

General conditions and function limitations, notes for configuration and operation

These notes take precedence over statements contained in other documents.

Because these notes contain important information for the installation and use of the software, please read them carefully.

SINAMICS S120 / S150 Software V2.6 SP2 inkl. SSP for STARTER

ARTSPUsRQ	Brief description	Circumstances	Possible work-around	Affected DO	Since version
SINAMICS_SW - General					
AP00316750	Changing the motor in the expert list	Another motor may only be selected via the drive wizard. Changing the motor code in the expert list can result in inconsistencies in the STARTER displays.	---		2.6 SP1
AP00325763	The information for rated current and rated power of the PM340 power module in the drive wizard can deviate from the catalog data in some cases.	The information for rated current and rated power of the PM340 power module in the drive wizard can deviate from the catalog data in some cases.	Select the power module by MLFB when using the drive wizard for commissioning		2.5 SP1
AP00325989	In the range of speeds greater than 3 times the rated speed (field weakening), the regenerative power is up to 30% too high.	In the range of speeds greater than 3 times the rated speed (field weakening), the regenerative power is up to 30% too high.	None	Vector	2.5 SP1
AP00330263	The information for the power unit duty cycles in indices 1 to 4 of parameters r0206, r0207 und r0209 in the expert list are not displayed correctly in some cases. The value in index 0 is applicable.	The information for the power unit duty cycles in indices 1 to 4 of parameters r0206, r0207 und r0209 in the expert list are not displayed correctly in some cases. The value in index 0 is applicable.	none		2.5 SP1
AP00394976	When a PM340 power module is inserted onto another CU305, the runtime meter of the power unit fan is reset to 0.	When a PM340 power module is inserted onto another CU305, the runtime meter of the power unit fan is reset to 0.	None		2.5 SP1
AP00485173	As of V2.5 SP1, the maximum number of nodes on a DRIVE-CLiQ line is limited to14 because of the increased data traffic.	As of V2.5 SP1, the maximum number of nodes on a DRIVE-CLiQ line is limited to14 because of the increased data traffic.	Distribute the components on different lines.	All	2.5 SP1
AP00490745	The number of permissible places after the decimal point is not taken into account for scripting.	With scripts, it is possible to write a parameter with more places after the decimal point than permitted or displayed in the screens. This can result in an inconsistency between the actual value set in the drive and the display in STARTER. These differences cannot be displayed through a comparison of lists.	Take the number of permissible places after the decimal point into account in the script. See expert list.		2.6 SP1
AP00708518	The Terminal Modules TM31, TM41, TM15 and TM17 are only taken into account in the message CU_ZSW1 Bit 6 "Device ready to start" (e.g. standard message frame 370) when the BICO connections are available to the Terminal Module as source and a servo or vector drive object as sink.	The Terminal Modules TM31, TM41, TM15 and TM17 are only taken into account in the message CU_ZSW1 Bit 6 "Device ready to start" (e.g. standard message frame 370) when the BICO connections are available to the Terminal Module as source and a servo or vector drive object as sink.	None		2.6 SP1
AP00810382	Sporadic error F3x129 after acknowledgement of F3x100 for SMI20.	After occurrence of error F3x100 "Encoder x: Faulty zero mark spacing", its acknowledgement and subsequent encoder deactivation/activation, sporadically with sensor module SMI20 error message F3x129 "Encoder x: Position difference Hall sensor / track C/D and track A/B too large" can occur. Error F3x129 can be acknowledged.	None.		2.6 SP2
AP00814475	With fault F03505 (TM: Analog input wire breakage) for analog input 0, leading zeros are not displayed in the fault value. The 0 for analog input 0 is not displayed at the thousands position.	With fault F03505 (TM: Analog input wire breakage) for analog input 0, leading zeros are not displayed in the fault value. The 0 for analog input 0 is not displayed at the thousands position.	None		2.6 SP2
AP00821619	Parameter r4074 "Current TM31 analog outputs output voltage/current" displays voltages up to approx. +/- 11.4 V. However, for modules with the order number 6SL3055-0AA00-3AA1 only voltages up to approx. +/- 10.8 V are output at the terminals.	Parameter r4074 "Current TM31 analog outputs output voltage/current" displays voltages up to approx. +/- 11.4 V. However, for modules with the order number 6SL3055-0AA00-3AA1 only voltages up to approx. +/- 10.8 V are output at the terminals.	None.		2.6 SP2

ARTSPlusRQ	Brief description	Circumstances	Possible work-around	Affected DO	Since version
SINAMICS_SW - General					
AP00825815	Encoders with high capacitance in the power supply circuit (e.g. YRTSM integrated angular measuring system from INA) result in failure of the DRIVE-CLiQ communication on the SME20 with MLFB 6SL3055-0AA00-5EA3 and on the SME25 with MLFB 6SL3055-0AA00-5HA3.	Encoders with high capacitance in the power supply circuit (e.g. YRTSM integrated angular measuring system from INA) result in failure of the DRIVE-CLiQ communication on the SME20 with MLFB 6SL3055-0AA00-5EA3 and on the SME25 with MLFB 6SL3055-0AA00-5HA3.	Use the SMC20.		2.6 SP2
AP00827130	With BICO connections, frequency signals are normalized with the reference speed. This results in the signals being shown to large in the percentage display by the factor of the number of motor pole pairs.	If the frequencies r0065 and r0066 are converted to percentages via BICO connection (e.g. for PROFIBUS, to the technology controller, to analog outputs), referencing is to the value p2000 / 60. This results in a display value of 200% for a 4-pole motor at a rated speed of 1500 rpm. The display value continues to increase with the number of motor pole pairs.	None.		2.6 SP2
AP00850399	With simultaneous activation of several SMCs via p0145, alarm 31885 "Encoder 1 DRIVE-CLiQ (CU): Cyclic data transfer faulted" can be output.	With simultaneous activation of several SMCs that are assigned to different drive objects via p0145, alarm 31885 "Encoder 1 DRIVE-CLiQ (CU): Cyclic data transfer faulted" can be output.	Acknowledge the alarm or wait at least five seconds between the activation operations.	Servo/Vector	2.6 SP2
SINAMICS_SW - Axis control panel					
AP00821489	When using the sector-specific message frame p0922 = 220, the speed controller enable STW2 bit 9 must be specified by the controller to traverse the drive with the axis control panel.	When using the sector-specific message frame p0922 = 220, the speed controller enable STW2 bit 9 must be specified by the controller to traverse the drive with the axis control panel. This behavior occurs when p0856 "BI: Enable speed controller" is wired (as is the case per definition of message frame 220). In this case, traversing with the control panel requires that the interconnected signal is set to 1.	The speed controller enable STW2 bit 9 must be specified by the controller to traverse the drive with the axis control panel. Alternatively, p856 can also be rewired, temporarily set to 1 for control panel operation.		2.6 SP2
SINAMICS_SW - Drive wizard					
AP00806539	A pulse frequency p1800 that is too large is not corrected to a smaller value after a download	After download of a project with small motor and large motor module, parameter p1800 "Pulse frequency setpoint" is set to a higher value and the error message F07085 "Drive: Parameter of the open/closed-loop control changed" is output with fault value 1800. After an upload, selection of a larger motor and renewed download, p1800 is not reduced again to the original value.	When selecting a larger motor, check and, if required, correct p1800.		2.6 SP2
SINAMICS_SW - Drive integration					
AP00563888	SINAMICS and safety data block: Parameterization problems while transferring parameter r9733	Because of the number of data words available for the transfer of the process data (PZD) between TO and drive (maximum 19), parameterization problems occur with some standard message frames, e.g. message frame 106, while transferring parameter r9733 (effective absolute velocity setpoint limitation in the drive) as a PZD is no longer available in doubleword format. Configuration of safety data block for drive object type SERVO: In order to be able to respond to the pending safety function from the user program of the SIMOTION, a safety data block must be created in the drive message frame between TO and drive. Whereby parameter 9733 (effective absolute velocity setpoint limitation in the drive) also has to be interconnected to a PZD in doubleword format in the actual value message frame of the drive (p2061 index 0 to 14). This is not possible for the following message frame types for the drive object type SERVO: Standard message frame 4 with/without technology data block, standard message frame 6 with/without technology data block, Siemens message frame 103 with/without technology data block, Siemens message frame 106 with/without technology data block	In this case, parameter r9733 must be interconnected to a PZD in word format (p2051 index 15-18). Also note that the immediately following PZD may not be interconnected in word format. Example: Standard message frame 106 without technology data block is used. This occupies PZDs 1-15 in the actual value message frame. The safety data block must be wired/interconnected to PZD 16 and consequently parameter r9733 to PZD 17. As an interconnection of r9733 to the PZD in doubleword format in p2061 index 16 is not possible, the parameter must be interconnected to p2051 index 16 as a substitute. In this case, PZD 18 (p2051 index 17) must be interconnected to the value 0%.		2.6 SP1
AP00789975	Alarm A01316 "Drive object inactive and again ready for operation"	After deactivation and disconnection of a drive, alarm A01316 "Drive object inactive and again ready for operation" may be output by mistake.	Ignore the alarm.		2.6 SP2
SINAMICS_SW - D4x5					
AP00326023	Digital and analog outputs at (CU, TB, TM)	SINAMICS resets for CLEAR on the PROFIBUS - only those digital and analog outputs (CU, TB, TM) that are supplied with their own PZD channel. - digital and analog outputs that receive their process data indirectly with BICO wiring using a drive or the incoming supply will not be reset to 0.	--		2.6 SP2
SINAMICS_SW - Data set changeover					
AP00820712	Parameter r0835 "CO/BO: Motor data set changeover status word" does not provide any information.	Parameter r0835 "CO/BO: Motor data set changeover status word" does not provide any information.	None		2.6 SP2
AP00842400	If during the commissioning of the vector control with the STARTER commissioning wizard, a second drive data set is created directly at the first commissioning, the selected motor data identification cannot be started after the subsequent parameter download.	If several drive data sets are created for a vector control and the motor data identification is selected simultaneously (p1910>0), it cannot be started after the subsequent parameter download. r0046 bit 19 displays an internal pulse disable.	Do not select the motor data identification online in the drive until after the parameter download.		2.6 SP2

ARTSPlusRQ	Brief description	Circumstances	Possible work-around	Affected DO	Since version
SINAMICS_SW - DRIVE-CLiQ					
AP00823581	If without previous deactivation, an SMI or SMC is unplugged on an axis and plugged in again, occasionally drive failures can occur on other axes to which the SMI or SMC is not assigned.	If without previous deactivation, an SMI or SMC is unplugged on an axis and plugged in again, occasionally drive failures can occur on other axes to which the SMI or SMC is not assigned.	When unplugging and plugging in an SMI or SMC, do not traverse an axis or deactivate the relevant component first.		2.6 SP2
SINAMICS_SW - EPOS					
AP00820472	For travel to fixed stop with step enabling condition CONTINUE_EXTERNAL_WAIT or following block WAIT, a reference point cannot be set via p2596.	For travel to fixed stop with step enabling condition CONTINUE_EXTERNAL_WAIT or following block WAIT, a reference point cannot be set via p2596.	Terminate motion command FIXED STOP with step enabling condition END. Set the reference point in the fixed stop and continue the motion command with the next traversing block.		2.6 SP2
SINAMICS_SW - Encoder					
AP00713994	Encoder errors are not cleared by acknowledging the TO "external encoder".	If a second encoder is attached to a drive and this encoder is controlled via a TO "external encoder", encoder errors are not cleared by acknowledging the TO "external encoder".	An error on the second encoder must be acknowledged "on" the drive.		2.6 SP2
SINAMICS_SW - Upgrade					
AP00847430	Alarm A01251 "CU: CU EEPROM read-write data faulty" with alarm value 1800 or 1795 after upgrade	after upgrading the SINAMICS software, alarm A01251 "CU: CU EEPROM read-write data faulty" with alarm value 1800 or 1795 can occur.	- Delete the error memory at the drive object with this alarm (p0952 = 0). - Alternatively delete the error memories of all drive objects (p2147 = 1) / not permitted on a CX32. - Alternatively replace the control unit.		2.6 SP2
SINAMICS_SW - PROFIBUS communication					
AP00334540	Diagnostics display for message frame 110 incomplete.	PZD MDI_vel and MDI_decc are missing in the diagnostics display for PROFIBUS message frame 110.	---		2.6 SP1
AP00535834	Software error for data exchange broadcast and isochronous PROFIBUS and dynamically faulted bus connection.	An internal software error (F1000) can occur when configuring data exchange broadcast and isochronous PROFIBUS, if the bus connection is dynamically (very fast/frequently, e.g. through a loose connection) interrupted and then established again.	Power Off / Power On.		2.6 SP1
AP00602836	Configuration frame error (A1900(50)) if further outputs from the master are configured on a DO after the data exchange broadcast data.	A configuration of PROFIBUS data exchange broadcast data followed by further master outputs on the same DO is not evaluated correctly. A syntax error in the configuration frame (A1950(50)) is signaled.	Configure data exchange broadcast data after all master outputs of the respective DO.		2.6 SP1
AP00602869	Crash after data exchange broadcast configuration with odd I/O address.	If a PROFIBUS data exchange broadcast configuration with odd I/O address is configured and loaded, the CU320 crashes as soon as the controller goes into "RUN" mode.	Do not configure any odd I/O addresses in the data exchange broadcast configuration.		2.6 SP1
AP00706496	Syntax error in the configuration frame (A1900(50)) when not only PROFIsafe, but also data exchange broadcast is configured.	A configuration of both PROFIsafe and data exchange broadcast is not evaluated correctly. A syntax error in the configuration frame (A1950(50)) is signaled.	Do not configure PROFIsafe and data exchange broadcast together.		2.6 SP1
SINAMICS_SW - PROFINET communication					
AP00670850	When loading a project with IP address offline to the CF card using the menu "Edit / Load to file system", the IP address is not transferred.	When loading a project with IP address offline to the CF card using the menu "Edit / Load to file system", the IP address is not transferred.	After the "Load to file system", edit the IP address online via the Ethernet node function (node designation).		2.6 SP1
AP00687479	SINAMICS CBE20 does not support PROFIsafe diagnostics.	SINAMICS CBE20 does not support PROFIsafe diagnostics.	None		2.6 SP1
AP00702785	The monitoring time for setpoints via PROFINET (p8840) has no effect after unplugging or switching the controller from RUN to STOP. F08501 is signaled immediately in these cases.	The monitoring time for setpoints via PROFINET (p8840) has no effect after unplugging or switching the controller from RUN to STOP. The delay of F08501 therefore works correctly when the communication fails because of faults on the PROFINET line.	F08501 can be acknowledged.		2.6 SP1
AP00724260	If the user directory is deleted on the CF card of a CU320 control unit, then the IP address of the CBE20 is lost.	The PROFINET addressing (IP address, name of station) is saved in SINAMICS parameters and consequently in the user directory on the CF card. If these files are deleted, the PROFINET addressing is also lost.	1. Do not delete the user directory during the software upgrade or make a back-up and then reload it, or 2. Perform an initial designation of the node again.	Servo/Vector	2.6 SP1
AP00843862	Alarm value 23 is not written for alarm A8511.	Alarm value 23 is not written for alarm A8511.	Missing description: "23: Illegal isochronous mode for PZD interface 2."	Servo/Vector	2.6 SP2
SINAMICS_SW - Closed-loop control					
AP00325983	Highly dynamic acceleration/deceleration operations at the converter current limit can cause an overcurrent error in the field weakening range.	Highly dynamic acceleration/deceleration operations at the converter current limit can cause an overcurrent error in the field weakening range.	none	Vector	2.5 SP1
AP00325986	In the range of speeds greater than 3 times the rated speed (field weakening), the motor power is up to 10% too high.	In the range of speeds greater than 3 times the rated speed (field weakening), the motor power is up to 10% too high.	See Circumstances	Vector	2.5 SP1

ARTSPlusRQ	Brief description	Circumstances	Possible work-around	Affected DO	Since version
SINAMICS_SW - Closed-loop control					
AP00326281	Power errors greater than 10% can occur in the field weakening range for IFE spindles.	Power errors greater than 10% can occur in the field weakening range for IFE spindles.	Perform motor data identification and activate kt estimator (additional CU processor performance).	Servo	2.5 SP1
AP00516843	When parameterizing a gearbox in p0432/p0433, this is not included in the position calculation.	If a gearbox is parameterized in p0432/p0433, this is only included in the speed, but not the position calculation.	A recalculation of the position can be achieved by activating the position tracking in p0411.0.		2.6 SP1
AP00522164	When using synchronous motors with incremental encoders with zero mark, but without absolute position (without C/D track), the "Commutation with zero mark" (fine synchronization) p404.15 is not automatically activated.	When using synchronous motors with incremental encoders with zero mark, but without absolute position (without C/D track), the "Commutation with zero mark" (fine synchronization) p404.15 is not automatically activated.	When using synchronous motors with incremental encoders with zero mark, but without absolute position (without C/D track), not only the coarse synchronization (pole position identification or Hall sensors) must be deselected, but also the fine synchronization with zero marks selected, as this is not performed automatically. Both settings must be made via the encoder data screen of the commissioning wizard at "Enter data, encoder data".		2.6 SP1
AP00817528	For devices without regenerative feedback and without braking chopper with servo control, the DC link voltage can rise up to the shutdown threshold for the DC brake.	For devices without regenerative feedback and without braking chopper with servo control, the DC link voltage can rise up to the shutdown threshold for the DC brake.	As a remedy, the current controller proportional gain can be halved and the integral time doubled. If this is detrimental for the operation, it can be performed later when activating the DC brake with the aid of the DDS changeover. Note that with active DC brake, the DDS changeover is locked. The changeover must therefore be performed a short time before, e.g. by linking the DC brake request with a pulse delay block PDE (from the free function blocks) and the data set changeover and activating the DC brake with output of the pulse delay (e.g. after 8 ms). Proceed as follows: 1. Activate the free function blocks as function module. This is done by right-clicking the drive offline in STARTER, selecting Properties and then the Function modules tab. "Free function blocks" can be activated here. This must then be downloaded and then has free function blocks as of p20000. There is a pulse delay block PDE here with adjustable delay time. 2. The activation of the DC brake which was previously connected to p1230 is now disconnected and instead connected to the data set changeover (e.g. p820) and the input of the PDE (p20158). The output of the PDE (p20160) now becomes the source for p1230 (DC brake). The time must now be set for the delay. 8 ms should be sufficient (p20159) and this block must be assigned to a time slice. To do this, an execution group is selected in p20161, e.g. 0 and in p20000[0] = sampling time 16*p20002 (the index is the execution group). Do not forget to halve p1715 of the second data set and to double p1717, otherwise the data of both data sets is identical.		2.6 SP2
AP00834139	During operation of the permanent-magnet-excited synchronous machine, the limit of the available motor q-axis current (torque-generating) in the overload range is reached too early.	The available motor q-axis current (torque-generating) is not sufficient for loads greater than the rated motor torque (see display r1548). This can result in the drive not being able to supply the required torque in the overload range and, depending on the application, the motor speed dropping.	Reduction of parameter p356 (stator quadrature-axis reactance) by a factor. Suggested value: 75% of the original value.		2.6 SP2
AP00840616	The drive is not found during a flying restart with V/f control. After searching, start-up is with frequency zero.	For motors that have a maximum speed p1082 more than four times greater than the rated speed p0311, the motor is not found during a flying restart with V/f characteristic. Overcurrent switch offs can occur during the subsequent start-up from standstill.	The search rate of the flying restart with V/f characteristic can be halved with p1203 = 200 percent. It is also possible to reduce the maximum speed (p1082).		2.6 SP2
AP00843055	In infeeds, the temperature input X21 (booksize) or X41 (chassis) cannot be freely used for temperature measurements, but is only activated to monitor line filter temperatures.	In infeeds, the temperature input X21 (booksize) or X41 (chassis) cannot be freely used for temperature measurements, but is only activated to monitor line filter temperatures. Note: A free parameterization of the temperature input according to the description in p0601 (A_INF, S_INF, B_INF) is not possible as after a power down, p0601 is assigned the value 0 of the factory setting again.	None.		2.6 SP2

ARTSPlusRQ	Brief description	Circumstances	Possible work-around	Affected DO	Since version
SINAMICS_SW - Closed-loop control					
AP00846965	If a combination of motor module and ALM are operated on a CU with CU SW version V2.4 and power unit SW version V2.6 (on DAC hardware), error messages (overcurrent, ground fault) can occur when switching on.	If a combination of motor module and ALM are operated on a CU with CU SW version V2.4 and power unit SW version V2.6 (on DAC hardware), error messages (overcurrent, ground fault) can occur when switching on. Operation is not possible.	- Use SW version V2.6 not only for the components, but also for the CU. - Upgrade to SW version V2.5 or V2.6 for all components. - If spare parts are required, use the same components as were originally installed. - Relocate the ALM to a separate CU.		2.6 SP2
AP00847734	When switching on with quick magnetization, it may occur that the motor does not start and error F7411 "Drive: Flux setpoint not reached during excitation" is displayed.	When switching on with quick magnetization, it may occur that the motor does not start and error F7411 "Drive: Flux setpoint not reached during excitation" is displayed. In addition to the known causes listed in the description of F7411, it may be that the actual flux value does not reach the setpoint because of inexact motor parameters (rated magnetization current, main inductance, saturation characteristic).	This error cause can be avoided when not only the motor data identification is performed, but also the rotating measurement.	Vector	2.6 SP2
AP00852190	If the DC brake is switched on and off again, the drive starts up, but the associated status bit r0899 bit 2 "Enable operation" is no longer set to 1.	If the DC brake is switched on and off again, the drive starts up, but the associated status bit r0899 bit 2 "Enable operation" is no longer set to 1.	No remedy possible.	Vector	2.6 SP2
SINAMICS_SW - Safety Integrated					
AP00479461	The Safety Integrated Extended Functions are not possible with a current and speed controller cycle clock of 62.5 µs.	The Safety Integrated Extended Functions are not possible with a current and speed controller cycle clock of 62.5 µs. Fault F01340 "Topology: Too many components on a line" is output.	Set current and speed controller cycle clock to greater or equal to 125 µs.	Servo	2.5 SP1
AP00719209	In a worst case situation, the total response time is increased by approx. 30 ms compared to V2.5 SP1 when the Safety Integrated extended functions are selected via PROFIsafe.	In a worst case situation, the total response time is increased by approx. 30 ms compared to V2.5 SP1 when the Safety Integrated extended functions are selected via PROFIsafe. This can result in increased overtravel. During the acceptance test of series machines that were previously operated with V2.5 SP1 and are now used with V2.6 SP1, a check must be made whether this is relevant for the safety in the respective application.	If the longer response time is critical, it can be reduced by setting a shorter monitoring cycle for the Safety Integrated extended functions (p9500/p9300) in the drive unit.		2.6 SP1
AP00721741	Fault F01652 for current control cycle clocks greater than 250 µs and Safety Integrated extended functions with default actual value update cycle.	For current control cycle clocks p0115[0] greater than 250 µs, Safety Integrated extended functions default actual value update cycle p9511 = 0 and isochronous PROFIBUS, the fault F01652 "SI CU: Illegal monitoring cycle clock" occurs with fault value 105, even when the PROFIBUS cycle clock is set to greater than or equal to four times the current control cycle clock. Current control cycle clocks greater than 250 µs occur in particular in applications with more than two vector axes.	Set a separate actual value acquisition cycle clock in p9511 (e.g. the same as the PROFIBUS cycle clock).		2.6 SP1
AP00808654	When using a double motor module and the Safety Integrated extended functions with the following configuration - p9511 on one drive of the double motor module = 1 ms - p9511 on the other drive of the double motor module = 0 ms (= take over DP cycle) - isochronous PROFIBUS with PROFIBUS cycle not equal to 1 ms error messages are output.	When using a double motor module and the Safety Integrated extended functions with the following configuration - p9511 on one drive of the double motor module = 1 ms - p9511 on the other drive of the double motor module = 0 ms (= take over DP cycle) - isochronous PROFIBUS with PROFIBUS cycle not equal to 1 ms the error messages C01711 "SI Motion CU: Defect in a monitoring channel" with fault value 1020 and C30711 "SI Motion MM: Defect in a monitoring channel" with fault value 1020 are output.	On the drive with p9511 = 0 ms, set PROFIBUS cycle instead of 0 ms.		2.6 SP2
AP00822802	After replacement of a rotary encoder by a linear position encoder, with activated safe motion monitoring functions, the error message F01671 "SI Motion: Parameterization of encoder faulty" with fault value 9518 occurs. This occurs, for example, when changing from a rotary encoder to a linear position encoder.	After replacement of a rotary encoder by a linear position encoder, with activated safe motion monitoring functions, the error message F01671 "SI Motion: Parameterization of encoder faulty" with fault value 9518.	1.) Deactivate the safe motion monitoring functions in the relevant drive and then perform a power off or warm restart. This reassigns the safety encoder parameters. Then reactivate the safe motion monitoring functions. This is generally the commissioning recommendation in order to avoid a manual parameterization of the safety encoder parameters. 2.) Correct the differences in the safety parameters (p95xx) displayed in error F01671.		2.6 SP2

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SINAMICS_SW - Safety Integrated					
AP00828893	When activating the Safety Integrated basic functions via PROFIsafe with non-isochronous PROFIBUS or PROFINET RT, error messages can occur sporadically after powering up.	When activating the Safety Integrated basic functions via PROFIsafe with non-isochronous PROFIBUS or PROFINET RT, the following error messages can occur sporadically after powering up: F01611 "SI CU: Defect in a monitoring channel" with fault value 6165, F01600 "SI CU: STOP A triggered" with fault value 9999, F30611 "SI MM: Defect in a monitoring channel" with fault value 6165 and F30600 "SI MM: STOP A triggered" with fault value 9999. The errors can be acknowledged via "safe acknowledgement". An error can occur in conjunction with PROFIsafe after Power off/on, when the addresses of the PROFIsafe data in the F-host are in an area that is subject to the process image update. The error can be acknowledged via "safe acknowledgement". With F-hosts, in which the process image update can be deactivated (e.g. S7-400), the address area for the PROFIsafe output data should be removed from the process image update.	1.) Select isochronous mode or 2.) With F-hosts, in which the process image update can be deactivated (e.g. S7-400), the address area for the PROFIsafe output data should be removed from the process image update.		2.6 SP2
AP00836947	A project download with parameterized PROFIsafe or dbsi0 via PROFIsafe fails when the correct SW version is not available in the motor module.	A project download with parameterized PROFIsafe (P9601.3 = 1) is aborted with error message "P9601[0]: Invalid value" when the SW versions in the control unit and motor module differ in the following way: Control unit has version V2.6, but the motor module still has version V2.5 or vice versa. The error "9601[0]: Invalid value" occurs under the specified conditions when the project is written directly to the CF card via "Load to file system".	Wait for automatic upload of the motor module, then power off/on and download the project again.		2.6 SP2
AP00841250	If the DRIVE-CLiQ connection between a TM54F and the CU320 is separated, the errors C01711 "SI Motion CU: Defect in a monitoring channel" (fault value 1012) and C30711 "SI Motion MM: Defect in a monitoring channel" (fault value 0) cannot be acknowledged.	If the DRIVE-CLiQ connection between a TM54F and the CU320 is separated, the errors C01711 "SI Motion CU: Defect in a monitoring channel" (fault value 1012) and C30711 "SI Motion MM: Defect in a monitoring channel" (fault value 0) cannot be acknowledged.	Switch 24 V supply off/on.		2.6 SP2
AP00843247	With Safety Integrated extended functions, occasionally the error messages C1700/C30700 fault value 0 and C1711/30711 fault value 1020 can occur for the sampling times, current controller cycle 0.250 ms and actual value acquisition cycle 1 ms.	With Safety Integrated extended functions, occasionally the following error messages can occur for the sampling times, current controller cycle 0.250 ms and actual value acquisition cycle 1 ms: C01700 SI Motion CU: STOP A triggered (fault value 0) C30700 SI Motion MM: STOP A triggered (fault value 0) C01711 SI Motion CU: Defect in a monitoring channel (fault value 1020) C30711 SI Motion MM: Defect in a monitoring channel (fault value 1020)	Increase actual value acquisition cycle (p9511/p9311) to 2 ms.		2.6 SP2
AP00850727	Alarm acknowledgement of safety alarms of the drive-based safety functions	Contrary to the description in the documentation and online help, alarms C1700, C1701, C1706, C1707 and C30700, C30701, C30706, C30707 can be acknowledged via terminal module 54F (TM54F) or PROFIsafe.		Servo/Vector	2.6 SP2
AP00853259	For projects with safety extended functions, TM54F and connection of the motor module via CUA31, safety error messages occur that cannot be acknowledged when a drive object is deactivated/activated and copy RAM to ROM is performed.	For projects with safety extended functions, TM54F and connection of the motor module via CUA31, safety error messages C30700 "SI Motion MM: STOP A triggered" and C30711 "SI Motion MM: Defect in a monitoring channel" occur that cannot be acknowledged after the following sequence of actions: 1. Deactivation of the drive object belonging to CUA31 via p105 = 0 2. Unplugging of the DRIVE-CLiQ cable at X200 of the CUA31 3. Copying of RAM to ROM 4. Switching off drive line-up 5. Plugging in of the DRIVE-CLiQ cable at X200 of the CUA31 6. Switching on drive line-up 7. Activation of the drive object belonging to CUA31 after ramp-up via p105 = 1	After activation via p105 = 1, copy RAM to ROM and switch the drive line-off and on again.	Servo/Vector	2.6 SP2
SINAMICS_SW - SIMOTION					
AP00416605	No error message for "Copy RAM to ROM" when the files on the CF card are write-protected.	If the saved data of a project is copied from a CD to a CF card, the files are write-protected after the copy operation. If settings for the Sinamics Integrated are changed and copied from RAM to ROM, the data is not saved. An error message is also not output.	When copying files to the CF card from a CD or another data carrier on which the files are write-protected, the write protection must be removed on the CF card for all files.		2.6 SP1
SINAMICS_SW - Topology					
AP00366904	Simultaneous unplugging and plugging in of several deactivated components results in display of the error F31885 "Encoder 1 DRIVE-CLiQ (CU): Cyclic data transfer faulted".	If in the topology, several components are simultaneously deactivated, unplugged and plugged in again and then reactivated, then the error F31885 "Encoder 1 DRIVE-CLiQ (CU): Cyclic data transfer faulted" can be displayed. The error can be acknowledged.	None.		2.5 SP1

ARTSPPlusRQ	Brief description	Circumstances	Possible work-around	Affected DO	Since version
SINAMICS_SW - Topology					
AP00451744	Problems with the MotID occur when operating one or more vector axes with an infeed (ALM,BLM,SLM with DQ) on a DRIVE-CLiQ line if the sampling times of the vector axes p0115[0] are greater than the sampling time of the infeed p0115[0]. In particular, this cancels the LqLd pulse measurement of the MotID for the permanently excited synchronous machine (PESM) for vectors.	Problems with the MotID occur when operating one or more vector axes with an infeed (ALM,BLM,SLM with DQ) on a DRIVE-CLiQ line if the sampling times of the vector axes p0115[0] are greater than the sampling time of the infeed p0115[0]. In particular, this cancels the LqLd pulse measurement of the MotID for the permanently excited synchronous machine (PESM) for vectors.	Vector axes must be appended directly to the CU and not to the infeed in a separate DQ line.	Vector	2.5 SP1
AP00667805	Before deactivating or parking SMI/SMEs, pending errors must be acknowledged, otherwise with some SMI/SMEs the errors cannot be acknowledged.	Before deactivating or parking SMI/SMEs, pending errors must be acknowledged, otherwise with some SMI/SMEs the errors cannot be acknowledged.	Acknowledge errors before the deactivation or parking. Perform restart after activation or termination of parking.	Servo/Vector	2.6 SP1
AP00710801	The automatic configuration with BLM and SLM is not possible when at least one of the components is available several times.	The automatic configuration with BLM and SLM is not possible when at least one of the components is available several times.	Offline configuration with the aid of the STARTER wizard.		2.6 SP1
AP00715042	The TM54F must be operated alone on a separate DRIVE-CLiQ line for vector projects with current control cycle clock P0115[0] = 500 µs.	The TM54F must be operated alone on a separate DRIVE-CLiQ line for vector projects with current control cycle clock P0115[0] = 500 µs.	Set 250 µs in P0115[0] or attach TM54F to a separate line.		2.6 SP1
AP00794764	It is not possible to add a second SMI motor via p9910 to an already commissioned drive.	It is not possible to add a second SMI motor to a motor module via p9910. The SMI motor is added to the reference topology. However, the error messages F01042 "Parameterization error p131, index 1, cause 20" and F7515 "Power unit and motor connected incorrectly (1)" appear.	The drive to which the second SMI motor is to be added, is first removed completely (p9912) and then the motor module and the two SMI motors added to the reference topology with p9910.		2.6 SP2
AP00803017	Unplugging and plugging in again of a TM31 that is connected in series behind two TM17s does not function sporadically.	If a TM31 module that is on a DRIVE-CLiQ line with two upstream TM17 modules is unplugged and plugged in again, then sporadically the TM31 cannot be commissioned again.	There are three options: a) Only connect two TM modules in series on a line. b) Unplug and plug in again all TM modules directly on the port of the control unit to which they are connected. c) Switch the control unit off and on again if the unplugging and plugging in again of the third TM module from the line was not successful.		2.6 SP2
AP00821612	Errors while accessing the RAM data result in topology investigation errors	Sporadically access to the memory of the CU, which contains information about the connected DRIVE-CLiQ nodes, may return incorrect values, e.g. invalid special characters in the serial number (T ^o SN2044681 instead of T-SN2044681).	Unplug the relevant DRIVE-CLiQ line directly at the CU or switch the CU off and on again.		2.6 SP2
AP00831299	Occasionally error 1000 (internal software error) occurs with rapid unplugging and plugging in of a DRIVE-CLiQ connection.	Occasionally error 1000 (internal software error) occurs with rapid unplugging and plugging in of a DRIVE-CLiQ connection. The error can be corrected by switching the control unit on and off.	None		2.6 SP2
AP00842336	Unplugging and plugging in of a TM15 in the deactivated/reactivated results in communication faults.	If a TM15 module is deactivated via p105, unplugged from the DRIVE-CLiQ line and plugged in again, and then reactivated via p105, communication errors occur with the components.	Do not deactivate/activate components during unplugging or plugging in or perform power on.		2.6 SP2
AP00845558	If an encoder component is unplugged, sporadically the communication with all drive objects can be interrupted.	If an encoder component assigned to a drive object that is connected downstream of a terminal module, is unplugged, whereby the encoder component is connected to a different CU port than the power unit, then sporadically the communication with all drive objects can be interrupted	Switch the CU off and on again		2.6 SP2
DCBLib_SINAMICS_RT - DCC					
AP00785705	DCBLib SINAMICS: For the DCB SAV.. blocks, the output is VLD (output variable valid) after delta download without initialization of the retain data, as well as always 1 after a power on even when a value has not been previously written to the block by the user via input M (M=1).	DCBLib SINAMICS: For the DCB SAV.. blocks, the output is VLD (output variable valid) after delta download without initialization of the retain data, as well as always 1 after a power on even when a value has not been previously written to the block by the user via input M (M=1).	Write a valid value from your application to the SAV blocks.		2.6 SP2

ARTSPlusRQ	Brief description	Circumstances	Possible work-around	Affected DO	Since version
DCBLib_SINAMICS_RT - DCC					
AP00852776	When using the engineering versions SCOUT V4.1.4.1 or STARTER V4.1.3 + SSP SINAMICS 2.6.2, after the import of configurations/systems with S120 V2.6.1, those that have been created with "previous" engineering versions and contain DCCs, must be upgraded to a new DCB library at least in the OFFLINE project.	A project has been created with dcbliV2_0_sinamcis2.6[2.60.35.0] (i.e. for Sinamics V2.6.1 with "older" engineering versions). If this is now imported/used in SCOUT V4.1.4.1 (contains SSP SINAMICS 2.6.2) or STARTER V4.1.3 + SSP SINAMICS 2.6.2, an update (upgrade) of the DCB library to "dcbliV2_0_sinamcis2.6[2.60.52.0]" is required at least in the offline project, so that the project can be compiled consistently and an error-free download can be performed again to the target device.	Case A (original project with DCC units available, i.e. DCCs can be opened and edited): Open DCC chart: In the menu OPTIONS / Block types, import the DCB library (dcbliV2_0_sinamcis2.6[2.60.52.0]) and then compile the DCC chart. Case B (an upload has been performed with an "older" engineering version and without the original project being available; the DCC units are then not available and the DCC charts cannot be opened or changed): In the context menu for the DCC chart in the project navigator (right-click the selected DCC chart), call menu item "Block types" and import the DCB library (dcbliV2_0_sinamcis2.6[2.60.52.0]) ; then compile the DCC chart.		2.6 SP2
PNIO_MC - PROFINET communication					
AP00796791	In the commissioning interface screen of STARTER, an IP address assigned by the PROFINET controller (automatically) is not displayed updated, but the default IP address or the IP address stored in the device.	In the commissioning interface screen of STARTER, an IP address assigned by the PROFINET controller (automatically) is not displayed updated, but the default IP address or the IP address stored in the device.	The correct or currently active/valid IP address is always displayed via "Accessible nodes" in STARTER. Or the IP address assigned via STARTER. The correct IP address is then also displayed on the interface screen.		2.6 SP2
AP00819506	Direct attacks can result in the communication crashing in unprotected networks.	Direct attacks can result in the communication crashing in unprotected networks.	Generally, the automation network should be isolated from the public network and also the office network (firewall, etc.) in order to prevent attacks (scans, ICMP/ARP attacks, etc.) having an effect on the automation network.		2.6 SP2
AP00836285	Station names (NOS - name of station) longer than 120 bytes result in the following incorrect response: Name is not taken over correctly or the IP address is reset.	Station names (NOS - name of station) longer than 120 bytes result in the following incorrect response: Name is not taken over correctly or the IP address is reset.	Assign station names (NOS - name of station) with a maximum length of 120 bytes.		2.6 SP2