	p489[0] (measuring input 2 input terminal, encoder 1)		
	p489[1] (measuring input 2 input terminal, encoder 2)		
	p489[2] (measuring input 2 input terminal, encoder 3)		

 Table A- 3
 Local measuring inputs, required settings in the expert list

As a maximum of three encoders can be assigned to a drive, the index [0...2] specifies whether the measurement applies to encoder 1, 2, or 3.

The following must be taken into account:

- Only two TO measuringInputs can be configured per TO axis or TO externalEncoder.
- Only one TO measuringInput can be active on a TO axis or TO externalEncoder.

Table A- 4	Local measuring inputs, configuration of t	he TO measuringInput
------------	--	----------------------

Axis measuring system no.	Under axis measuring system number, enter the number of the used encoder system (namely, encoder 1, 2 or 3). Encoder system 1 is the default setting.
Drive-related (local measuring input)	Activate the checkbox when a local measuring input is used.
Measuring input number	Enter here which measuring input is used (namely, 1 or 2). Input 1 is the default setting.

Detailed information can be found in the *SIMOTION Motion Control Output Cams and Measuring Inputs* Function Manual.

Standards and approvals

B.1 General rules

EN 61131, EN 60950

The SIMOTION programmable controller meets the requirements and criteria of the standards EN 61131 and EN 60950.

CE marking



EMC Directive

SIMOTION products are designed for industrial use in accordance with product standard DIN EN 61800-3, Category C2.

cULus Approval

C US	Listed component mark for United States and the Canada Underwriters Laboratories (UL) according to Standard UL 508, File E164110, File E115352, File E85972.
------	--

EMC

USA	
Federal Communications Commission Radio Frequency Interference Statement	This equipment has been tested and found to comply with the limits for a Class A digital device, pursuant to Part 15 of the FCC Rules. These limits are designed to provide reasonable protection against harmful interference when the equipment is operated in a commercial environment. This equipment generates, uses, and can radiate radio frequency energy and, if not installed and used in accordance with the instruction manual, may cause harmful interference to radio communications. Operation of this equipment in a residential area is likely to cause harmful interference in which case the user will be required to correct the interference at his own expense.
Shielded Cables	Shielded cables must be used with this equipment to maintain compliance with FCC regulations.

B.1 General rules

USA	
Modifications	Changes or modifications not expressly approved by the manufacturer could void the user's authority to operate the equipment.
Conditions of Operations	This device complies with Part 15 of the FCC Rules. Operation is subject to the following two conditions: (1) this device may not cause harmful interference, and (2) this device must accept any interference received, including interference that may cause undesired operation.

CANADA	
Canadian Notice	This Class B digital apparatus complies with Canadian ICES-003.
Avis Canadien	Cet appareil numérique de la classe B est conforme à la norme NMB-003 du Canada.

AUSTRALIA	
C	D425, D435, D445, D445-1 meets the requirements of the AS/NZS CISPR 22.

Declaration of conformity

The current Declaration of conformity is available on the Internet at Declaration of conformity (http://support.automation.siemens.com/WW/view/en/10805446/134200).

Electromagnetic compatibility

Standards for EMC are satisfied, if the EMC Installation Guideline is observed.

CAUTION

There is a risk of injury or of damage to assets. In hazardous areas, personal injury or damage to assets can occur if plug-in connections are disconnected during operation. Always de-energize your equipment in hazardous areas before disconnecting plug-in connections.

B.2 Safety of electronic controllers

Note

The product standard EN 61800-3 describes the EMC requirements placed on "Variablespeed drive systems". As such, it defines different limits depending on the location of the drive system.

SINAMICS S120 power units are designed for use in the second environment. The term second environment refers to all locations outside residential areas. These are basically industrial areas which are supplied from the medium-voltage line supply via their own transformers.

It is essential to follow the installation instructions in the SINAMICS S120 Manuals in order to ensure compliance with emitted interference and immunity values.

For more information on this topic also refer to Catalog PM21 as well as the SINAMICS Function Manuals.

B.2 Safety of electronic controllers

Introduction

The following remarks relate to fundamental criteria and apply irrespective of the type of controller and the manufacturer.

Risk

A higher degree of safety standard applies to all applications and situations where there is a risk of material damage or injury to persons if there is a failure. Special regulations specific to the system apply to such applications. These must be taken into account for configuration of the controller (e.g. VDE 0116 for furnaces).

For electronic controllers with safety responsibility, the measures required for preventing or controlling faults depend on the hazard inherent in the plant. In this respect, the basic measures listed above are no longer adequate once the hazard exceeds a certain potential. Additional measures (e.g. double redundancy, tests, checksums, etc.) for the controller must implemented and certified (DIN VDE 0801).

B.2 Safety of electronic controllers

The residual risk

When assessing his machine's risk in accordance with the EC Machinery Directive, the machine manufacturer must take into account the following residual risks emanating from the control and drive components:

- 1. Unintentional movements of driven machine components during commissioning, operation, maintenance, and repairs caused by, for example:
 - Hardware defects and/or software errors in the sensors, controllers, actuators, and connection technology
 - Response times of the controller and drive
 - Operating and/or ambient conditions not within the scope of the specification
 - Parameterization, programming, cabling, and installation errors
 - Use of radio devices / cellular phones in the immediate vicinity of the controller
 - External influences / damage
- 2. Exceptional temperatures as well as emissions of light, noise, particles, or gas caused by, for example:
 - Component malfunctions
 - Software errors
 - Operating and/or ambient conditions not within the scope of the specification
 - External influences / damage
- 3. Hazardous shock voltages caused by, for example:
 - Component malfunctions
 - Influence of electrostatic charging
 - Induction of voltages in moving motors
 - Operating and/or ambient conditions not within the scope of the specification
 - Condensation / conductive contamination
 - External influences / damage
- 4. Electrical, magnetic and electromagnetic fields generated in operation that can pose a risk to people with a pacemaker, implants or metal replacement joints, etc. if they are too close
- 5. Release of environmental pollutants or emissions as a result of improper operation of the system and/or failure to dispose of components safely and correctly

ESD guidelines

C.1 ESD definition

What does ESD mean?

All electronic modules are equipped with highly integrated modules or components. Because of the technology used, these electronic components are very sensitive to overvoltages and thus to discharge of static electricity.

The acronym **ESD** has become the established designation for such Electrostatic Sensitive **D**evices. The **ESD** designation is used internationally to refer to **e**lectrostatic **s**ensitive **d**evices.

Electrostatic sensitive devices are identified by the following symbol:



Figure C-1 Symbol for identification of electrostatic sensitive devices

Electrostatic sensitive devices can be irreparably damaged by voltages that are far lower than anything a person can perceive. These voltages occur if you touch a component or the electrical connection of a module without having previously discharged any static from your body. Any damage that occurs to a module as a result of overvoltage is generally not recognized immediately and only comes to light after the equipment has been operating for some time.

C.2 Electrostatic charging of individuals

C.2 Electrostatic charging of individuals

Any person who is not conductively connected to the electrical potential of the environment can accumulate an electrostatic charge.

This figure indicates the maximum electrostatic charges that can accumulate on an operator when he comes into contact with the indicated materials. These values comply with the specifications in IEC 801-2.



Figure C-2 Electrostatic voltage that can accumulate on operating personnel

C.3 Basic measures for protection against discharge of static electricity

C.3 Basic measures for protection against discharge of static electricity

Ensure sufficient grounding

When working with electrostatic sensitive devices, make sure that the you, your workstation, and the packaging are properly grounded. This prevents the accumulation of static electricity.

Avoid direct contact

You should only touch ESD components if unavoidable (for example, during maintenance work). When you touch modules, make sure that you do not touch either the pins on the modules or the printed conductors. If you follow these instructions, electrostatic discharge cannot reach or damage sensitive components.

If you have to take measurements on a module, make sure that you first discharge any static that may have accumulated in your body. To do this, touch a grounded metal object. Only use grounded measuring instruments.

ESD guidelines

C.3 Basic measures for protection against discharge of static electricity

Index

Α

Active setting Programming devices/PCs, 123 Ambient conditions Climatic, 28 Automatic configuration, 168 Automatic controller setting Position controller, 240 Speed controller, 239 Automatic position controller setting, 240 Automatic speed controller setting, 239 Axis Creating with axis wizard, 204 Testing with the axis control panel, 212 Axis control panel, 211 Axis grouping, 15 DRIVE-CLiQ components, 16 SIMOTION D, 16 SINAMICS infeed, 16 SINAMICS power unit, 16

В

batteryexisting, 99 batterynecessary, 99 Boot loader, 297 Reading, 297 Writing, 297 Bus connector, 67 MPI, 72 setting the terminating resistor, 69

С

CE marking, 327 Commissioning Download project to CF card, 163 Individual steps, 139 Load into file system, 163 Requirements, 135 Compact Flash card Changing, 295 CompactFlash card

Content, 92 Formatting, 297 Writing to, 296 CompactFlash Card inserting, 84 Properties, 83 Conditions of use, 26 Configuration Global measuring inputs D4x5, 323 Local measuring inputs D4x5, 323 Measuring inputs on the D4x5, 323 Control Unit mounting D445-1 next to Line Module, 35 On the side of the Line Module, 34 On the wall of the control cabinet, 35 With spacers, 36 Without spacers, 37 Controller optimization, 242 Automatic position controller setting, 240 Automatic speed controller setting, 239 Function generator, 242 Measuring functions, 242 Trace, 242 cULus Approval, 327 CX32 LEDs during booting, 308 CX32 configuration Online configuration, 183 Overview, 174 Requirement, 176 topology, 179 Cycle clock scaling external/internal PROFIBUS, 119

D

D4x5 Installing, 31 Removal and installation, 268 Replacing, 263 Upgrading, 263 Data Deleting, 249 Data storage Diagnostic data, 314 Data transmission rate Aligning, 122 Declaration of conformity, 328 Designs, 31 Diagnostic buffer entries, 96 **Diagnostic data** Back up, 310, 318 Backing up during operation, 311 Backing up during startup, 312 Backing up via IT DIAG, 318 Data storage, 314 Diagnostics 7-segment display of the D4x5, 304 **IT DIAG, 321** LED displays, 300 SIMOTION Task Profiler, 320 Via HTML, 315 Digital input/digital output Connecting cables, 62 Wiring, 62 Distributed I/O systems, 18 DMC20/DME20 Creating, 236 Properties, 235 DP cycle, 118 PROFINET, 132 Drive optimization, 242 Drive wizard Calling, 143 DRIVE-CLiQ Advantages, 20 Components, 20 Connectable components, 56 Rules for wiring, 54

Ε

Electromagnetic compatibility, 328 EMC guidelines, 51, 327 EMERGENCY OFF concept, 51 EN 60950, 327 EN 61131, 327 Equipment open, 31 Equipotential bonding, 49 ESD guideline, 331 Ethernet Configuring addresses, 127 Interfaces, 126 Properties, 125

F

Fan/battery module, 100

D425/D435, 101 D445/D445-1, 101 Fan control, 100 Fan faults, 101 Max. permissible supply air temperature, 100 Firmware Updating automatically, 293 Updating manually, 294 Upgrading, 285 Firmware downgrade, 294 Firmware update **IT DIAG, 286** Perform, 285 Front cover Opening, 50 FW update Perform, 285

G

Global measuring inputs D4x5, 323 Guideline ESD, 331

Η

Hardware Configuring, 172

I

I/O systems PROFIBUS, 18 PROFINET, 19 Released, 21 Installation CBE30, 39 CX32, 40 D4x5, 31 TB30, 38 Integrated drive Downloading a configuration, 172 SINAMICS S120, 142 Interface X122/X132, 62 IT DIAG Diagnostics, 321 FW update, 286

L

LED display CBE30 PROFINET, 306 CX32, 309 D4x5 backup of non-volatile data, 304 PROFIBUS DP, 301 **PROFINET** interface, 301 SINAMICS Integrated with D4x5, 301 Upgrading the D4x5, 303 License Back up, 291 Protection against deletion, 252 Undervoltage indicator, 301 Load Into file system, 163 Project, 161 To the target system, 294 Local measuring inputs D4x5, 323 Local measuring inputs on the D4x5 Parameter, 325

Μ

Maintenance Overview, 263 Measuring input D4x5 overview, 230 Global for D4x5, 230 Measuring inputs on the D4x5 Local/global measuring inputs, 323 Mechanical rated conditions, 27 Memory model, 88 Memory reset, 249 via SIMOTION SCOUT, 250 with mode selector, 251 Module Transport and storage conditions, 25 MPI bus Bus connector, 72 Connection rules, 72 interface, 124 Parameters, 124 MPI interface, 117

Ν

Non-volatile data Back up, 94, 318 Backing up, 311 Backing up via IT DIAG, 318 Diagnostics, 96

SIMOTION D4x5 Commissioning and Hardware Installation Manual, 11/2010 Power-up, 96 Reloading, 95 Restoring, 317 Saving to CompactFlash card, 91

0

Offline configuration Overview, 141 Procedure, 142 Requirement, 141 Onboard I/Os of the D4x5 Configuration overview, 227 Overview, 226 Online configuration Procedure, 166 Requirement, 166 Output cam Configuration for D4x5, 233 Overview Diagnostic data, 310 Upgrading and downgrading, 285 Overview of connections, 48

Ρ

PG/PC connection enabling the active setting, 123 via Ethernet, 112 via PROFIBUS, 110 Power failure, 95 Power supply connecting, 53 Rules for the line voltage, 52 Safety regulations, 51 Switching on, 85 VDE guideline, 52 Power-up Control unit, 85 PROFIBUS address, 117 **PROFIBUS** cable Baud rate, 67 Cable length, 67 connecting, 68 Properties, 67 removing, 69 Rules for cabling, 68 PROFIBUS DP Creating a new subnet, Data transmission rate, Definitions, 114

DP cycle. Interfaces. PROFINET Cable types, 75 Cabling, 73 Diagnostics via LED displays, 299 DP cycle, 132 IO controller, 133 IO device, 133 Properties, 133 Project archiving on CF card, 165 creating, 107 Load, 294 Project update IT DIAG, 286 Protection against external electrical phenomena, 53

R

References, 4 Reliability **Risk**, 329 Replace module DRIVE-CLiQ type, 269 Residual risk, 330 Restoring Non-volatile data, 317 Restoring the default settings SINAMICS Integrated, 253 Restoring the factory settings SIMOTION D4x5, 253 Retain data Back up, 273 Backing up, 311 Retain data and user data Back up, 291

S

Safety information, 24 Safety of electronic controllers, 329 Service Overview, 263 Service selector switch Switch position 1, 318 Shield connection Using, 63 SIMOTION D4x5 Hardware components, 15 Installation,

Possible applications, 14 Software components, 16 System overview, 13 User memory concept, 88 Variants, 14 SIMOTION SCOUT Documentation, 23 engineering, 203 Installing, 107 SIMOTION Task Profiler, 320 SINAMICS Integrated Restoring the factory settings, 253 Speed controller Adjusting the P-Gain, 246 Optimum, 243 Starting the measuring function, 244 Standard IE cable types, 74 Starter, 23 Subnet Connection components, 66 Connection rules, 70 Segment, 66 Terminating resistor, 66 Switching on Requirement, 83 System Powering down, 254 System components, 17 System cycle clock, 118 Bus cycle clock, 118 DP cycle, 132 IPO cycle clock, 118, 132 Ratios of system cycle clocks, 118 Servo cycle clock, 118 System function _savePersistentMemoryData, 95 System variable batteryexisting, 99 batterynecessary, 99

Т

Task Profiler, 320 Terminating resistor, 66 Testing the drive, 200 TM41 Programming, 238 TM41 terminal module, 236 Configuring, 237 Totally Integrated Automation, 13

U

UL certification, 327 Unit data Back up, 273 User data Deleting, 252 Load, 248 User memory concept, 88 Backup time, 90 Fan/battery module, 90 Non-volatile data, 89 Volatile data, 91

۷

Variables Back up, 273 Vibrations Reduction, 27 Volatile data, 91 Index