

SIEMENS

SIMOTION

SIMOTION D4x5

Commissioning and Hardware Installation Manual

Preface

Safety instructions

1

Description

2

Use planning

3

Installing

4

Connection

5

Commissioning (hardware)

6

Parameter assignment / addressing

7

Commissioning (software)

8

Service and maintenance

9

Diagnostics

10

Configuration of drive-related I/Os (without symbolic assignment)

A

Standards and approvals

B

ESD guidelines


C


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.

 DANGER
indicates that death or severe personal injury will result if proper precautions are not taken.

 WARNING
indicates that death or severe personal injury may result if proper precautions are not taken.

 CAUTION
indicates that minor personal injury can result if proper precautions are not taken.

NOTICE
indicates that property damage can result if proper precautions are not taken.


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

Qualified Personnel

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

Proper use of Siemens products

Note the following:

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

Trademarks

All names identified by ® are registered trademarks of 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.

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.

The software configuration is described in this manual based on SIMOTION SCOUT and SIMATIC STEP 7 Version V5.x.

The Engineering Framework Totally Integrated Automation Portal (SCOUT in the TIA Portal) only supports the newer SIMOTION D4xx-2 Control Units. Configuration of the SIMOTION D4xx Control Units in the TIA Portal is not possible.

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.
- **Installing**
Provides information on the various installation options for the device.
- **Connecting**
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.

- Service and maintenance
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 the SIMOTION Documentation Overview document.

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

The following documentation packages are available for SIMOTION V4.4:

- SIMOTION Engineering System Handling
- 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 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 it 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

Frequently Asked Questions can be found in SIMOTION Utilities & Applications, which are included in the scope of delivery of SIMOTION SCOUT, and in the Service&Support pages in **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 ISO 11469.
- 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 FAQ:

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

The following information sources are also available:

- 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-to-apply 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
- For additional documentation, see the *Overview of SIMOTION documentation* (separate document)

Table of contents

	Preface	3
1	Safety instructions	15
1.1	Fundamental safety instructions.....	15
1.1.1	General safety instructions.....	15
1.1.2	Safety instructions for electromagnetic fields (EMF).....	19
1.1.3	Handling electrostatic sensitive devices (ESD).....	19
1.1.4	Industrial security.....	20
1.1.5	Residual risks of power drive systems.....	20
1.2	Specific safety information for SIMOTION D4x5.....	22
2	Description	25
2.1	System overview.....	25
2.2	System components.....	29
2.3	I/O integration.....	33
2.4	Commissioning software.....	34
3	Use planning	37
3.1	Shipping and storage conditions.....	37
3.2	Mechanical and climatic ambient conditions.....	38
3.3	Specifications for Protection Class and Degree of Protection.....	41
4	Installing	43
4.1	Installation notes.....	43
4.2	Installing the SIMOTION D4x5.....	43
4.3	Side-mounting of SIMOTION D4x5 on SINAMICS assembly.....	46
4.4	Mounting SIMOTION D4x5 on the wall of the control cabinet.....	47
4.4.1	Mounting the SIMOTION D4x5 with spacers.....	48
4.4.2	Mounting SIMOTION D425, D435, and D445-1 without spacers.....	49
4.5	Installing supplementary system components.....	51
4.5.1	Installing the TB30.....	51
4.5.2	Installing the CBE30.....	52
4.5.3	Installing the CX32.....	53
4.5.4	Removing the cover of the CX32.....	56
5	Connection	59
5.1	Complete overview (example).....	59
5.2	Safety information for wiring.....	61
5.3	Opening the front cover.....	64
5.4	Power supply.....	65

5.4.1	Safety rules.....	65
5.4.2	Standards and Regulations.....	66
5.4.3	Mains voltage.....	67
5.4.4	Connecting the power supply.....	68
5.5	Connecting DRIVE-CLiQ components.....	68
5.5.1	DRIVE-CLiQ wiring.....	68
5.5.2	Connectable DRIVE-CLiQ components.....	70
5.5.3	Connecting CX32.....	71
5.6	Connecting inputs/outputs.....	74
5.6.1	Creating a shield connection.....	75
5.6.2	Connecting inputs/outputs of the TB30.....	77
5.7	Connecting PROFIBUS/MPI.....	78
5.7.1	PROFIBUS connection components.....	78
5.7.2	PROFIBUS cables and connectors.....	79
5.7.3	PROFIBUS cable lengths.....	80
5.7.4	Rules for the laying of PROFIBUS cables.....	80
5.7.5	Connecting PROFIBUS DP (interfaces X126 and X136).....	81
5.7.6	Connection rules in the PROFIBUS subnet.....	82
5.7.7	Operating the X136 interface as MPI.....	84
5.8	Connecting PROFINET IO components.....	85
5.8.1	Wiring PROFINET.....	85
5.8.2	PROFINET cable.....	87
5.9	Routing.....	88
5.9.1	Routing on SIMOTION D.....	88
5.9.2	Routing on SIMOTION D (SINAMICS integrated).....	91
5.10	Connecting Ethernet.....	92
5.10.1	Wiring Ethernet.....	92
5.10.2	Ethernet cables and connectors.....	92
6	Commissioning (hardware).....	95
6.1	Requirements for commissioning.....	95
6.1.1	Inserting the CompactFlash card.....	95
6.1.2	Checking the system.....	98
6.1.3	Switching on the power supply.....	98
6.2	RESET button.....	100
6.3	User memory concept.....	101
6.3.1	SIMOTION D4x5 memory model.....	101
6.3.2	Properties of the user memory.....	102
6.3.3	Operations and their effect on the user memory.....	105
6.4	Fan.....	112
6.4.1	Cooling the SIMOTION D4x5.....	112
6.4.2	Fan/battery module on the D425/D435.....	113
6.4.3	Fan/battery module on the D445/D445-1.....	114
6.4.4	Overview of states, fan/battery module.....	115
6.4.5	Response to overtemperature.....	118
7	Parameter assignment / addressing.....	121
7.1	Software requirements.....	121

7.2	Creating a project and configuring communication.....	121
7.2.1	Creating a SIMOTION project and inserting a D4x5.....	121
7.2.2	Configuring the PROFIBUS PG/PC interface.....	124
7.2.3	Configuring the Ethernet PG/PC interface.....	125
7.2.4	Representation of SIMOTION D4x5 in HW Config.....	127
7.3	Configuring PROFIBUS DP.....	128
7.3.1	General information about communication via PROFIBUS DP.....	128
7.3.2	Operating SIMOTION D4x5 on PROFIBUS DP.....	129
7.3.3	Assignment of the PROFIBUS addresses in HW Config.....	131
7.3.4	Setting the DP cycle and system cycle clocks.....	131
7.3.5	Cycle clock scaling of external PROFIBUS interface to internal PROFIBUS interface.....	133
7.3.6	Creating a new PROFIBUS subnet.....	135
7.3.7	Modifying the data transmission rate.....	135
7.3.8	Establishing a PG/PC assignment.....	136
7.4	Configuring an Ethernet subnet.....	137
7.4.1	Configuring an MPI bus.....	137
7.4.1.1	Operating the X136 interface as MPI.....	137
7.4.1.2	MPI parameters.....	138
7.4.2	Properties of the Ethernet interfaces.....	138
7.4.3	Configuring Ethernet addresses in HW Config.....	141
7.4.4	Reading out IP and MAC address.....	142
7.5	Configuring PROFINET IO.....	143
7.5.1	General information about communication via PROFINET IO.....	143
7.5.2	Setting a send cycle clock and a system cycle clock.....	145
7.5.3	Properties of PROFINET.....	146
7.5.4	Configuration tasks.....	147
8	Commissioning (software).....	149
8.1	Overview of commissioning.....	149
8.1.1	Symbolic assignment / adaptation.....	149
8.1.2	Procedure when commissioning.....	153
8.1.3	Important functions for the project handling during commissioning.....	154
8.2	Performing offline configuration for the D4x5.....	155
8.2.1	Overview.....	155
8.2.2	Accessing the drive wizard.....	156
8.2.3	Configuring components.....	157
8.2.4	Downloading a project into the target system.....	176
8.2.5	Downloading a project to the CF card.....	179
8.2.6	Loading a project, including sources and additional data.....	180
8.2.7	Archiving a project to the CompactFlash Card (zip file).....	181
8.3	Performing online configuration for D4x5.....	182
8.3.1	Overview.....	182
8.3.2	Establish an online connection.....	182
8.3.3	Starting the automatic configuration.....	183
8.3.4	Editing SINAMICS components.....	188
8.3.5	Downloading a project to SIMOTION D4x5.....	188
8.4	Configuring a CX32.....	190
8.4.1	Overview.....	190
8.4.2	Basic principles of the CX32.....	190

8.4.3	Preparing for configuration.....	191
8.4.4	Displaying the topology.....	194
8.4.5	Performing CX32 configuration offline.....	196
8.4.5.1	Loading a project created offline to the target system.....	197
8.4.5.2	Loading a project created offline to the CF card.....	198
8.4.6	Performing CX32 configuration online.....	199
8.4.7	CX32 configuration instructions.....	200
8.4.7.1	CX32 power-up.....	200
8.4.7.2	Interconnecting the infeed "Operation" signal on the CX32.....	201
8.4.7.3	CX32 diagnostics.....	203
8.4.7.4	Upgrading D4x5/CX32.....	204
8.4.7.5	Replacing D4x5/CX32.....	205
8.5	Additional information on configuring the SINAMICS Integrated.....	206
8.5.1	Settings for DP slave properties.....	206
8.5.2	Using vector drives.....	207
8.5.3	Setting the time of day.....	210
8.5.4	SINAMICS diagnostic buffer.....	213
8.5.5	Acyclic communication with the drive.....	213
8.5.6	Control properties and performance features.....	214
8.5.7	Current controller cycle clocks <> 125 µs / use of output cams and measuring inputs.....	215
8.6	Testing a drive with the drive control panel.....	216
8.7	Creating and testing axes.....	219
8.7.1	Overview of SIMOTION engineering.....	219
8.7.2	Creating an axis with the axis wizard.....	220
8.7.3	Testing the axis with the axis control panel.....	227
8.8	Activating the infeed (line module).....	229
8.8.1	Infeed without DRIVE-CLiQ connection.....	229
8.8.2	Infeeds with DRIVE-CLiQ connection.....	230
8.8.3	Using one infeed for several CUs.....	231
8.9	Setting up addresses and message frames.....	232
8.9.1	Setting up communication for symbolic assignment.....	232
8.9.2	Message frame configuration.....	232
8.10	Linking an additional encoder (optional).....	236
8.10.1	Fundamentals.....	236
8.10.2	Additional encoders on the drive.....	236
8.10.3	Additional encoders via PROFIBUS/PROFINET.....	238
8.11	Symbolic assignment of I/O variables (PROFIdrive message frame / drive parameters).....	238
8.11.1	Symbolic assignment of I/O variables to the PROFIdrive message frame of the TO axis.....	238
8.11.2	Symbolic assignment of I/O variables to drive parameters.....	239
8.12	Configuration of drive-related I/Os (with symbolic assignment).....	243
8.12.1	Configuration of the I/O terminals.....	244
8.12.1.1	Configuration of the D4x5 I/Os (terminal X122/X132).....	245
8.12.1.2	Configuration of the CX32/CU3xx/TB30/TMxx I/O terminals.....	246
8.13	Configuration of the technology objects and I/O variables.....	247
8.13.1	Configuration of global measuring inputs.....	247
8.13.2	Configuration of local measuring inputs.....	248
8.13.3	Configuration of output cams / cam tracks.....	248
8.13.4	Configuration of the I/Os (variables / TO axis).....	250

8.14	DMC20/DME20 DRIVE-CLiQ hub.....	252
8.14.1	Hub properties.....	252
8.14.2	Creating a DMC20/DME20 DRIVE-CLiQ hub.....	253
8.15	TM41 Terminal Module.....	254
8.15.1	Overview.....	254
8.15.2	Configuring TM41 at SINAMICS Integrated.....	254
8.15.3	Configuring TM41 using the Axis Wizard.....	255
8.16	Optimizing drive and closed-loop controller.....	255
8.16.1	Overview of automatic controller setting.....	255
8.16.2	Automatic speed controller setting.....	256
8.16.3	Automatic position controller setting.....	257
8.16.4	Measuring functions, trace, and function generator.....	259
8.16.5	Manual speed controller optimization.....	260
8.17	Downloading and saving SIMOTION user data.....	264
8.18	Deleting data.....	266
8.18.1	Overview of data deletion.....	266
8.18.2	Overall reset of SIMOTION D4x5.....	266
8.18.3	Deleting user data from CF card.....	269
8.18.4	Restoring the default settings of SINAMICS Integrated.....	270
8.18.5	Setting SIMOTION D4x5 to the default settings.....	270
8.19	Powering down the system.....	271
8.20	Configuring Safety Integrated functions.....	271
8.21	Migration D445 to D445-1.....	276
8.21.1	Overview.....	276
8.21.2	Configuration.....	277
8.21.3	Compatibility.....	277
9	Service and maintenance.....	281
9.1	Overview.....	281
9.2	Replacing modules (spare part scenario).....	285
9.2.1	Parts replacement for SIMOTION D4x5.....	285
9.2.2	Removal and replacement of the SIMOTION D4x5.....	286
9.2.3	Replacing DRIVE-CLiQ components.....	288
9.2.4	Replacing the CompactFlash Card.....	290
9.3	Adapting a project (Updating the project / Replacing the SIMOTION controller).....	291
9.3.1	Overview.....	291
9.3.2	Creating backup copies (project/CF).....	291
9.3.3	Backing up user data (backup variables).....	291
9.3.4	Upgrading a user project to the new SCOUT version.....	294
9.3.5	Platform replacement via XML export/import.....	295
9.3.6	Preparing the device replacement.....	296
9.3.7	Device replacement in HW Config.....	298
9.3.8	Upgrading technology packages.....	299
9.3.9	Upgrading the device version of SINAMICS S120 control units.....	301
9.3.10	Upgrading a library.....	302
9.3.11	Save project, compile and check consistency.....	303
9.4	Performing a firmware and project update.....	303

9.4.1	Upgrading the CompactFlash Card's boot loader	303
9.4.2	Update - preparatory measures.....	304
9.4.3	Update via SIMOTION IT web server.....	305
9.4.4	Upgrade via device update tool (upgrading SIMOTION devices).....	305
9.4.5	Upgrade via CF card.....	310
9.4.5.1	Backup of the CF card data.....	310
9.4.5.2	Firmware upgrade via CF card.....	311
9.4.5.3	Upgrading SINAMICS.....	312
9.4.5.4	Loading a project to the target system.....	313
9.5	SIMOTION Compact Flash card.....	314
9.5.1	Changing the CompactFlash Card.....	314
9.5.2	Writing to the the CompactFlash card.....	315
9.5.3	Formatting the CompactFlash card.....	316
9.5.4	Bootloader on the CompactFlash card.....	316
9.5.5	Recommended method for dealing with CF cards.....	317
9.5.6	Card reader for CF cards.....	317
10	Diagnostics.....	319
10.1	Diagnostics via LED displays.....	319
10.1.1	SIMOTION D4x5 and SINAMICS Integrated displays.....	320
10.1.2	LED displays of the PROFINET interface.....	325
10.1.3	LED displays of the Ethernet interface.....	327
10.1.4	LED displays of the CX32 controller extension.....	327
10.1.4.1	Behavior of the LEDs during booting of the CX32.....	327
10.1.4.2	Behavior of the LEDs after booting of the CX32.....	328
10.2	Diagnostic data and non-volatile SIMOTION data.....	329
10.2.1	Overview.....	329
10.2.2	Backup of diagnostic data and non-volatile SIMOTION data.....	330
10.2.2.1	Diagnostic data.....	330
10.2.2.2	Non-volatile SIMOTION data (retain data).....	330
10.2.2.3	Procedure for backing up during operation.....	331
10.2.2.4	Procedure for backing up during startup.....	332
10.2.2.5	Storing data.....	333
10.2.3	Diagnostics via websites.....	334
10.2.4	Deleting/restoring non-volatile SIMOTION data.....	336
10.2.5	Back up diagnostic data and non-volatile SIMOTION data via the web server.....	338
10.3	Additional service and diagnostics options.....	339
10.3.1	SIMOTION Task Profiler application.....	339
10.3.2	Diagnostics via the SIMOTION IT web server.....	339
A	Configuration of drive-related I/Os (without symbolic assignment).....	341
A.1	Overview.....	341
A.2	Local and global measuring inputs.....	342
A.3	Configuring local measuring inputs.....	344
B	Standards and approvals.....	347
B.1	General rules.....	347
B.2	SIMOTION D4x5 device-specific notes.....	348

C	ESD guidelines.....	349
	C.1 ESD definition.....	349
	C.2 Electrostatic charging of individuals.....	349
	C.3 Basic measures for protection against discharge of static electricity.....	350
	Index.....	351

Safety instructions

1.1 Fundamental safety instructions

1.1.1 General safety instructions



DANGER

Danger to life due to live parts and other energy sources

Death or serious injury can result when live parts are touched.


- Only work on electrical devices when you are qualified for this job.
- Always observe the country-specific safety rules.

Generally, six steps apply when establishing safety:


1. Prepare for shutdown and notify all those who will be affected by the procedure.
2. Disconnect the machine from the supply.
 - Switch off the machine.
 - Wait until the discharge time specified on the warning labels has elapsed.
 - Check that it really is in a no-voltage condition, from phase conductor to phase conductor and phase conductor to protective conductor.
 - Check whether the existing auxiliary supply circuits are de-energized.
 - Ensure that the motors cannot move.
3. Identify all other dangerous energy sources, e.g. compressed air, hydraulic systems, or water.
4. Isolate or neutralize all hazardous energy sources by closing switches, grounding or short-circuiting or closing valves, for example.
5. Secure the energy sources against switching on again.
6. Ensure that the correct machine is completely interlocked.

After you have completed the work, restore the operational readiness in the inverse sequence.




 WARNING
Danger to life from hazardous voltage when connecting an unsuitable power supply
Touching live components can result in death or severe injury.
<ul style="list-style-type: none">• Only use power supplies that provide SELV (Safety Extra Low Voltage) or PELV (Protective Extra Low Voltage) output voltages for all connections and terminals of the electronics modules.




 WARNING
Danger to life from touching live parts on damaged devices
Improper handling of devices can result in damage.
For damaged devices, hazardous voltages can be present at the enclosure or at exposed components; if touched, this can result in death or severe injury.
<ul style="list-style-type: none">• Observe the limit values specified in the technical specifications during transport, storage, and operation.• Do not use damaged devices.



 WARNING
Danger to life through electric shock due to unconnected cable shields
Hazardous touch voltages can occur through capacitive cross-coupling due to unconnected cable shields.
<ul style="list-style-type: none">• As a minimum, connect cable shields and the cores of power cables that are not used (e.g. brake cores) at one end at the grounded housing potential.



 WARNING
Danger to life due to electric shock when not grounded
For missing or incorrectly implemented protective conductor connection for devices with protection class I, high voltages can be present at open, exposed parts, which when touched, can result in death or severe injury.
<ul style="list-style-type: none">• Ground the device in compliance with the applicable regulations.

 **WARNING****Danger to life due to fire spreading if housing is inadequate**

Fire and smoke development can cause severe personal injury or material damage.

- Install devices without a protective housing in a metal control cabinet (or protect the device by another equivalent measure) in such a way that contact with fire inside and outside the device is prevented.
- Ensure that smoke can only escape via controlled and monitored paths.

 **WARNING****Danger to life from unexpected movement of machines when using mobile wireless devices or mobile phones**

Using mobile radios or mobile phones with a transmit power > 1 W closer than approx. 2 m to the components may cause the devices to malfunction, influence the functional safety of machines therefore putting people at risk or causing material damage.

- Switch off wireless devices or mobile phones in the immediate vicinity of the components.

 **WARNING****Danger to life due to fire if overheating occurs because of insufficient ventilation clearances**


Inadequate ventilation clearances can cause overheating of components followed by fire and smoke development. This can cause death or serious injury. This can also result in increased downtime and reduced service life for devices/systems.

- Ensure compliance with the specified minimum clearance as ventilation clearance for the respective component.

 **WARNING****Danger of an accident occurring due to missing or illegible warning labels**

Missing or illegible warning labels can result in accidents involving death or serious injury.


- Check that the warning labels are complete based on the documentation.
- Attach any missing warning labels to the components, in the national language if necessary.
- Replace illegible warning labels.

 WARNING
Danger to life when safety functions are inactive
Safety functions that are inactive or that have not been adjusted accordingly can cause operational faults on machines that could lead to serious injury or death.
<ul style="list-style-type: none">• Observe the information in the appropriate product documentation before commissioning.• Carry out a safety inspection for functions relevant to safety on the entire system, including all safety-related components.• Ensure that the safety functions used in your drives and automation tasks are adjusted and activated through appropriate parameterizing.• Perform a function test.• Only put your plant into live operation once you have guaranteed that the functions relevant to safety are running correctly.

Note

Important safety notices for safety functions

If you want to use safety functions, you must observe the safety notices in the safety manuals.

 WARNING
Danger to life or malfunctions of the machine as a result of incorrect or changed parameterization
As a result of incorrect or changed parameterization, machines can malfunction, which in turn can lead to injuries or death.
<ul style="list-style-type: none">• Protect the parameterization (parameter assignments) against unauthorized access.• Respond to possible malfunctions by applying suitable measures (e.g. EMERGENCY STOP or EMERGENCY OFF).

1.1.2 Safety instructions for electromagnetic fields (EMF)



WARNING

Danger to life from electromagnetic fields

Electromagnetic fields (EMF) are generated by the operation of electrical power equipment such as transformers, converters or motors.

People with pacemakers or implants are at a special risk in the immediate vicinity of these devices/systems.

- Ensure that the persons involved are the necessary distance away (minimum 2 m).

1.1.3 Handling electrostatic sensitive devices (ESD)

Electrostatic sensitive devices (ESD) are individual components, integrated circuits, modules or devices that may be damaged by either electric fields or electrostatic discharge.



NOTICE

Damage through electric fields or electrostatic discharge

Electric fields or electrostatic discharge can cause malfunctions through damaged individual components, integrated circuits, modules or devices.

- Only pack, store, transport and send electronic components, modules or devices in their original packaging or in other suitable materials, e.g. conductive foam rubber or aluminum foil.
- Only touch components, modules and devices when you are grounded by one of the following methods:
 - Wearing an ESD wrist strap
 - Wearing ESD shoes or ESD grounding straps in ESD areas with conductive flooring
- Only place electronic components, modules or devices on conductive surfaces (table with ESD surface, conductive ESD foam, ESD packaging, ESD transport container).

1.1.4 Industrial security

Note

Industrial security

Siemens provides products and solutions with industrial security functions that support the secure operation of plants, solutions, machines, equipment and/or networks. They are important components in a holistic industrial security concept. With this in mind, Siemens' products and solutions undergo continuous development. Siemens recommends strongly that you regularly check for product updates.

For the secure operation of Siemens products and solutions, it is necessary to take suitable preventive action (e.g. cell protection concept) and integrate each component into a holistic, state-of-the-art industrial security concept. Third-party products that may be in use should also be considered. For more information about industrial security, visit <http://www.siemens.com/industrialsecurity>.

To stay informed about product updates as they occur, sign up for a product-specific newsletter. For more information, visit <http://support.automation.siemens.com>



WARNING

Danger as a result of unsafe operating states resulting from software manipulation

Software manipulation (e.g. by viruses, Trojan horses, malware, worms) can cause unsafe operating states to develop in your installation which can lead to death, severe injuries and/or material damage.

- Keep the software up to date.
Information and newsletters can be found at:
<http://support.automation.siemens.com>
- Incorporate the automation and drive components into a state-of-the-art, integrated industrial security concept for the installation or machine.
For more detailed information, go to:
<http://www.siemens.com/industrialsecurity>
- Make sure that you include all installed products into the integrated industrial security concept.

1.1.5 Residual risks of power drive systems

The control and drive components of a drive system are approved for industrial and commercial use in industrial line supplies. Their use in public line supplies requires a different configuration and/or additional measures.

These components may only be operated in closed housings or in higher-level control cabinets with protective covers that are closed, and when all of the protective devices are enabled.

These components may only be handled by qualified and trained technical personnel who are knowledgeable and observe all of the safety instructions on the components and in the associated technical user documentation.

When assessing the machine's risk in accordance with the respective local regulations (e.g. EC Machinery Directive), the machine manufacturer must take into account the following residual risks emanating from the controller and drive components of a drive system:

1. Unintentional movements of driven machine components during commissioning, operation, maintenance, and repairs caused by, for example:
 - Hardware faults and/or software errors in sensors, controllers, actuators, and connection systems
 - Response times of the controller and drive
 - Operating and/or ambient conditions outside of the specification
 - Condensation / conductive contamination
 - Parameterization, programming, cabling, and installation errors
 - Use of radio devices/cellular phones in the immediate vicinity of the controller
 - External influences / damage
2. In the event of a fault, exceptionally high temperatures, including an open fire, as well as emissions of light, noise, particles, gases, etc. can occur inside and outside the inverter, for example:
 - Component malfunctions
 - Software errors
 - Operating and/or ambient conditions outside of the specification
 - External influences / damage

Inverters of the Open Type / IP20 degree of protection must be installed in a metal control cabinet (or protected by another equivalent measure) such that the contact with fire inside and outside the inverter is not possible.
3. Hazardous touch voltages caused by, for example:
 - Component malfunctions
 - Influence of electrostatic charging
 - Induction of voltages in moving motors
 - Operating and/or ambient conditions outside 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.

Note

The components must be protected against conductive contamination (e.g. by installing them in a control cabinet with degree of protection IP54 according to IEC 60529 or NEMA 12).

Assuming that conductive contamination at the installation site can definitely be excluded, a lower degree of cabinet protection may be permitted.

For more information about residual risks of the components in a drive system, see the relevant sections in the technical user documentation.

1.2 Specific safety information for SIMOTION D4x5



! WARNING

Danger to life from hazardous voltage when connecting an unsuitable power supply

Only safety extra low voltage in accordance with EN/IEC 60950-1 may be connected at all connectors and terminals.

! WARNING

Danger to life from unexpected movement of machines on automatic restart

An automatic restart can be programmed for SIMOTION controllers. When the power returns, the axes start automatically.

Make sure this presents no hazard to personnel or property.

NOTICE

Damage to option boards caused by electric fields or electrostatic discharge

Option boards are ESD-sensitive components.

De-energize the SIMOTION D4x5 device before inserting or removing the option board. SIMOTION D4x5 is in a de-energized state when all the LEDs are OFF.

Comply with the ESD rules.

NOTICE

Damage to the CompactFlash card from electrical fields or electrostatic discharge

The CompactFlash card is an ESD-sensitive component.

De-energize the SIMOTION D4x5 device before inserting or removing the CompactFlash card. SIMOTION D4x5 is in a de-energized state when all the LEDs are OFF.

Comply with the ESD rules.

NOTICE

Higher operating temperature if ventilation clearances are too small

The 80 mm clearances above and below the components must be observed.

The unit protects itself from overheating by shutting down.

The ventilation clearance is measured from the lower edge of the module, i.e. the fan/battery module is not included in the dimension.

Description

2.1 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 and D410-2 single-axis modules and 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.

Application

SIMOTION D4x5 is ideally suited to applications with many coordinated axes with high clock-pulse rates.

Typical applications include:

2.1 System overview

- 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.

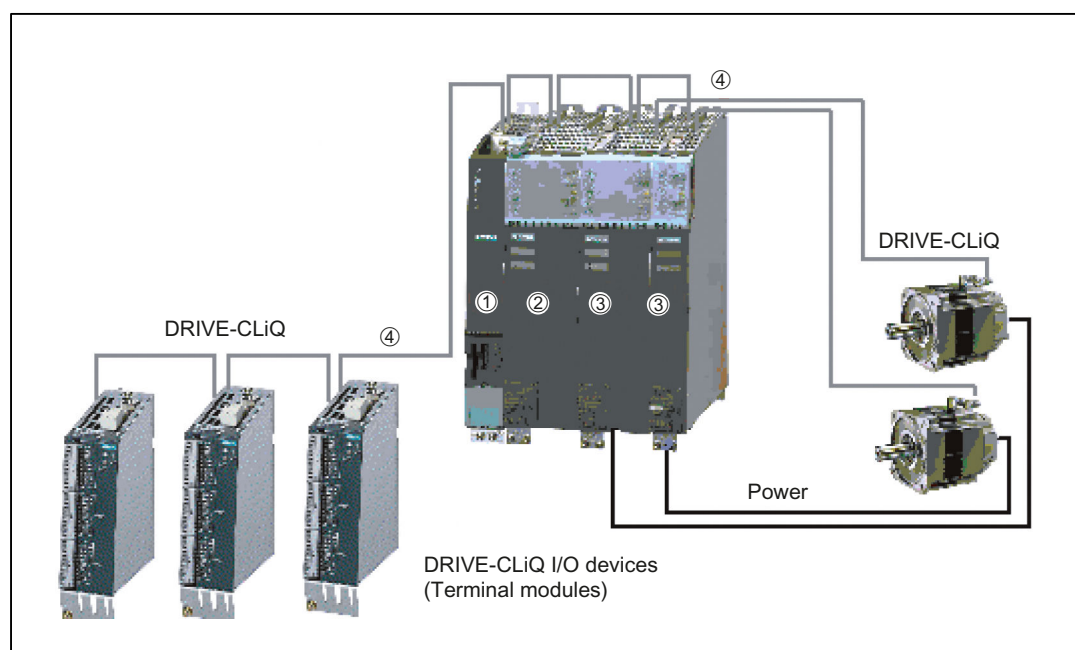


Figure 2-1 Example of a SIMOTION D4x5 axis assembly

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:

- User-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:

- Current and torque control
- Speed control
- Closed-loop infeed

2.2 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.

Table 2-1 Central components

Component	Function
SIMOTION D4x5 controller	<p>... 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:</p> <ul style="list-style-type: none"> • Homing inputs • Inputs for measuring inputs • User-addressable process I/Os • Outputs for fast output cams <p>The measuring sockets can output any analog signals.</p>
System software	<p>The basic functionality of SIMOTION D is supplied on a CompactFlash card containing the following:</p> <ul style="list-style-type: none"> • SIMOTION runtime (kernel) • Drive software of SINAMICS S120 - implements all drive functions
Power supply	<p>... provides the electronics power supply for SIMOTION D, e.g. via the SITOP power supply.</p>

PROFIBUS DP

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

Table 2-2 Components on PROFIBUS DP

Component	Function
Programming device (PG/PC)	<p>... configures, parameterizes, programs, and tests with the "SIMOTION SCOUT" engineering system (ES)</p>
SIMATIC HMI device	<p>... is used for operating and monitoring functions. This is not an essential requirement for the operation of a control unit</p>

2.2 System components

Component	Function
Other controllers (e.g. SIMOTION or SIMATIC)	.. e.g. higher-level controller (plant controller); modular machine concepts with multiple controllers, 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	<ul style="list-style-type: none"> • 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	<ul style="list-style-type: none"> • 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. Can also be operated as an isochronous slave on the PROFIBUS DP.
Teleservice adapter	Remote diagnostics

Ethernet

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

Table 2-3 Components on the Ethernet

Component	Function
Programming device (PG/PC)	... configures, parameterizes, programs, and tests with the "SIMOTION SCOUT" engineering system (ES)
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:

Table 2-4 Components on the 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 controllers, 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	<ul style="list-style-type: none"> • IE/AS-Interface link PN IO for the PROFINET IO gateway to AS-Interface • PN/PN coupler for connecting two PROFINET IO networks

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:

Table 2-5 Components connected to 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 Power Module in blocksize format (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 I/Os) for controlling the secure motion monitoring functions of the integrated drives.
TM15, TM17 High Feature Terminal Modules	The Terminal Modules TM15 and TM17 High Feature are used to implement measuring inputs inputs and output cam outputs. In addition, these Terminal Modules provide drive-related digital I/Os 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.

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 2-6 Optional components

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

The selected component is plugged into the option slot of the Control Unit.

Note

CBE30 can only be used in SIMOTION D4x5 Control Units.

CBE30-2 can only be used in SIMOTION D4x5-2 Control Units.

2.3 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 real-time 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.

2.4 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, see 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)

The following SSPs are relevant for SIMOTION SCOUT:

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

You will find detailed information on the SSPs in the readme files and in the software compatibility list at Internet address (<http://support.automation.siemens.com/WW/view/en/18857317>).

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 more information, see Section Adapting a project (Upgrading the project / Replacing the SIMOTION controller) (Page 291).

SIMOTION IT web server

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 the web server (IT DIAG license) and for SIMOTION IT OPC XML-DA.

Additional references

You will find detailed information on working with projects in the *SIMOTION SCOUT* Configuration Manual.

You will find detailed information on the SIMOTION IT web server in the following reference:
SIMOTION IT Diagnostics and Configuration Diagnostics Manual.

Use planning

3.1 Shipping and storage conditions

Transportation 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

Table 3-1 Transportation and storage 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

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.

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 ignition, explosion, and combustion

Incorrect handling of backup batteries can result in a risk of ignition, explosion, and combustion.

The regulations of DIN EN 60086-4, in particular regarding avoidance of mechanical or electrical tampering of any kind, must be complied with.

- Do not recharge
- Do not throw into a fire
- Do not solder on the body of the cell
- Do not open
- Only replace with identical types
- 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 where possible.

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.

3.2 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 that require special monitoring, e.g.
 - Elevator installations
 - Electrical installations in highly sensitive areas

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 3-2 Mechanical ambient conditions

Frequency range (Hz)	continuous	infrequent
$10 \leq f \leq 58$	0.0375 mm amplitude	0.075 mm amplitude
$58 \leq f \leq 150$	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 3-3 Mechanical ambient conditions

Testing	Test standard	Comments
Vibrations	Vibration testing in accordance with IEC 68 Part 2-6 (sine) severity level 12	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 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 accordance with IEC 68 Part 2-27	Type of shock: half sine Severity of shock: 15 g peak value, duration = 11 ms Direction of shock: 3 shocks each in +/- direction in each of the 3 perpendicular axes

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	from 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	SO ₂ : < 0.5 ppm; Relative humidity < 60%, no condensation H ₂ S: < 0.1 ppm; Relative humidity < 60%, no condensation	Test: 10 ppm; 4 days 1 ppm; 4 days

3.3 Specifications for Protection Class and Degree of Protection

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

IP20 degree of protection 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.


Installing

4.1 Installation notes

Open components

These modules are open components. 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.



	DANGER
Danger to life from energized parts	
Death or serious injury will result if energized parts are touched.	
Turn off and lock out all power supplying this device before working on this device.	

4.2 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.

Note

The components must be protected against conductive contamination, e.g. by installing them in a control cabinet with degree of protection IP54 according to IEC 60529 or NEMA 12.

If conductive contamination can be excluded at the installation site, a lower degree of cabinet protection may be permitted.

See Residual risks of power drive systems (Page 20).

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 CF 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.

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.

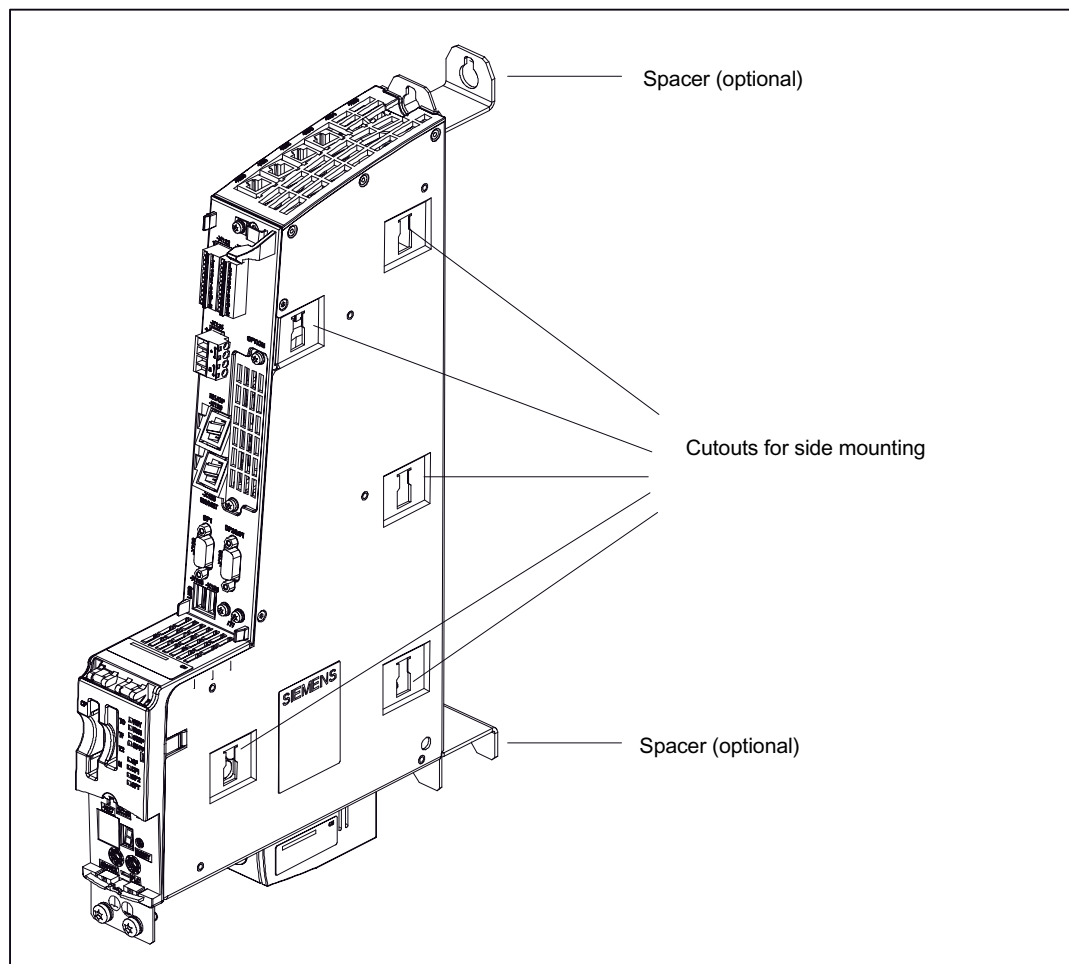


Figure 4-1 Mounting aids based on the example of SIMOTION D425 and D435

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 46)

Mounting the SIMOTION D4x5 with spacers (Page 48)

Mounting SIMOTION D425, D435, and D445-1 without spacers (Page 49)

4.3 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

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.

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.

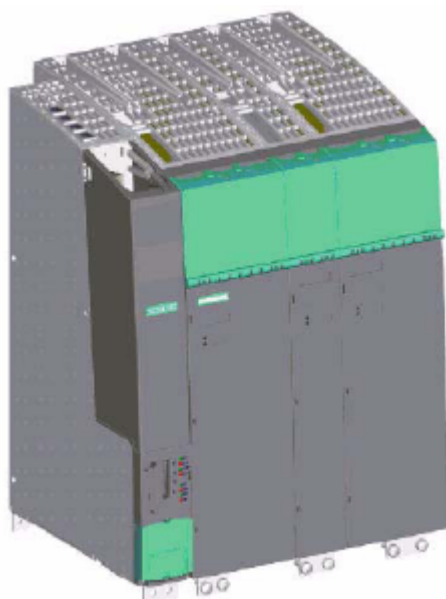


Figure 4-2 SINAMICS assembly with SIMOTION D4x5

4.4 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

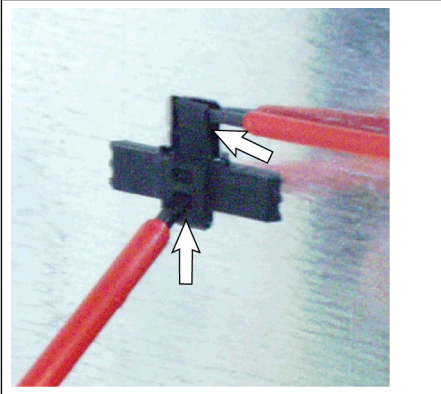
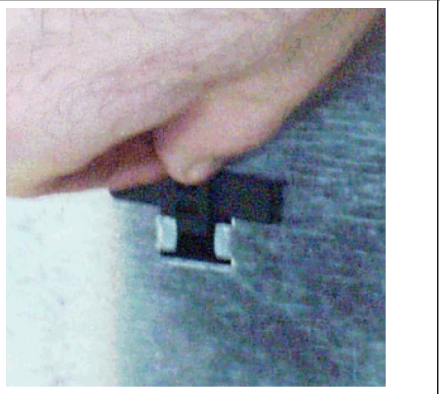
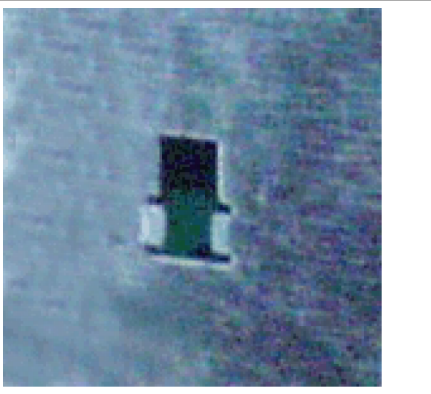
If you wish to install a SIMOTION D445-1 directly to the left of a Line Module, you will need to remove the plastic mounting fixtures from the side wall of the Line Module.

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:

4.4 Mounting SIMOTION D4x5 on the wall of the control cabinet

		
1. Use suitable tools to lift the latching device and push up the holder.	2. Remove the holder	View of the side wall once the holder has been removed

4.4.1 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

The spacers are included in the scope of delivery of a Control Unit and are ready-assembled.

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 (tightening torque of 6 Nm) to mount the Control Unit on the wall of the control cabinet.

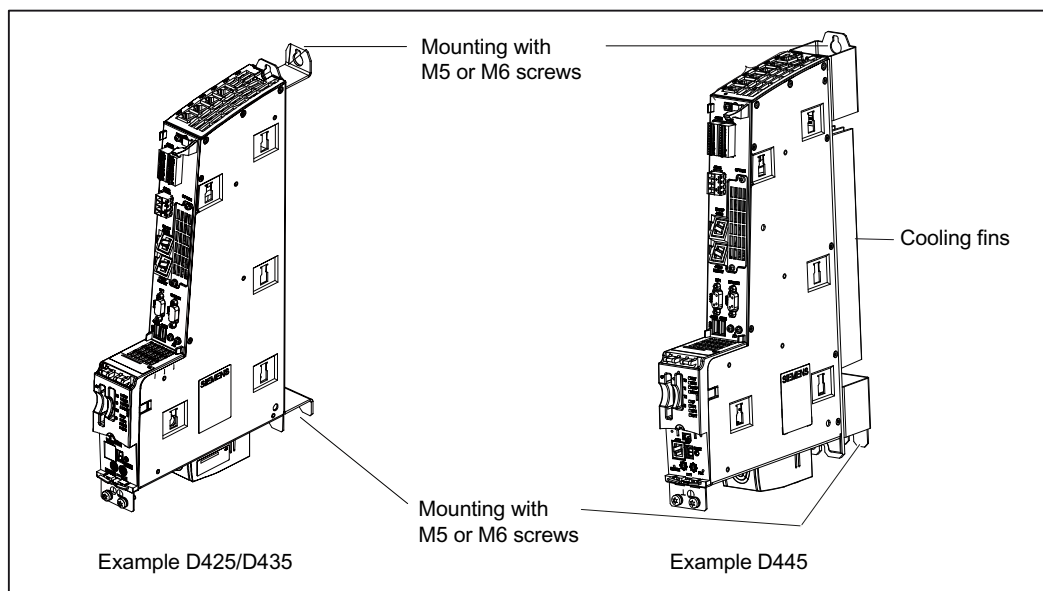


Figure 4-3 Mounting the Control Unit with spacers

Result

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

4.4.2 Mounting SIMOTION D425, D435, and D445-1 without spacers

The Control Units are supplied with pre-assembled spacers. Proceed as follows to mount without spacers:

1. Remove the upper and lower spacers (screws: M3, Torx T10)
2. A metal clip is located beneath the upper spacer; when shipped, this clip is pushed in and secured with 3 screws (M3, Torx T10). Loosen the screws and push the clip up until the upper hole extends beyond the housing.

4.4 Mounting SIMOTION D4x5 on the wall of the control cabinet

3. Retighten the three screws on the clip (0.8 Nm tightening torque).
4. 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).

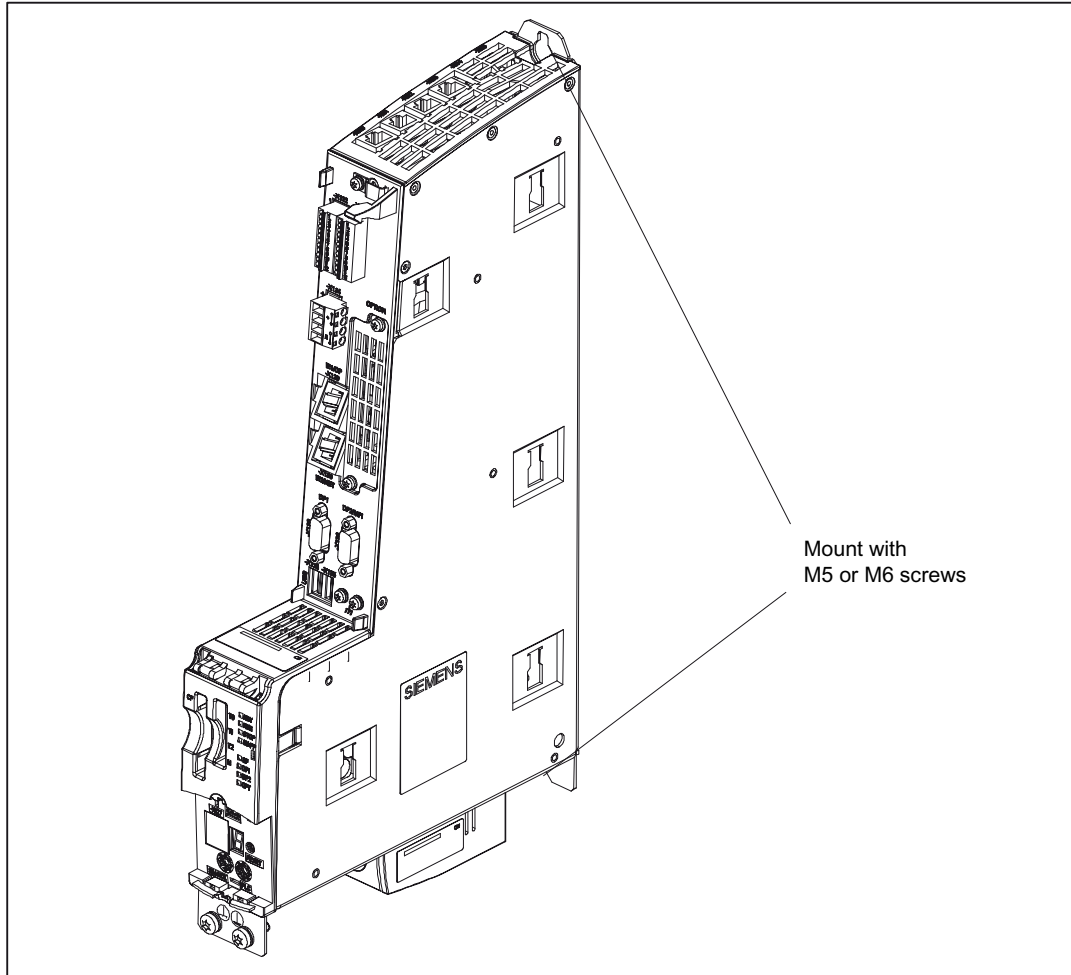


Figure 4-4 Mounting the Control Unit on the wall of the control cabinet

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

4.5 Installing supplementary system components

4.5.1 Installing the TB30

Requirement

Note

Damage to the TB30 caused by electric fields or electrostatic discharge

Option boards are ESD-sensitive components.

De-energize the SIMOTION D4x5 device before inserting or removing the option board. SIMOTION D4x5 is in a de-energized state when all the LEDs are OFF.

Observe the ESD guidelines (see Section ESD guidelines (Page 349)).

Procedure

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

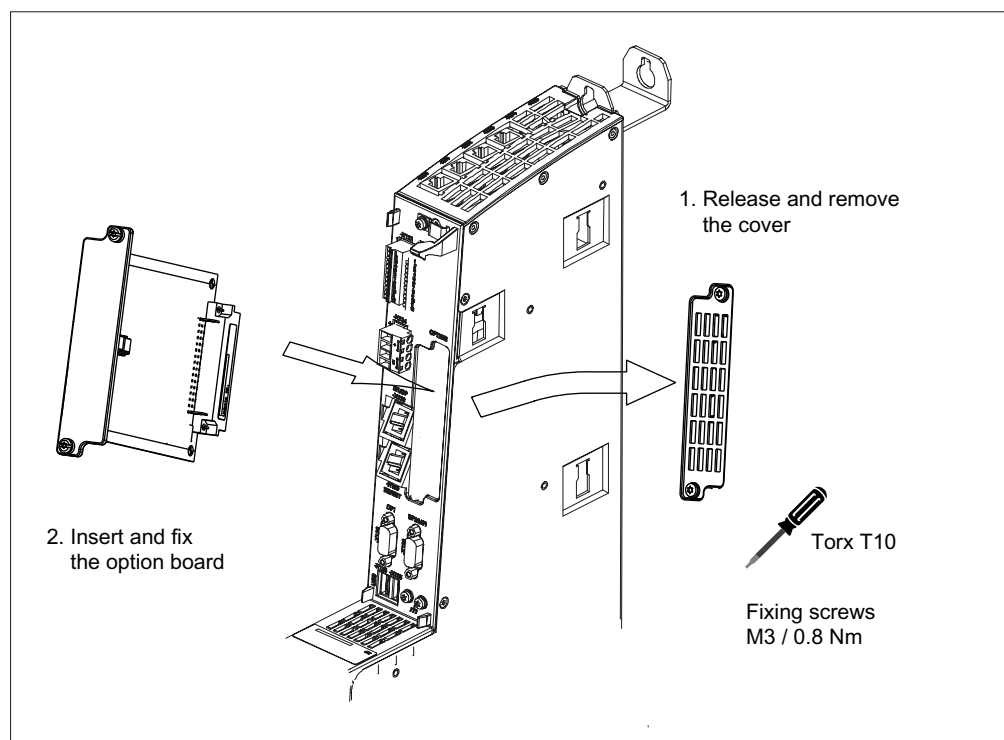


Figure 4-5 TB30 terminal board installation

4.5.2 Installing the CBE30

Requirement

NOTICE

Damage to the CBE30 caused by electric fields or electrostatic discharge

Option boards are ESD-sensitive components.

De-energize the SIMOTION D4x5 device before inserting or removing the option board. SIMOTION D4x5 is in a de-energized state when all the LEDs are OFF.

Comply with the ESD rules.

Procedure

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

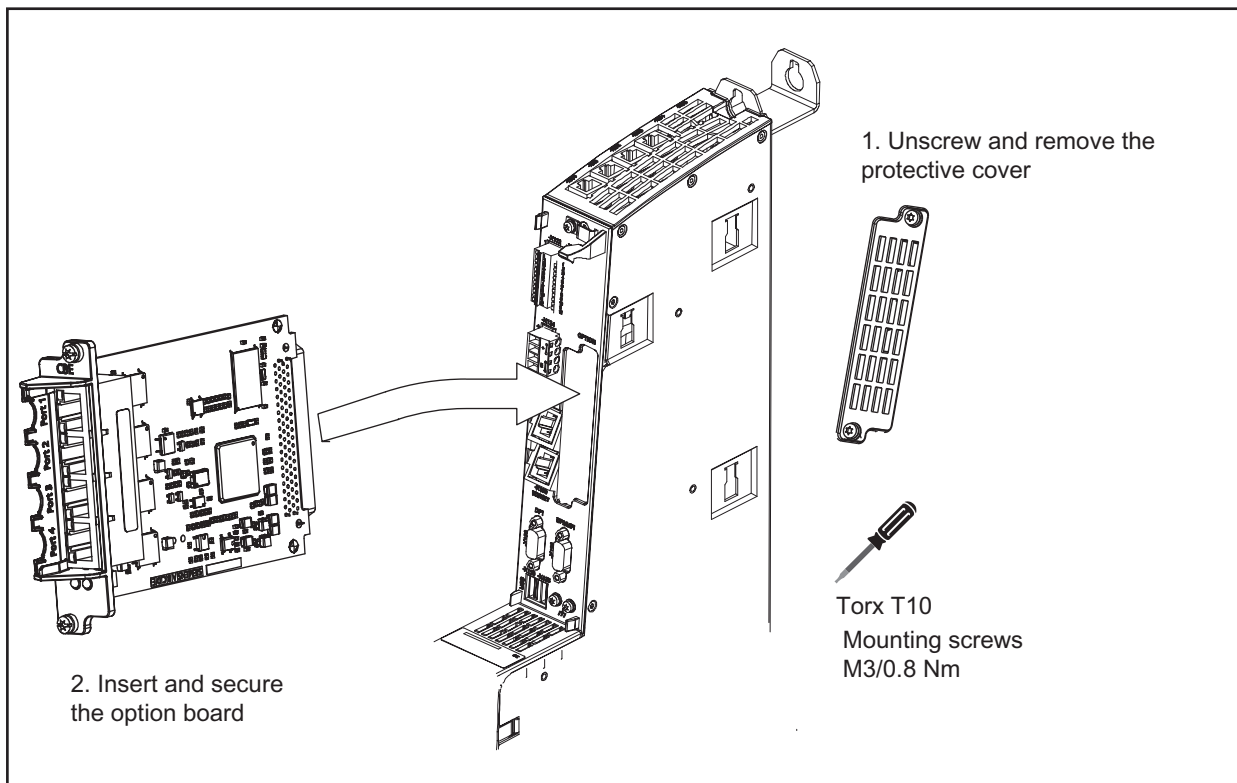


Figure 4-6 Installing the CBE30

4.5.3 Installing the CX32

Overview

The CX32 can be installed in several ways.

Mounting the CX32 directly on a Line Module in booksize format

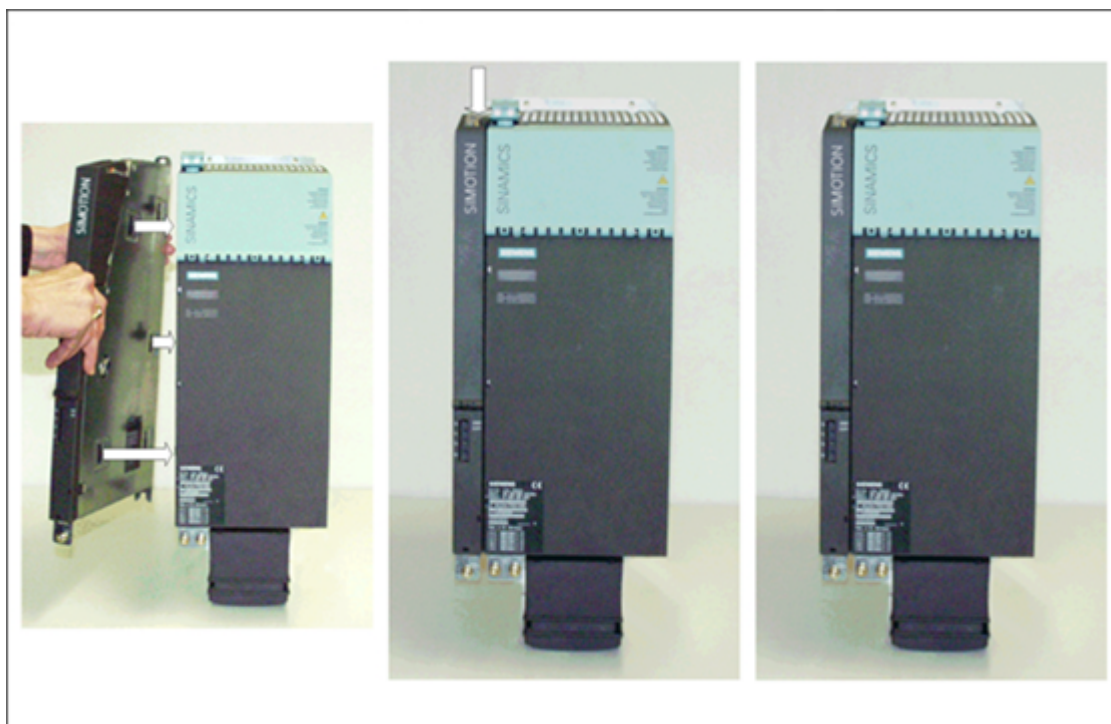

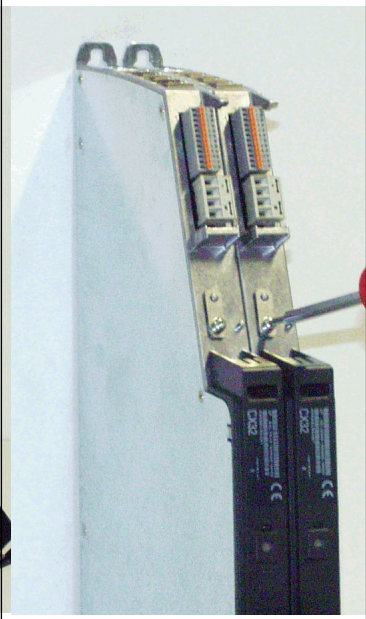
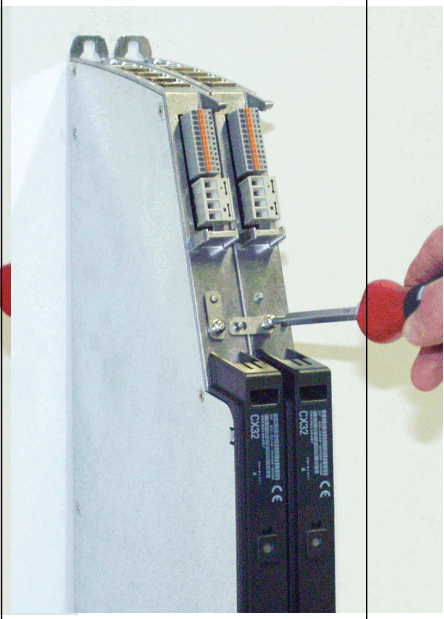
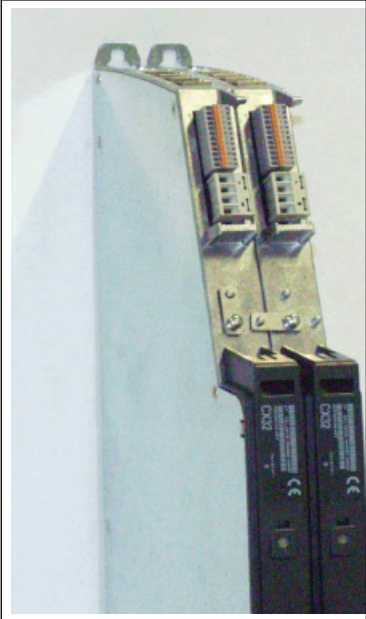
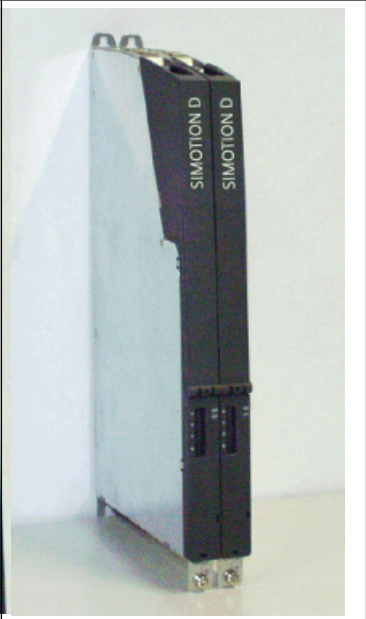


Figure 4-7 Mounting the CX32 directly on a Line Module Booksize

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 56).

Table 4-1 Mounting a CX32 on another CX32

		
<p>Opening the covers.</p>	<p>Unscrewing the screw (M3, Torx T10)</p>	<p>The bracket must be moved so that the pin is in the opening of the bracket. Tightening the screw (tightening torque 0.8 Nm).</p>
		
<p>Mounted bracket.</p>	<p>Closing the cover.</p>	

CX32 directly on a mounting surface

There are 2 mounting points on the rear side of the CX32. These can be screwed directly to a wall, e.g. a control cabinet wall.

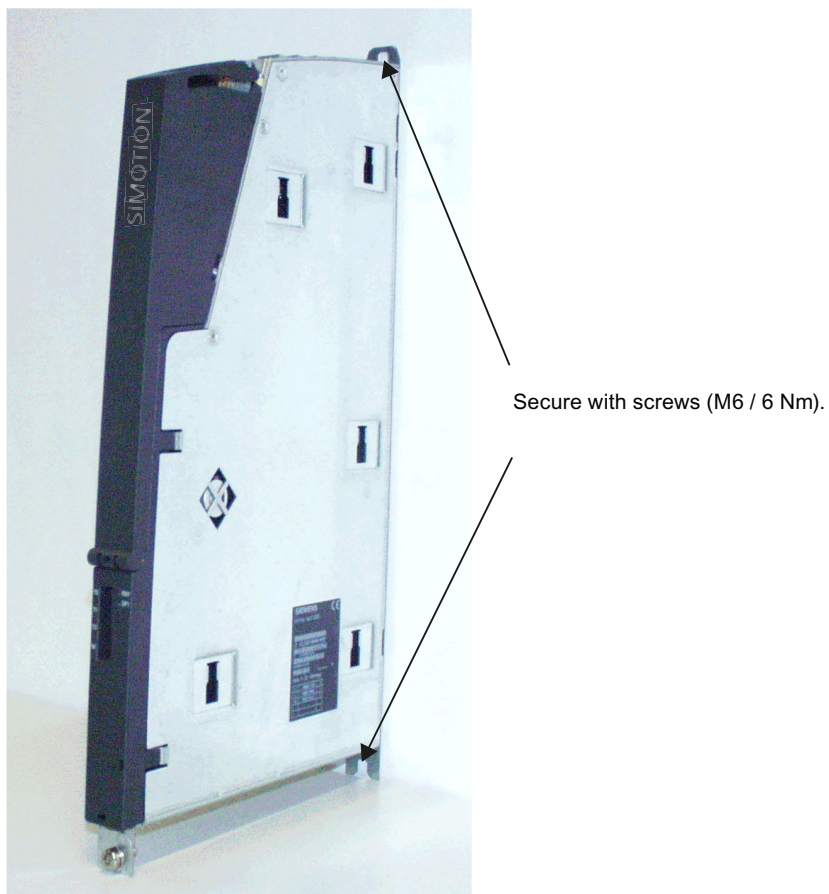


Figure 4-8 Mounting the CX32 directly on a mounting surface

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.

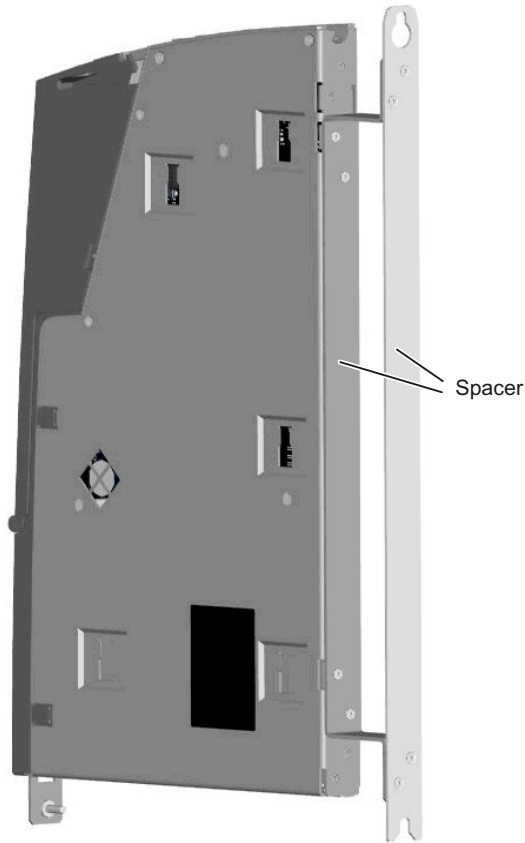


Figure 4-9 Mounting a CX32 with spacers

4.5.4 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°.

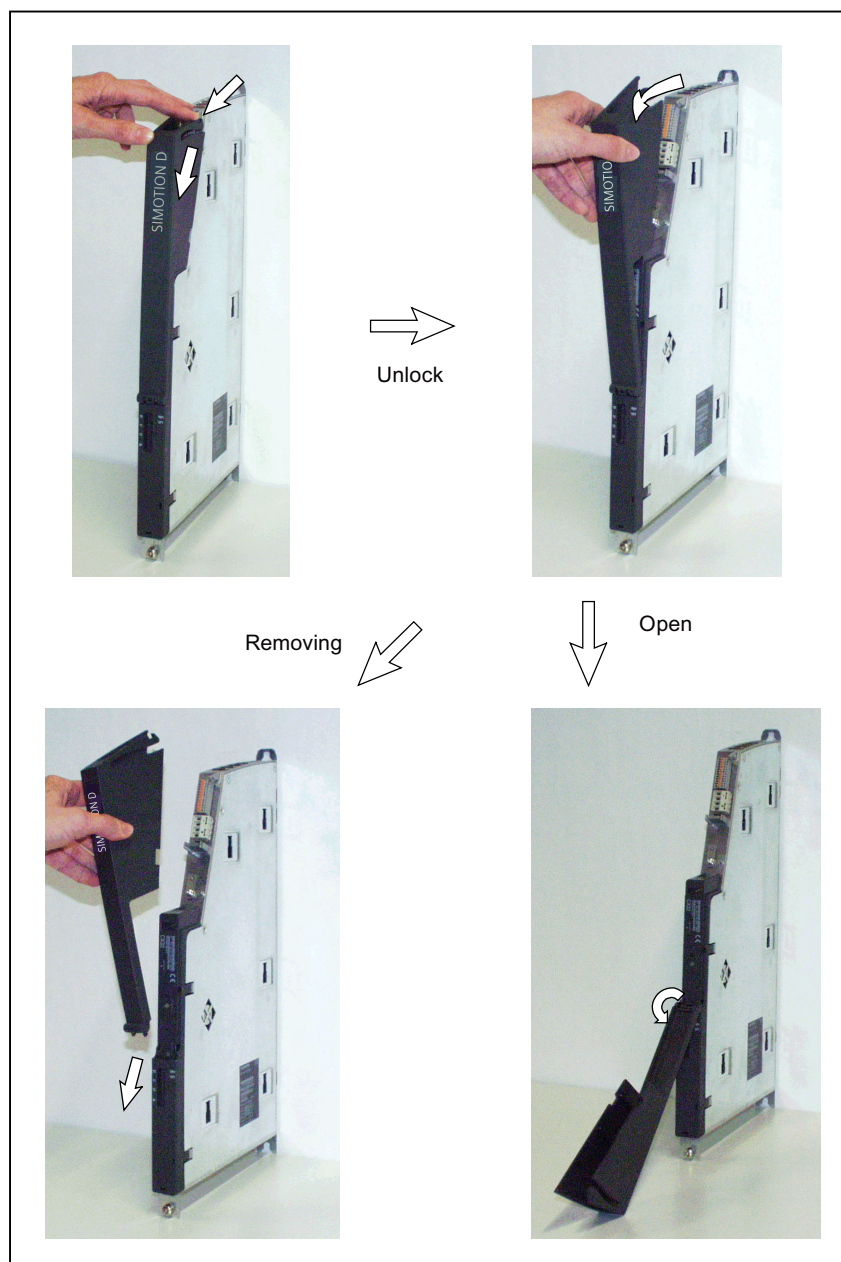


Figure 4-10 Opening/removing the protective cover

Connection

5.1 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.

Overview of connections

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

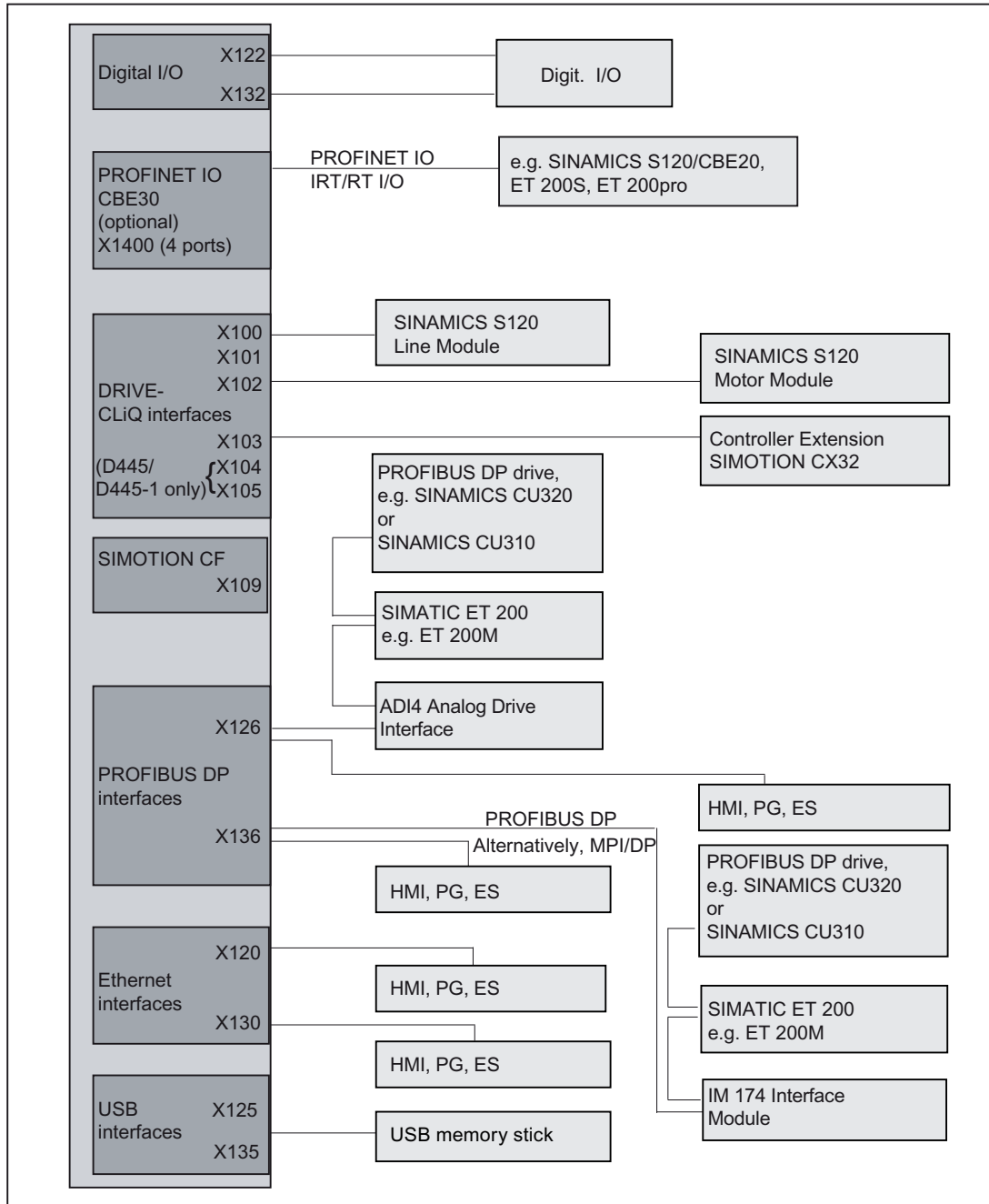


Figure 5-1 Connection possibilities for SIMOTION D4x5

5.2 Safety information for wiring

Requirement

You have mounted the Control Unit in the control cabinet.

The SIMOTION D4x5 Control Unit has a connection for the protective conductor and a connection for the equipotential bonding conductor (M5 screw, Torx T25). Only one connection is available for CX32 - this must be used both for the protective conductor and the equipotential bonding conductor.

Note

Requirements for functional safety for machines and systems; reliability and EMC are only guaranteed with original SIEMENS cables.



DANGER

Danger to life from energized parts

Death or serious injury will result if energized parts are touched.

Turn off and lock out all power supplying this device before working on this device.

Protective conductor connection

SIMOTION D and the SINAMICS S120 drive system are designed for use in cabinets with a protective conductor connection.

All system components and machine parts must be incorporated in the protection concept. The drive line-up must be arranged on a common bright mounting plate ① in order to comply with the EMC limit values. The connection ② establishes a low-impedance connection to the mounting plate.

The mounting plate must be connected to the protective conductor connection of the control cabinet. For this purpose, a connection ③ must be established to the protective conductor bar ④. The protective conductor bar ④ must be connected to the protective conductor ⑤.

The protective connection (PE connection) that is used for the motors ⑥ must be established through the motor cable.

For EMC reasons, the motor cable shield must be laid flat at both the Motor Module (MM) / Power Module (PM) and motor.

A protective connection ⑧ must also be established for components that are **not** connected with low impedance (e.g. control cabinet door via hinges ⑦).

Example: Booksize axis grouping comprising Control Unit (CU), Line Module (LM), and Motor Modules (MM) as well as drive in blocksize format comprising a Power Module (PM) with snapped on Control Unit (CU)

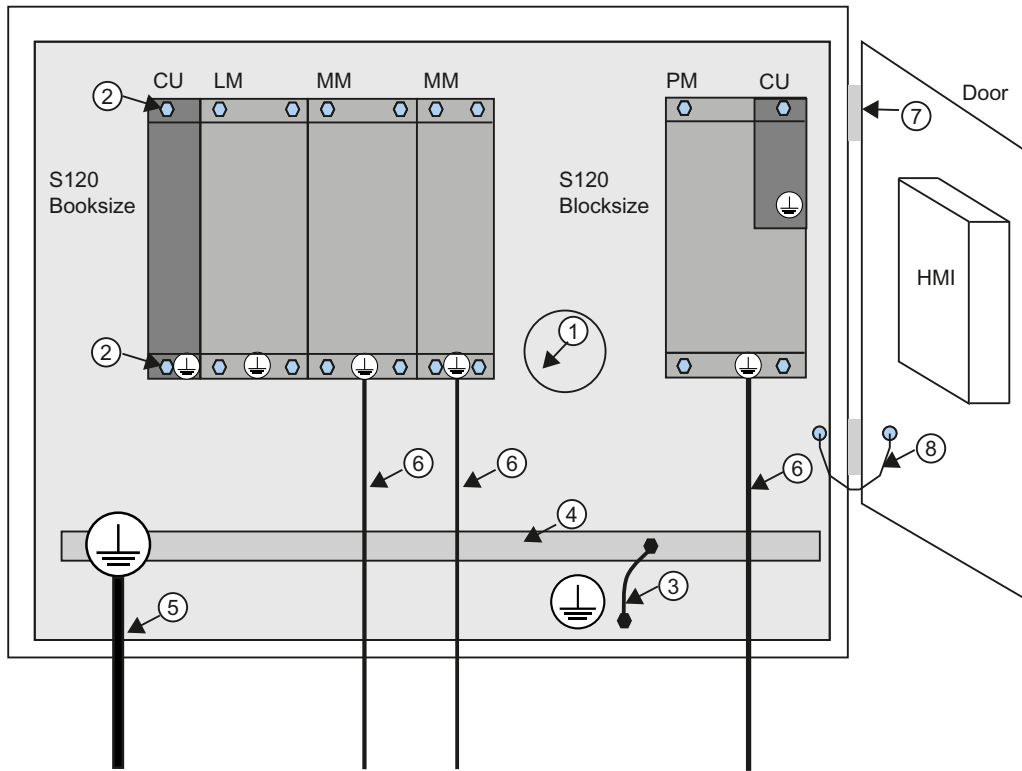


Figure 5-2 Protective conductor connection, cabinet with mounting plate / equipotential bonding surface

The protective conductor connections must be dimensioned as follows:

Table 5-1 Conductor cross-section for copper protective connections

Line supply cable in mm ²	Copper protective connections in mm ²
Up to 16 mm ²	The same as the line supply cable
From 16 mm ² to 35 mm ²	16 mm ²
From 35 mm ²	0.5 x line supply cable

For materials other than copper, the cross-section should be increased so that as a minimum, the same conductivity is attained.

Equipotential bonding

A mounting plate serves simultaneously as an equipotential bonding surface. This means that no additional equipotential bonding is required within the drive line-up. If a common bright mounting plate is not available, then equally good equipotential bonding (9) must be

established using cable cross-sections as listed in the table above or, as a minimum, with the same conductivity.

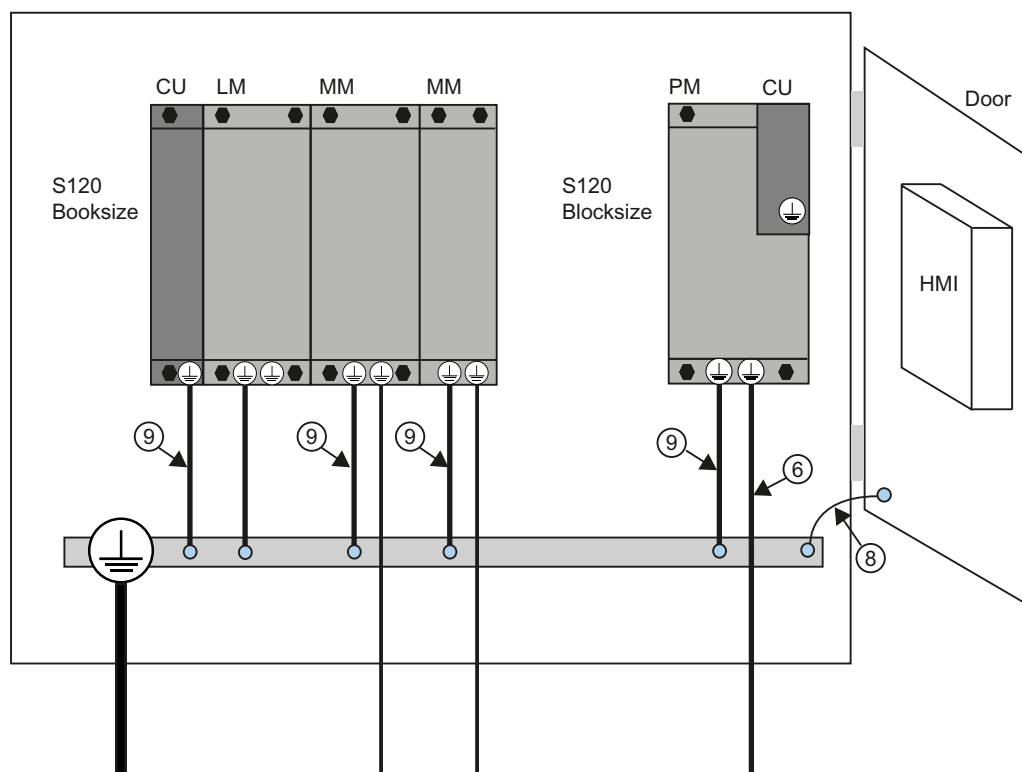


Figure 5-3 Protective conductor connection without equipotential bonding

Communication links

Within the same control cabinet, no equipotential bonding conductor is required for fieldbus components if they installed as described above.

You have to ensure equipotential bonding for communication connections between remote components in a system (e.g. devices in different control cabinets) as well as between buildings or building sections.

If, for example, data cables (PROFIBUS, PROFINET, Ethernet or DRIVE-CLiQ) are routed through several control cabinets, equipotential bonding must be established with an equipotential bonding conductor. Install the equipotential bonding conductor together with the data cable.

The following minimum cross-sections are required according to IEC 60364-5-54:

5.3 Opening the front cover

- For copper, at least 6 mm²
- For aluminum, at least 16 mm²
- For steel, at least 50 mm²

Note

If this is not observed, high leakage currents can flow through the cable. This can result in a fault in the data connection or device defects.

Due to the maximum length of 100 m for PROFIBUS copper cable at 12 Mbit/s or for PROFINET copper cable and due to the electrical isolation, EMC protection and equipotential bonding aspects, it is recommended that fiber-optic cables be used for connections between buildings.

Additional information

You will find more information on the protective connection and equipotential bonding in the following references:

- SINAMICS drive system: See the SINAMICS manuals
- PROFINET and PROFIBUS: See the following Internet address (<http://www.profibus.com>) (at Downloads)

5.3 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 56).

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.

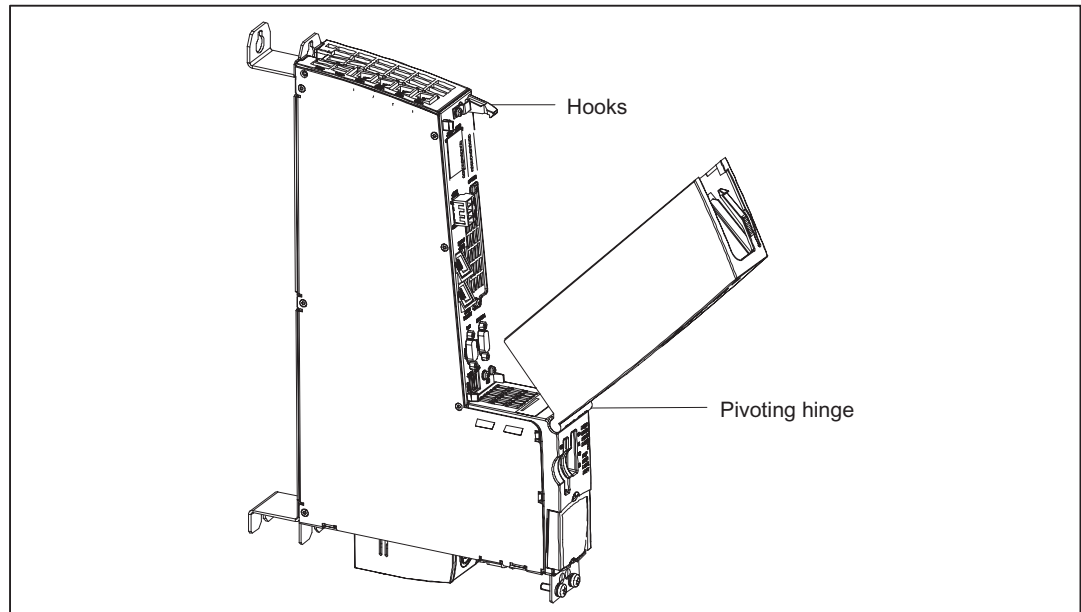


Figure 5-4 D4x5 with cover, figure similar for CX32

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.

5.4 Power supply

5.4.1 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 concept 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.

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 installing a system with SIMATIC ET 200 I/O (e.g. ET 200S, ET 200M, etc.), see the manuals for the relevant ET 200 I/O systems.
- As a further source of information on EMC, we recommend the configuration manual *EMC Installation Guidelines / Basic System Requirements*, order number 6FC5297-0AD30-0AP3.

5.4.2 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.

5.4.3 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	

Protection against external electrical phenomena

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

Table 5-2 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.

Additional references

The same installation instructions apply for the SIMOTION D4x5/CX32 Control Units as for the SINAMICS S120 CU320 Control Units with regard to EMC. See the SINAMICS manuals.

5.4.4 Connecting the power supply

Wiring the screw-type terminal block

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



WARNING

Danger to life from hazardous voltage when connecting an unsuitable power supply

Implement the 24 V DC supply with protective separation as protective extra-low voltage.

Supply system lines

Use flexible cables with a cross section of 0.25 to 2.5 mm² (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.

5.5 Connecting DRIVE-CLiQ components

5.5.1 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.

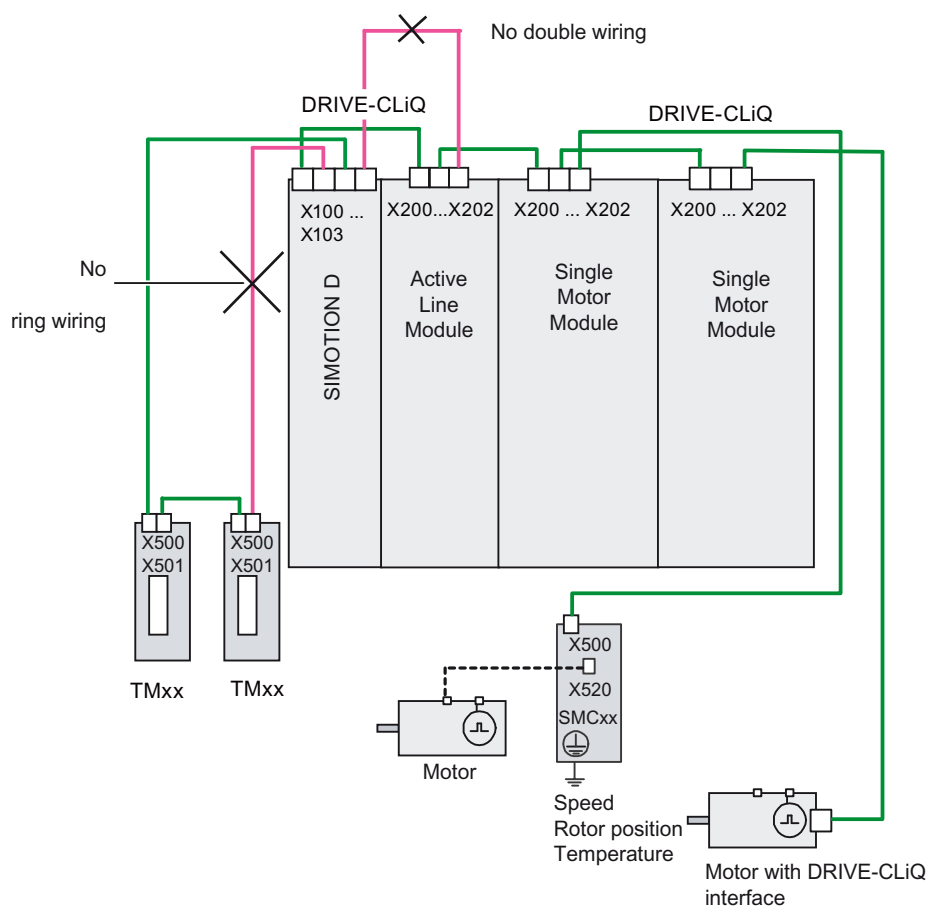


Figure 5-5 DRIVE-CLiQ wiring (example)

5.5.2 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 5-3 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/faxes.
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. <ul style="list-style-type: none"> • 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.
DMC20/DME20	DRIVE-CLiQ hubs provide 4 more DRIVE-CLiQ interfaces. They can be used, for example, to establish star topologies. <ul style="list-style-type: none"> • 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 (with CUA31/CUA32)	An AC DRIVE PM340 power module can be connected using the CUA31/ CUA32 control unit adapter. You will find more information on the CUA31/CUA32 in the <i>SINAMICS S120 AC Drive Manual</i> .

Example of axis assembly

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

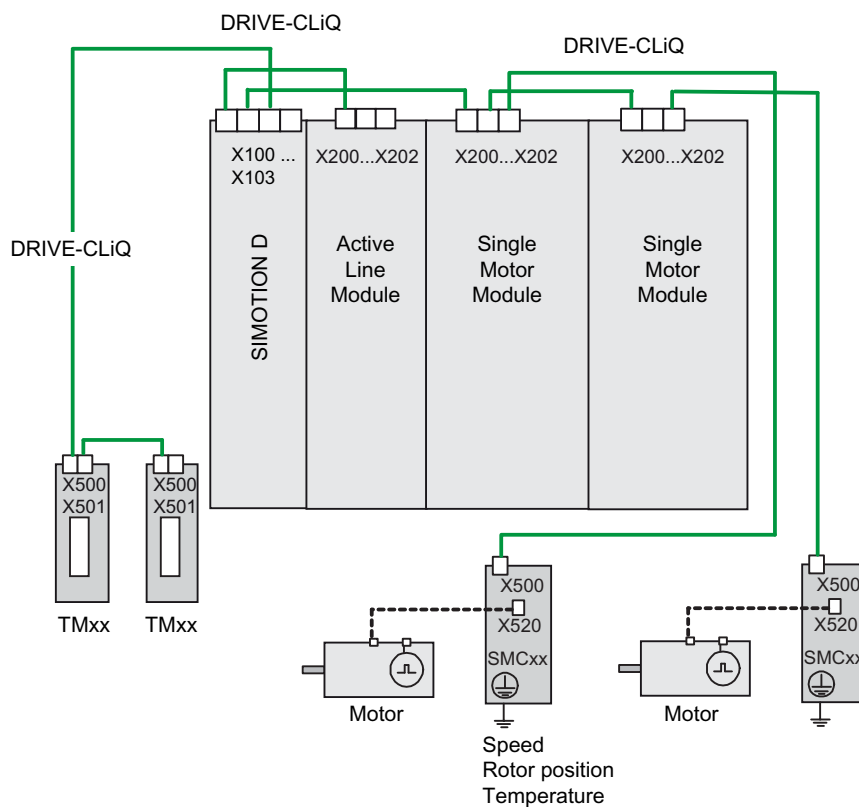


Figure 5-6 Axis assembly with DRIVE-CLiQ

5.5.3 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 into 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 190)). 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.
CX32-2 can only be operated on SIMOTION D4x5-2, but not on D435 or D445/D445-1.

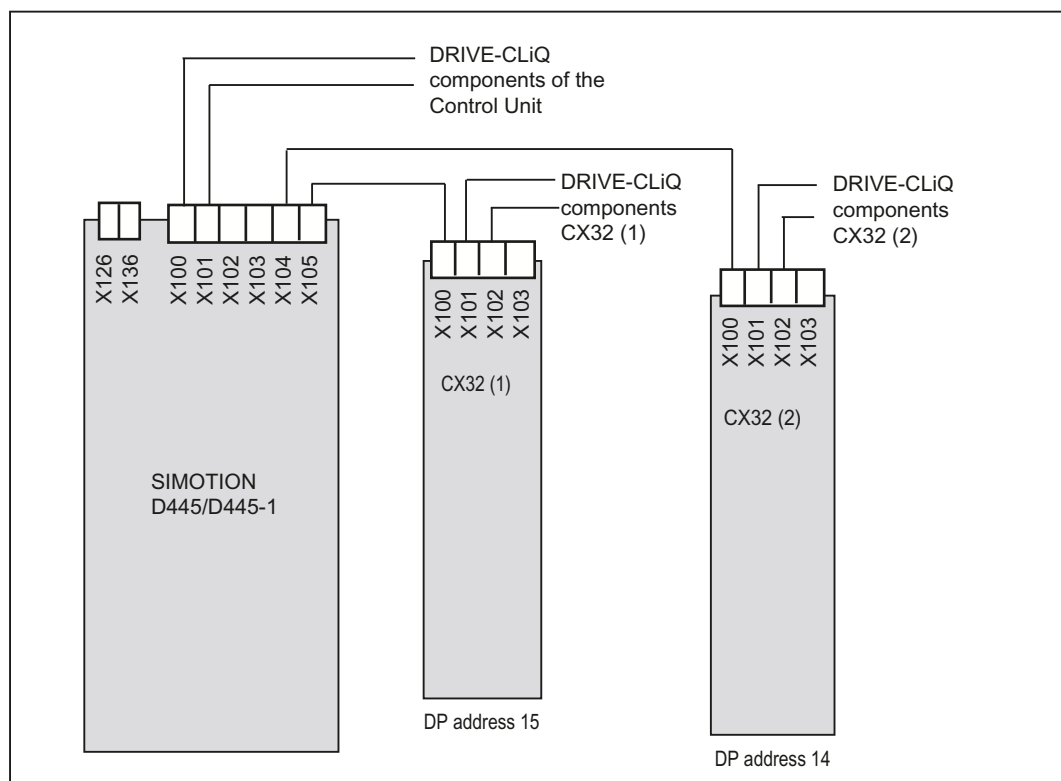


Figure 5-7 CX32 topology

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 5-4 Quantity 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.

SIMOTION V4.0 HF2/SINAMICS V2.4

5.6 Connecting inputs/outputs

Table 5-5 Quantity structure for 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	---

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.

5.6 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 a maximum of 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".

5.6.1 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. To do so, lay the cable shield bare on the cable.
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 (M3 screw, Torx T10).
2. Insert the cable. To do so, firstly lay the cable shield bare.
3. Fasten the fixing bracket in such a way that the cable shield and cable are pressed against the device housing by the fixing bracket (tightening torque 0.8 Nm).

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.

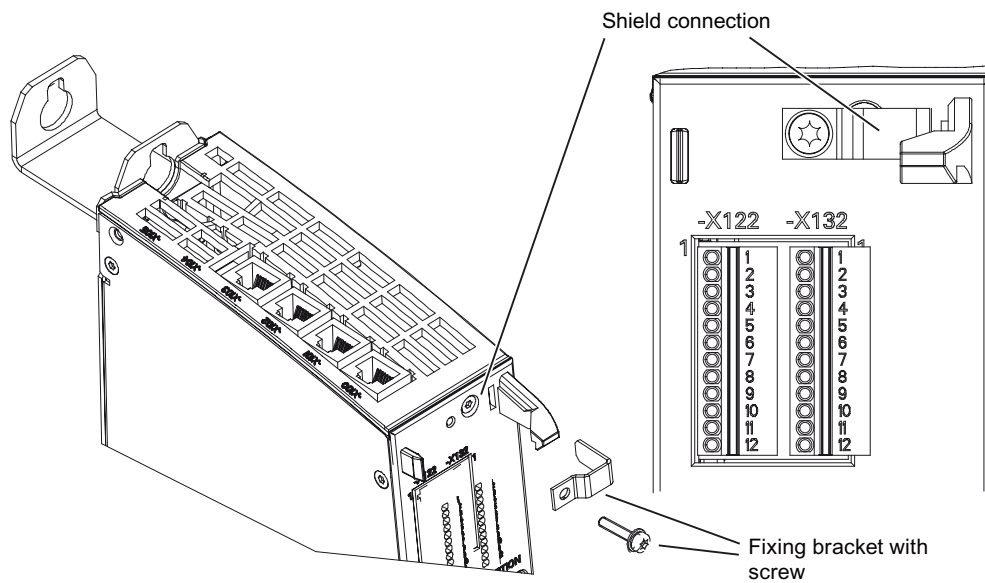


Figure 5-8 D4x5 shield connection

5.6.2 Connecting inputs/outputs of the TB30

Pin assignment

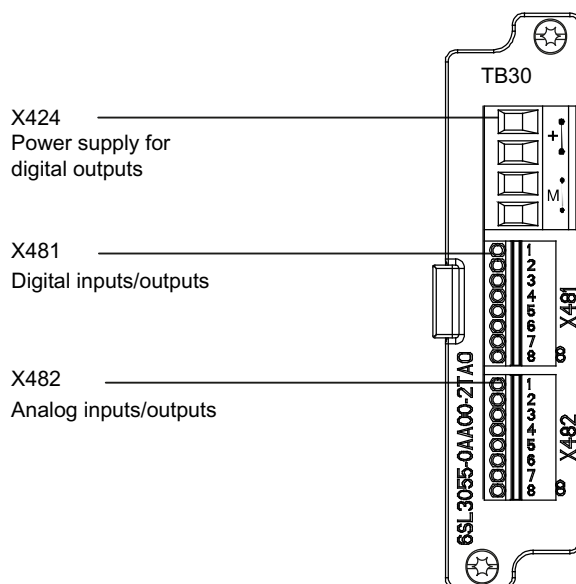


Figure 5-9 Interface arrangement on the TB30

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.

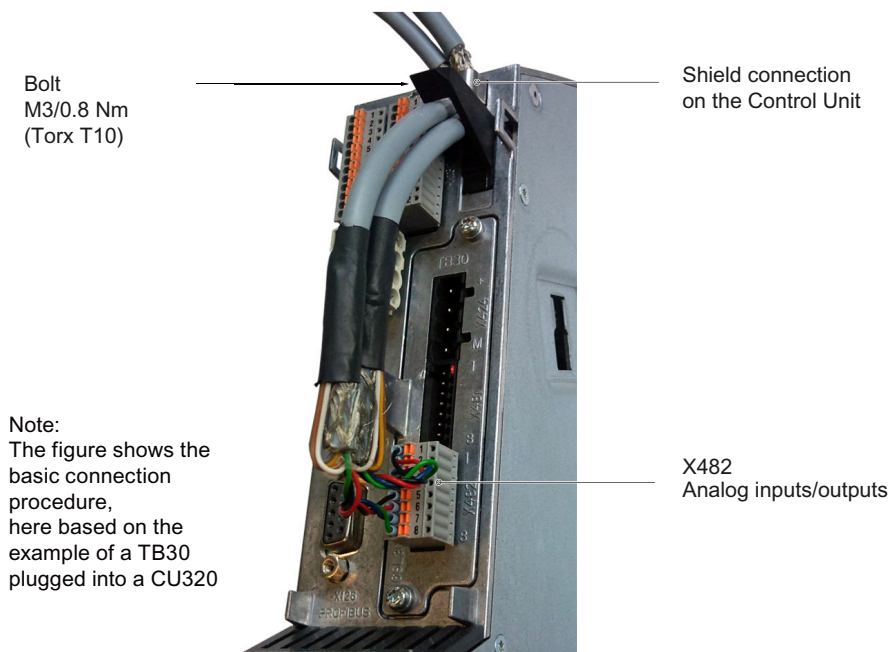


Figure 5-10 TB30 shield connection

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

5.7 Connecting PROFIBUS/MPI

5.7.1 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.

5.7.2 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 5-6 Properties of PROFIBUS cables

Characteristics	Values
Wave impedance	Approximately 135 to 160 Ω (f = 3 to 20 MHz)
Loop resistance	$\leq 115 \Omega/\text{km}$
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

SIMOTION D4x5 Manual, Available spare parts and accessories Section

5.7.3 PROFIBUS cable lengths

Cable lengths and baud rate

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

Table 5-7 Permitted cable length of a subnet segment for specific 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.

5.7.4 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 5-8 Boundary conditions for routing of PROFIBUS cables

Characteristics	Boundary conditions
Bending radius for a single bend	80 mm (10xdA)
Bending radius for multiple bends	160 mm (20xdA)

Characteristics	Boundary conditions
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)

5.7.5 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 5-11 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.

NOTICE

Disturbance of data traffic on the bus due to missing bus terminator

A bus segment must be terminated at both ends with a terminating resistor. This is not the case if the last bus connector node is de-energized, for example. Because the bus connector takes its voltage from the station, this terminating resistor is ineffective.

Make sure that the stations at which the terminating resistor is connected are always energized.

5.7.6 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.

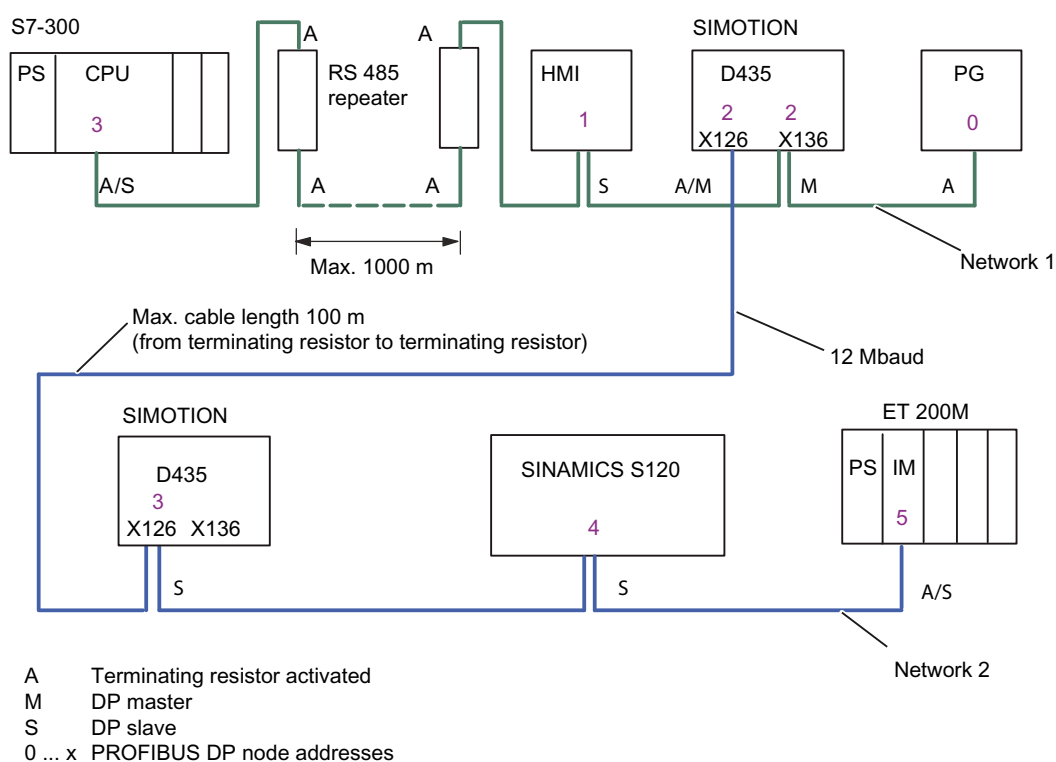


Figure 5-12 Networking example for a D435

5.7.7 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 Available spare parts and accessories*

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.
- 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 79)

PROFIBUS cable lengths (Page 80)

5.8 Connecting PROFINET IO components

5.8.1 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.

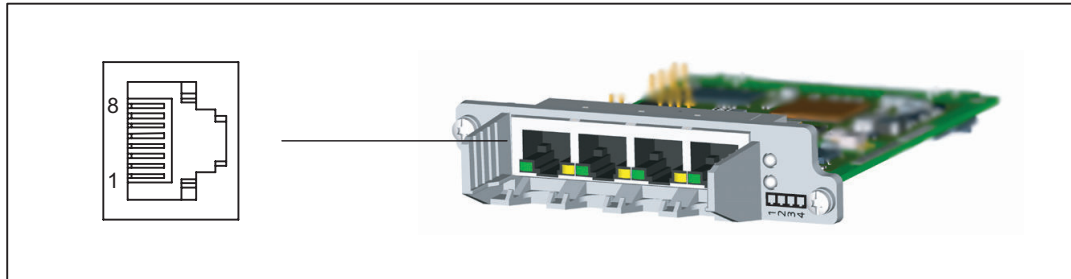


Figure 5-13 Connections on the CBE30

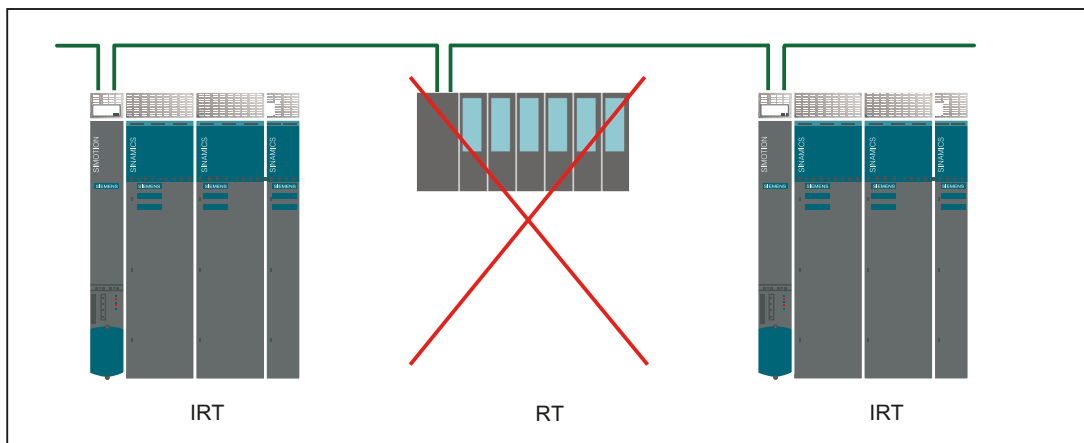
Note

CBE30 can only be used in SIMOTION D4x5 Control Units.

CBE30-2 can only be used in SIMOTION D4x5-2 Control Units.

Mixed operation of IRT and RT

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



5.8.2 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 5-14 RJ45 PN connector with a 145° cable outlet

Table 5-9 Connector types for PROFINET

Connectors	Designation	Order No.
IE FC RJ-45 Plug 145	RJ45 FastConnect connector for Industrial Ethernet/PROFINET with 145° cable outlet <ul style="list-style-type: none"> • 1 package = 1 unit • 1 package = 10 units 	6GK1 901-1BB30-0AA0 6GK1 901-1BB30-0AB0

Table 5-10 Cable types for PROFINET

Cable	Designation	Order No.
IE FC Cable GP 2x2 (Type A)	4-wire, shielded TP installation cable for IE FC RJ45	6XV1 840-2AH10
IE FC Flexible Cable GP 2x2 (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 5-11 Stripping tool for Industrial Ethernet / PROFINET

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

Note

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

5.9 Routing

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

5.9.1 Routing on SIMOTION D

Routing between the different interfaces

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

- IP routing from IP subnet to IP subnet is not supported. You can use an external IP router for this.
- S7 routing between PROFINET/Ethernet subnets and also to PROFIBUS is supported.

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)

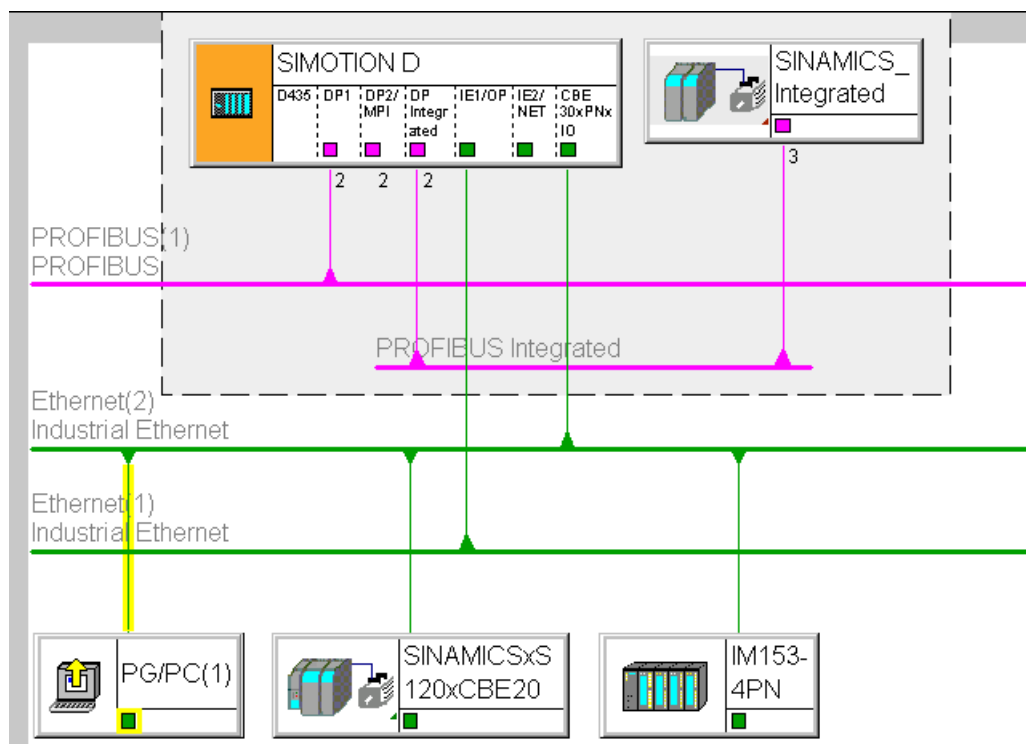


Figure 5-15 Example for PG/PC to CBE30

- 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

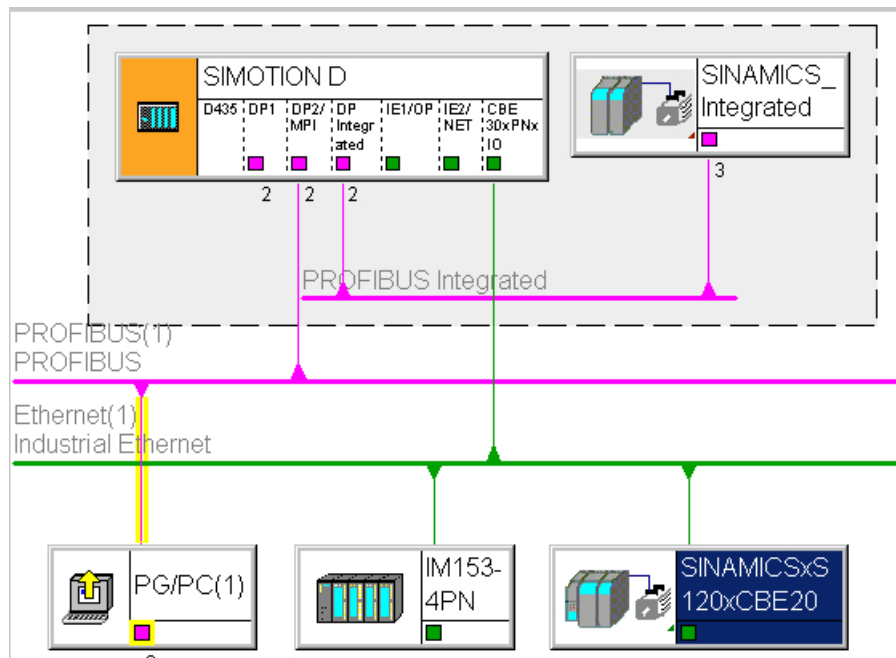


Figure 5-16 Example for PG/PC to PROFIBUS

- 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

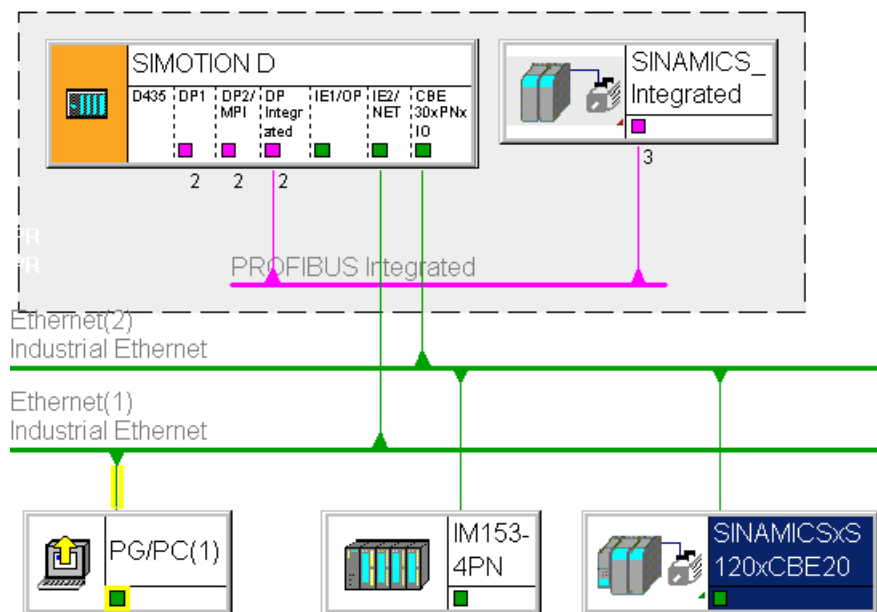


Figure 5-17 Example for PG/PC to Ethernet X120, X130

- 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

5.9.2 Routing on SIMOTION D (SINAMICS integrated)

S7 routing to the internal PROFIBUS on SINAMICS Integrated

All SIMOTION D have an integrated SINAMICS drive control. To be able to access drive parameters, the telegrams 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

You will find more information about routing and the differences between IP and S7 routing in the *SIMOTION Communication System Manual*.

5.10 Connecting Ethernet

5.10.1 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.

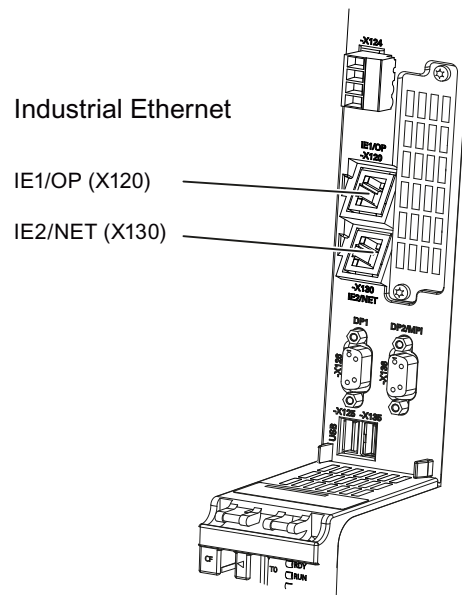


Figure 5-18 Connecting Industrial Ethernet

5.10.2 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□□□ (□□□ - length code)
- SIMATIC NET, Industrial Ethernet TP CORD RJ45/RJ45
 - TP cable prefabricated with 2xRJ45 connectors
 - Uncrossed send and receive cable
 - Order No.: 6XV1870-3Q□□□ (□□□ - length code)

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.

Commissioning (hardware)

6.1 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 95)
2. Checking the system (Page 98)
3. Switching on the power supply (Page 98)

Additional references

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

6.1.1 Inserting the CompactFlash card

Characteristics 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.

6.1 Requirements for commissioning

To load the SIMOTION Kernel, the CF card must be inserted when the SIMOTION D4x5 is powered up.

NOTICE

Damage to the CompactFlash card from electrical fields or electrostatic discharge

The CompactFlash card is an ESD-sensitive component.

De-energize the SIMOTION D4x5 device before inserting or removing the CompactFlash card. SIMOTION D4x5 is in a de-energized state when all the LEDs are OFF.

Comply with the ESD rules.

Procedure

To insert the CF card, perform the following steps:

1. The direction of insertion of the CF card is indicated by an arrow located on both the plug-in 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.

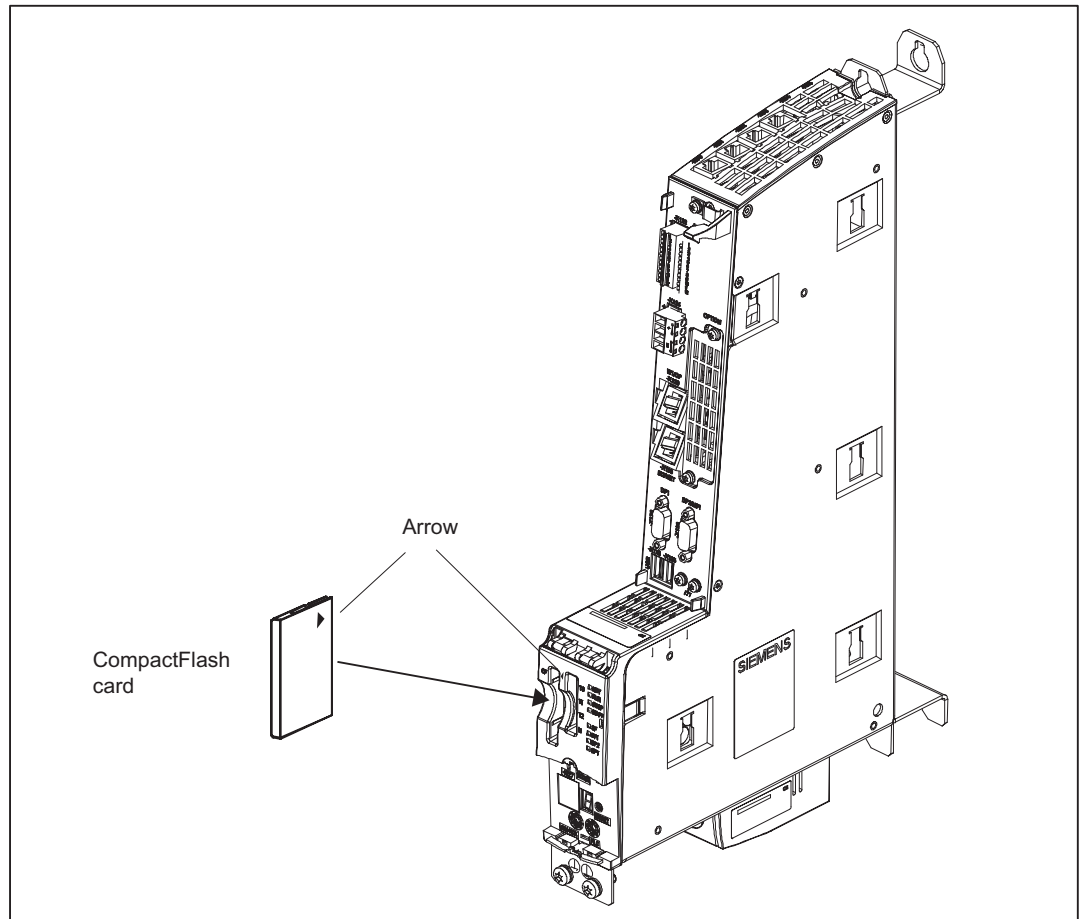


Figure 6-1 Inserting the CF card

See also

Changing the CompactFlash Card (Page 314)

6.1.2 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?

Note

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

6.1.3 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.

NOTICE
SIMOTION D4x5 shuts down if the power supply is interrupted
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.
Additional information is available in Section Properties of the user memory (Page 102).

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. Startup of the SIMOTION Kernel.

3. 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 firmware version on the CF card and the firmware 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:

A firmware update on DRIVE-CLiQ components is indicated by the RDY LED flashing red/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 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.

4. The first time it is energized, the SIMOTION D4x5 goes to STOP mode following power-up. 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.

NOTICE
SIMOTION D445 enters the reset state
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.

NOTICE

SIMOTION D445-1 enters the reset state

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.

6.2 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.

6.3 User memory concept

6.3.1 SIMOTION D4x5 memory model

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

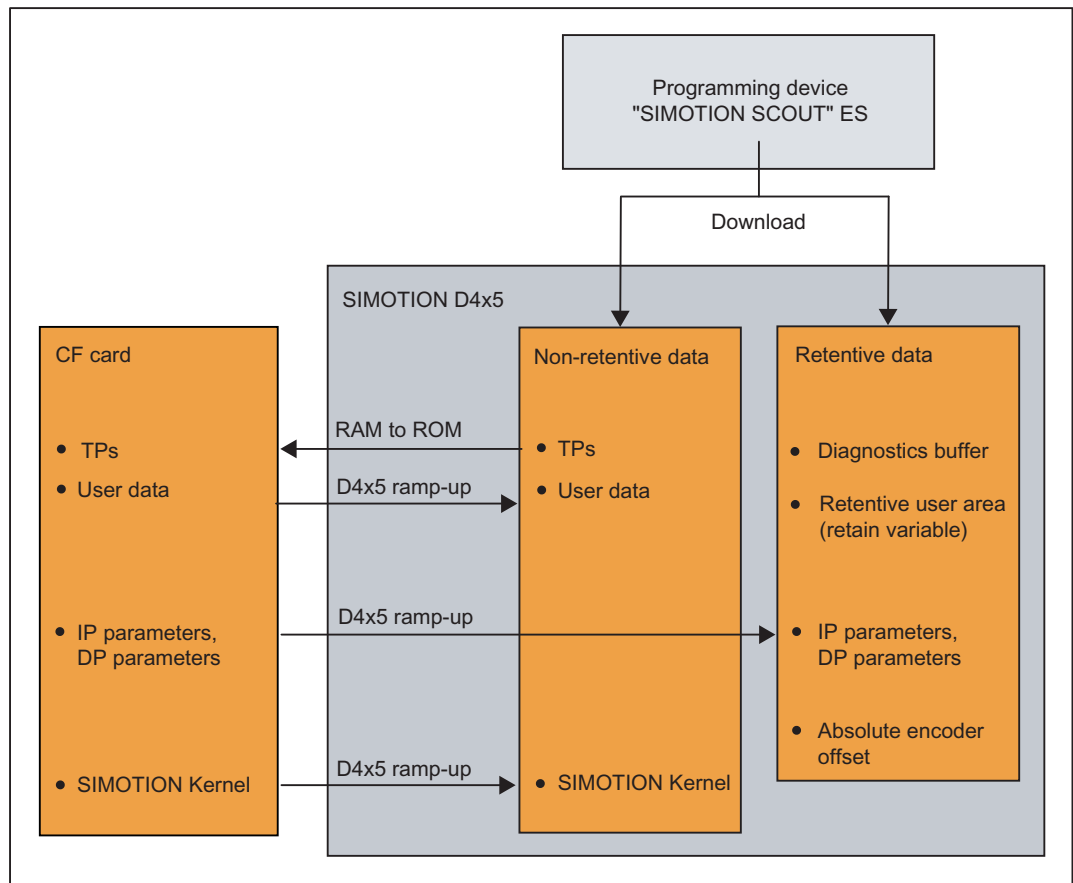


Figure 6-2 SIMOTION D4x5 memory model

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 sections you will find information about the user memories and the steps involved in certain operations.

6.3.2 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:

Table 6-1 Non-volatile data contents

Non-volatile data	Content
Kernel data	<ul style="list-style-type: none"> • Last operating mode • IP parameters (IP address, subnet mask, router address) • DP parameters (PROFIBUS DP address, baud rate) • Diagnostic buffer
Retain variables	<ul style="list-style-type: none"> • 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)

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 SIMOTION 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 more information on DCC, see the DCC Programming Programming Manual.

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

Table 6-2 Non-volatile data properties

Characteristic	Meaning
City:	<p>The non-volatile data is in the SIMOTION D SRAM. The following backup options are available:</p> <ul style="list-style-type: none"> • 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 (<code>_savePersistentMemoryData</code>)
Backup time:	<ul style="list-style-type: none"> • SuperCap: 5 days, minimum • Battery: At least 3 years

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 when a battery is used 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 SIMOTION data (RAM / current data RAM)

The volatile SIMOTION data is defined by the following properties:

- The volatile SIMOTION data is located in the RAM memory of the SIMOTION device.
- The download data of SIMOTION SCOUT is written to this memory.
- This data is lost with the SIMOTION D4x5 is switched off.
- The "volatile SIMOTION data" area contains the following data:
 - SIMOTION Kernel (D4x5 firmware)
 - Technology packages (TP)
 - User data (programs, configuration data, parameter settings)

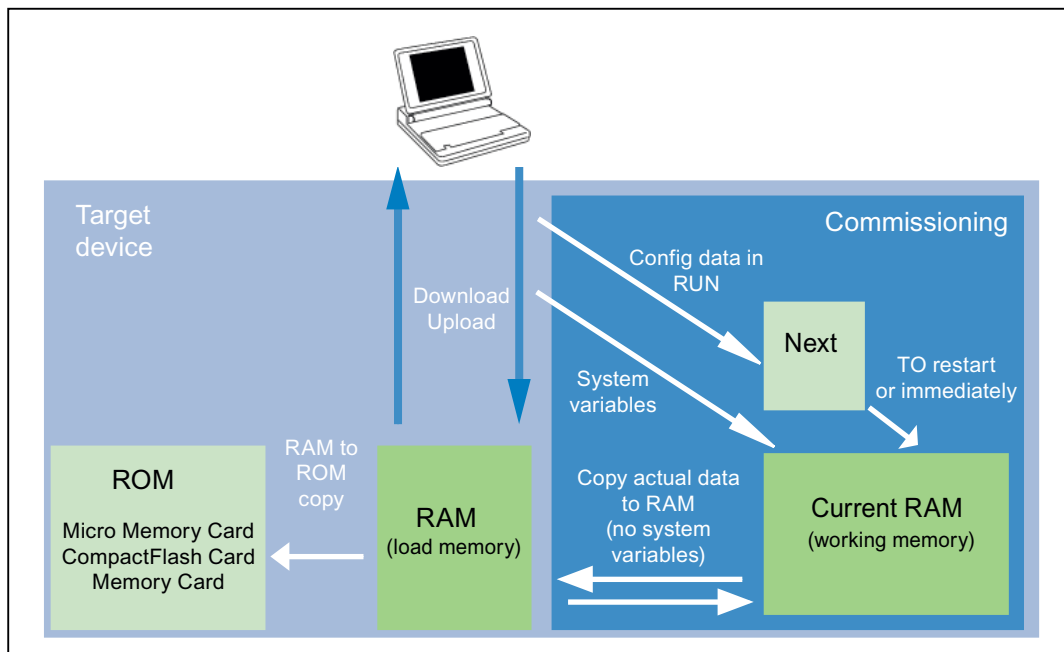


Figure 6-3 Configuration data and system variables in the volatile memory

You can find additional information about memory management in SIMOTION in the *SIMOTION Runtime Basic Functions* Function Manual.

CompactFlash card (CF card)

The CF card contains 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.

6.3.3 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 following data are transferred with "Download project to target system" or "Download CPU / drive unit to target device" from the engineering system to the "volatile SIMOTION 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 SIMOTION 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 SIMOTION data will be 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, parameter assignments, task configuration) from the "volatile SIMOTION data" area
- Current values are copied to the "volatile SIMOTION 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 purpose.

Note

The "Copy RAM to ROM" function is also available for drive units and saves the volatile SINAMICS data to the non-volatile memory (CF card).

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 take immediate effect are 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 value ACTIVATE_RESTART) are only written to the current RAM once the RESTART has taken place.

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.

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

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

The SIMOTION Kernel is loaded from the CF card to the "volatile SIMOTION data" area when the SIMOTION D4x5 is powered up.

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

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

Backing up non-volatile SIMOTION data

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

- In the user program:
with the **_savePersistentMemoryData** system function, the user program can back up the non-volatile SIMOTION data content to the CF card. This backs up the retain variables and the absolute encoder position.
The data are saved to the PMEMORY.XML backup file in the "USER\SIMOTION" directory.
- Using a switch position (SIMOTION D4x5 service selector switches) or the SIMOTION IT web server. See Section Diagnostic data and non-volatile SIMOTION data (Page 329). The contents are saved to the "PMEMORY.XML" backup file in the "USER\SIMOTION\HMI \SYSLOG\DIAG" directory.

On the system side, this system function ensures that a consistent overall image of the non-volatile SIMOTION data is always available the next time the unit is switched on, even if there is a power failure during backup. An already existing backup file is renamed to "PMEMORY.BAK" before a new backup file is generated. 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 SIMOTION data content. If the new file is successfully created, the backup copy of the backup file is deleted.

NOTICE

Loss of data due to failure to make backup copies

Non-backed-up non-volatile SIMOTION data can be lost on hardware replacement (module defect), for example, if the current value of the retain variables have not been backed up and replaced by their initial values again.

Back up the non-volatile SIMOTION data on the CF card.

NOTICE

Repeat referencing necessary after absolute encoder overflow

If an absolute encoder overflow occurs after **_savePersistentMemoryData**, the actual position value is no longer correct after the non-volatile SIMOTION data are restored.

In this case, homing (absolute encoder adjustment) must be repeated.

With the SCOUT functions "Save 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.

Restoring non-volatile SIMOTION data

SIMOTION data backed up on a CF card with **_savePersistentMemoryData** are restored in the following cases:

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 285)

6.3 User memory concept

3. After a memory reset, see Section SIMOTION D4x5 memory reset (Page 266)
4. by switch setting, see Section Deleting/restoring non-volatile SIMOTION data (Page 336).

If you want to restore data backed up via switch/web server, you may have to delete existing PMEMORY.XML and PMEMORY.BAK backup files in the \USER\SIMOTION\ directory on the CF card. See also Section Deleting/restoring non-volatile SIMOTION data (Page 336).

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 are available again the next time the unit is powered up. Thus, the control unit is immediately operational without data loss.

Power-up and non-volatile SIMOTION data

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

Table 6-3 Power-up scenarios for non-volatile SIMOTION data

Case	Initial condition	Result
1	The non-volatile SIMOTION data are valid.	SIMOTION D4x5 powers up with the non-volatile SIMOTION data, meaning, for example, that the PROFIBUS address in the non-volatile data is valid.
2	The non-volatile SIMOTION data are 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 SIMOTION data and powers up with this data. In this case, for example, the default PROFIBUS address is used.
3	The non-volatile SIMOTION data are invalid and the backup file (PMEMORY.XML) exists and has valid content.	SIMOTION D4x5 copies the backup file contents to the non-volatile SIMOTION data and powers up with this data.
4	The non-volatile SIMOTION data are 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 SIMOTION data and powers up with this data, in which case, for example, the default PROFIBUS address is used.
5	The non-volatile SIMOTION data are 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 SIMOTION data and powers up with this data.

Non-volatile SIMOTION data diagnostics

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

Evaluating via the diagnostic buffer

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

Table 6-4 Messages of the diagnostic 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 SIMOTION data has been successfully restored from the backup file on the CF card.	-
Non-volatile data loaded from the backup file (Persistent Data Backup File Loading done)	Non-volatile SIMOTION 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 could not be loaded. Possible causes: <ul style="list-style-type: none"> • Backup file or backup copy not available • Invalid data in backup file 	Use the <code>_savePersistentMemoryData</code> system function to generate a backup file with valid contents.
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 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

You will find detailed information on setting up Taskstartinfo (#TSI) in the *SIMOTION Runtime Basic Functions* Function Manual.

Evaluating via system variables

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

Table 6-5 Status of the non-volatile SIMOTION data and 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.
rtcFailure (as of V4.3)	Indicates that the clock contents (RTC) are invalid (clock must be set again)	NO (91) YES (173)	Is updated once during power-up; status must be reset to "NO" via the application; the status is retained even after power off/on.
retainDataFailure (as of V4.3)	Indicates a checksum error in the non-volatile SIMOTION data;	NO (91) YES (173)	Is updated once during power-up; status must be reset to "NO" via the application; the status is retained even after power off/on.
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

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).

The system variable **device.persistentDataPowerMonitoring.powerFailure = YES** indicates that the buffer voltage of the SuperCap or the battery was too low after switching on.

This may have led to a loss of non-volatile SIMOTION data and to a loss of the date/time.

In the event of **powerFailure = YES**, the non-volatile SIMOTION data (where present) is downloaded from the CF card.

As of SIMOTION V4.3, a data loss of the real-time clock is signaled via the system variable **device.persistentDataPowerMonitoring.rtcFailure = YES**. In addition to this, checksum errors in the non-volatile SIMOTION data are indicated in the system variable **device.persistentDataPowerMonitoring.retainDataFailure = YES**.

Note

retainDataFailure = YES and **powerFailure = NO** can simultaneously be an indication of hardware faults

The **device.persistentDataPowerMonitoring.persistentDataState** system variable indicates the state of the non-volatile SIMOTION data after power-up.

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

State	Meaning
FROM_RAM (1)	Non-volatile SIMOTION data in the SIMOTION device is used
FROM_FILE (2)	Non-volatile SIMOTION data are restored from the backup file
FROM_BACKUP (3)	Non-volatile SIMOTION data are restored from the backup copy of the backup file
INVALID (4)	Data in the non-volatile SIMOTION 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 SIMOTION data and used this data to power up.

Requirement for/presence of the battery (from 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 present (or not)

Table 6-7 System variable batterynecessary/batteryexisting

System variable on the device	States	Description
fanbattery of data type StructDeviceFanBattery (the system variables are of the data type EnumFanBattery)		
.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 installed.
	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 installed. Example: D4x5

6.4 Fan

System variable on the device	States	Description
	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 installed. Example: D4x5-2
	NOT_MANDATORY ¹⁾	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: <ul style="list-style-type: none"> • MANDATORY or • OPTIONAL or • OPTIONAL_RTC and a battery is installed.
	NOT_EXISTING	Battery is not installed

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

6.4 Fan

6.4.1 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.

Table 6-8 Fan/battery module for SIMOTION D4x5

Characteristic	SIMOTION D425	SIMOTION D435	SIMOTION D445	SIMOTION D445-1
Fan/battery module	Optional	D435 with order no. 6AU1 435-0AA00-0A A1: Optional D435 with order no. 6AU1435-0AA00-0A A0: Required for supply air temperatures of 43° C and above	Always required	Always required

Characteristic	SIMOTION D425	SIMOTION D435	SIMOTION D445	SIMOTION D445-1
Fan/battery module included in the scope of delivery of the D4x5	--	--	Fan/battery module (single fan) with order no. 6FC5348-0AA01-0AA0	Double fan/battery module with order no. 6FC5348-0AA02-0AA0
Fan/battery modules which can be used in principle	Only type 6FC5348-0AA01-0AA0 (single fan)	Only type 6FC5348-0AA01-0AA0 (single fan)	Only type 6FC5348-0AA01-0AA0 (single fan)	Type 6FC5348-0AA01-0AA0 (single fan) and type 6FC5348-0AA02-0AA0 (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)

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 115).

6.4.2 Fan/battery module on the D425/D435

Operation without fan

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 at power on, a warning will be output by variable **device.CpuDataRW.fanwarning**.

6.4 Fan

In the absence of a fan/battery module at power 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).

Operation with fan

Operation with fan enables improved heat dissipation from the Control Unit as a result of forced convection.

In the event of fan failure, the module will behave as if operated without a fan.

I.e. the module will continue to operate as long as an overtemperature is not reported. In the event of overtemperature (temperature threshold 2 exceeded), the control switches to FAULT status (7-segment display shows "F", all LEDs flickering red). The state can only be exited by POWER on/off.

6.4.3 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 also guarantees sufficient cooling with just one functional fan.

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 the 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.

6.4.4 Overview of states, fan/battery module

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

Table 6-9 Overview of states

State	Fan ⁴⁾	PeripheralFaultTask	System variables ³⁾	
		Diagnostic buffer entry		
<code>_cpuDataRW.fanWarning</code>	<code>_cpuDataRW.redundantfanWarning</code> 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

6.4 Fan

State	Fan ⁴⁾	PeripheralFaultTask	System variables ³⁾	
		Diagnostic buffer entry		
Failure of one fan during RUN	Single 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
	Double fan	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

- 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**.

Diagnostic buffer entry

The diagnostic 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 (this is only the case for D445-1)

Requirement for/presence 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 installed (or not)

Table 6-10 System variable `fannecessary/fanexisting`

System variable on the device	States	Description
fanbattery of data type StructDeviceFanBattery (the system variables are of the data type EnumFanBattery)		
<code>.fannecessary</code>	MANDATORY	Fan is required for operation of the device. <code>.fanexisting</code> can be used to query whether a fan is installed. Examples: D410, D445, D445-1, D445-2 DP/PN, D455-2 DP/PN
	OPTIONAL	Fan can be used optionally. <code>.fanexisting</code> can be used to query whether a fan is installed. Examples: D425, D435
	NOT_MANDATORY	Fan is not required for operation of the device.
<code>.fanexisting</code> ¹⁾	SINGLE	A single fan is installed Examples: D410, D4x5
	REDUNDANT	Double fan is installed. Examples: D445-1, D445-2 DP/PN, D455-2 DP/PN
	NOT_EXISTING	No fan is installed. Example: D425 without optional fan

¹⁾ Value for SIMOTION D4x5 is updated dynamically

References

You will find detailed information on setting up `TaskStartInfo(#TSI)` in Function Manual *SIMOTION Runtime Basic Functions*.

6.4.5 Response to overtemperature

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

Causes

Cause 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

Table 6-11 Response of the temperature monitoring (as of V4.2)

Temperature...	Response
... exceeds the 1st temperature threshold (overtemperature)	Call of the PeripheralFaultTask: <ul style="list-style-type: none"> • TSI#InterruptId = _SC_PC_INTERNAL_FAILURE (= 205) • TSI#details = 16#00000002 Diagnostic buffer entry: "Temperature exceeded in the housing"
... falls below the 1st temperature threshold minus a hysteresis of approx. 5° C	Call of the PeripheralFaultTask: <ul style="list-style-type: none"> • TSI#InterruptId = _SC_PC_INTERNAL_FAILURE (= 205) • TSI#details = 16#00000004 Diagnostic 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) Diagnostic buffer entry (as of V4.3): "Temperature in the housing too high, self-protection function of the module activated"

References

You will find detailed information on setting up Taskstartinfo (#TSI) in the *SIMOTION Runtime Basic Functions* Function Manual.

Parameter assignment / addressing

7.1 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.

Note

The software configuration is described in this manual based on SIMOTION SCOUT and SIMATIC STEP 7 Version V5.x.

The Engineering Framework Totally Integrated Automation Portal (SCOUT in the TIA Portal) only supports the newer SIMOTION D4xx-2 Control Units. Configuration of the SIMOTION D4xx Control Units in the TIA Portal is not possible.

7.2 Creating a project and configuring communication

7.2.1 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.

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

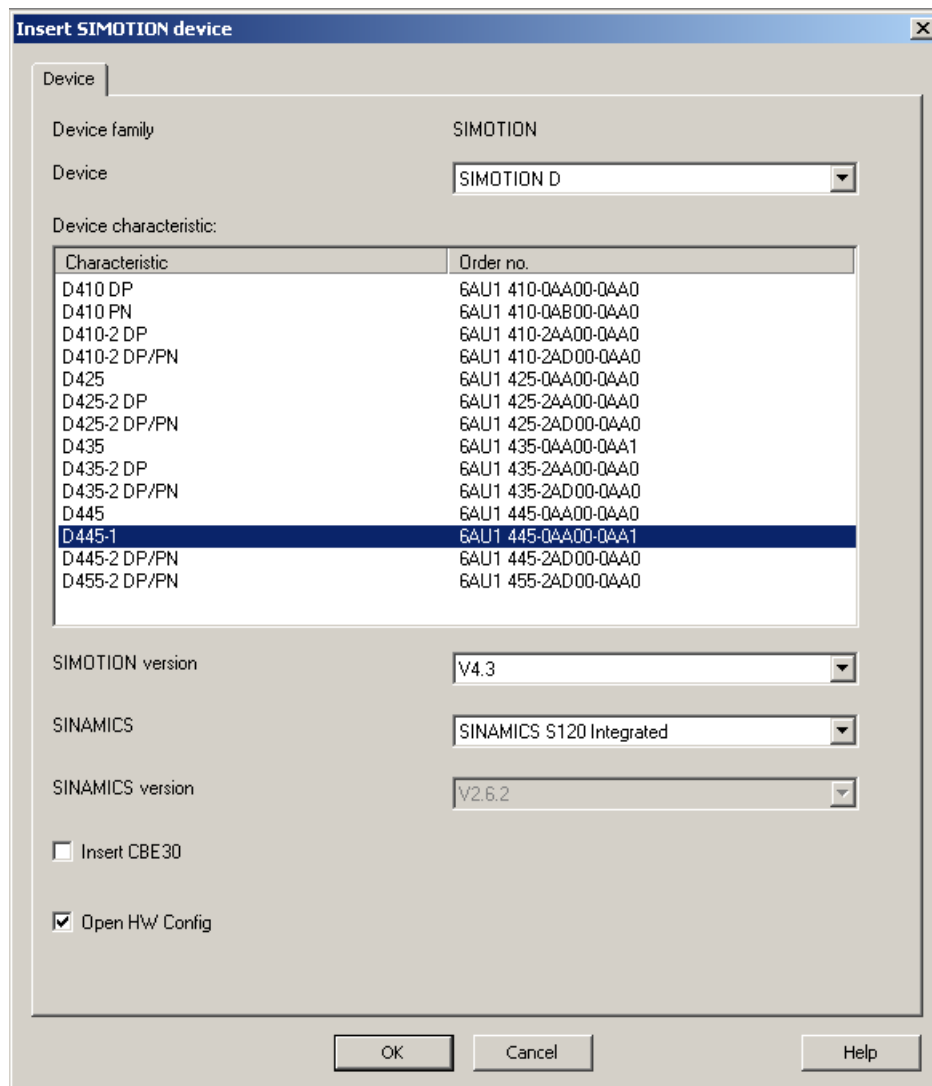


Figure 7-1 Inserting a SIMOTION device

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
 - Inserting CBE30: 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 special circumstances (e.g. for existing systems) PROFINET version V2.1 can also 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.

7.2.2 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 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 box.

Proceed as follows to configure the PROFIBUS DP interface:

Procedure

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

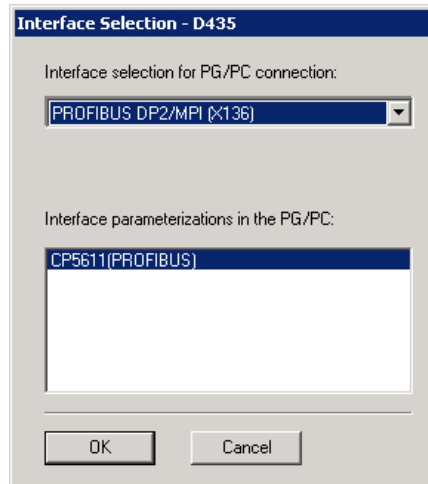


Figure 7-2 Selecting a PROFIBUS interface

2. Confirm with "OK".

The dialog box 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" > "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 are supplied with SIMOTION SCOUT.

See also

Establishing a PG/PC assignment (Page 136)

7.2.3 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 box.

Proceed as follows to configure the Ethernet interface:

Procedure

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

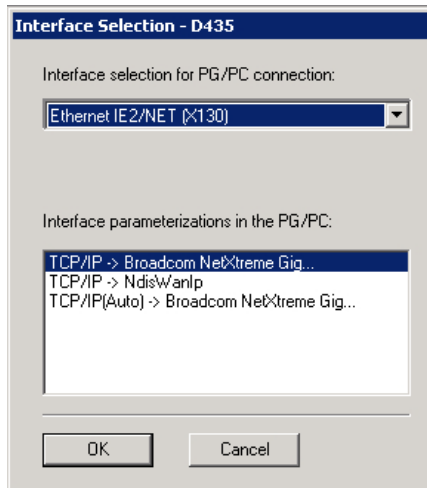


Figure 7-3 Configuring an Ethernet Interface

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

The dialog box 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 138).)

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" > "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, "Online connections to SIMOTION devices" FAQ
SIMOTION Utilities & Applications are supplied with SIMOTION SCOUT.

See also

Establishing a PG/PC assignment (Page 136)

7.2.4 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.

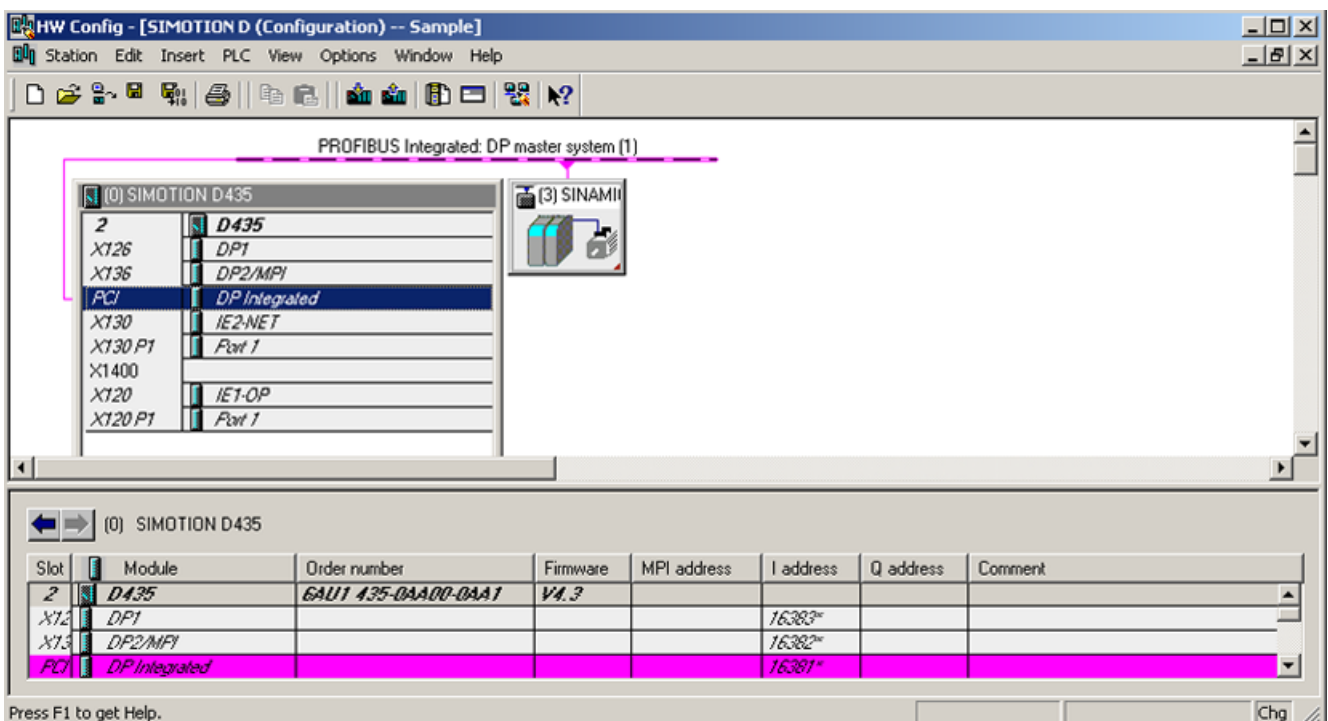


Figure 7-4 Representation of SIMOTION D4x5 in HW Config

7.3 Configuring PROFIBUS DP

7.3.1 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 82)

7.3.2 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 7-1 Master-slave configuration

X126	X136	Note	Actions in the application
DP slave, isochronous	DP master, isochronous	Application synchronized to DP master (X136), application controls synchronization to DP slave (X126) Internal drive is synchronous with external cycle clock Cycle clock DP-136 = cycle clock DP Integrated	DP master/DP slave synchronization mechanisms
DP master, isochronous	DP slave, isochronous	Application synchronized to DP master (X126), application controls synchronization to DP slave (X136) Internal drive is synchronous with external cycle clock Cycle clock DP-126 = cycle clock DP Integrated	DP master/DP slave synchronization mechanisms
DP slave, isochronous	DP master, 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 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

7.3 Configuring PROFIBUS DP

X126	X136	Note	Actions in the application
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
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.

7.3.3 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 82)

7.3.4 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.

7.3 Configuring PROFIBUS DP

Table 7-2 Range of values for SIMOTION D4x5

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

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

The SINAMICS Integrated always runs in isochronous mode. The SINAMICS Integrated's DP cycle setting is displayed as the "Bus data cycle" 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 7-3 Ratios of system cycle clocks

Position control cycle clock: Bus cycle clock	IPO cycle clock: Position control cycle clock	IPO 2 cycle clock: IPO cycle clock
1 ... 4, 8	1 ... 6	2 ... 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 145)

Settings for DP slave properties (Page 206)

7.3.5 Cycle clock scaling of external PROFIBUS interface to internal PROFIBUS interface

Definition

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, free-running 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 structure on the bus; in all cases, its cycle time exceeds that of the internal DP interface's cycle clock.
- 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.

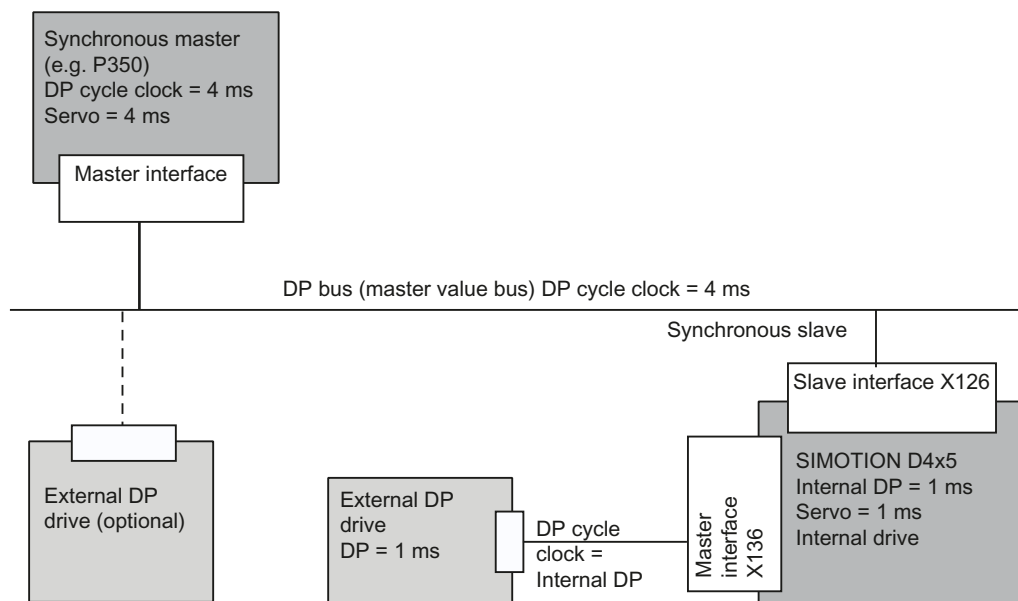


Figure 7-5 Example application for a cycle clock scaling

7.3.6 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**.
2. 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 box.
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 box.
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**.

7.3.7 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.
5. Select the required transmission rate on the "Network settings" tab.
If you wish to activate an isochronous 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 Runtime Basic Functions*, Chapter *Isochronous I/O processing on fieldbus systems*

7.3.8 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 on 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 box 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).

7.4 Configuring an Ethernet subnet

7.4.1 Configuring an MPI bus

7.4.1.1 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.

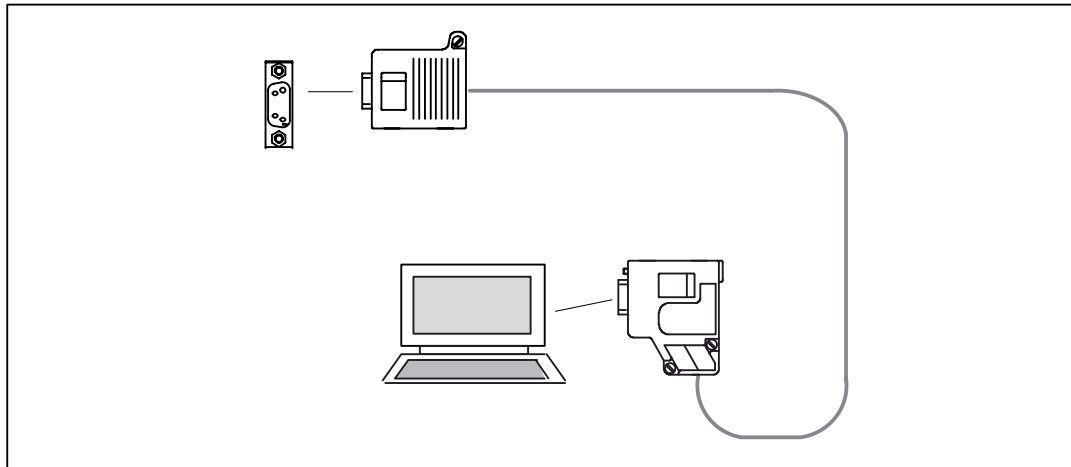


Figure 7-6 Connection of D4x5 (using X136) and MPI bus component

7.4.1.2 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:

- 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.

7.4.2 Properties of the Ethernet interfaces

Characteristics

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. telegrams are not forwarded from one interface to the other. As a rule, the interfaces belong to separate S7 subnets. SIMOTION D4x5 does not have IP router functionality; it does not forward the telegrams from one subnet to another.

The features of the Ethernet interfaces are as follows:

- TCP/IP timeout parameters can be configured in common for all Ethernet/PROFINET interfaces (in HW Config: Double-clicking on the D4x5 module, "Ethernet Extended" tab)
- 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 (e.g. via SIMOTION IT OPC XML-DA).
- PROFINET basic services (as of V4.3)
These PROFINET basic services (e.g. DCP, LLDP, SNMP) provide uniform functions for address assignment and diagnostics, but do not provide PROFINET IO communication for connecting drives or I/O modules, for example.

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.

See also

You will find more information on routing and the differences between IP and S7 routing in the *SIMOTION 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

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**. You will find a description of how to switch a connection to active again in Establishing the PG/PC assignment (Page 136).

Separate Ethernet interfaces

The two Ethernet interfaces are completely separate from one another and are generally connected to 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.
2. Open HW Config. Double-clicking the Ethernet port (e.g. X120 P1) opens the "IE1-OP properties ..." dialog box.
3. You can configure the Ethernet connection in the "Options" 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 "IE1-OP properties..." dialog box with "OK".

5. Save and compile the modified hardware configuration.
6. Load the new hardware configuration to the SIMOTION D4x5 via PROFIBUS DP/Ethernet.

Note

The settings are adjusted in SIMOTION < V4.3 by double-clicking on the D4x5 module in HW Config. The "Properties - D4x5" dialog box is opened. You can configure the Ethernet connection in the "Extended Ethernet" tab.

For additional information, see the *SIMATIC NET, Industrial Twisted Pair, and Fiber Optic Networks* Manual.

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

7.4.3 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.
4. 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".
5. The newly created Ethernet subnet is now displayed under "Subnet" in the "Properties - Ethernet Interface" dialog box and must be selected.
6. 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".

7.4 Configuring an Ethernet subnet

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.

7.4.4 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.

7.5 Configuring PROFINET IO

7.5.1 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 telegrams, 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.

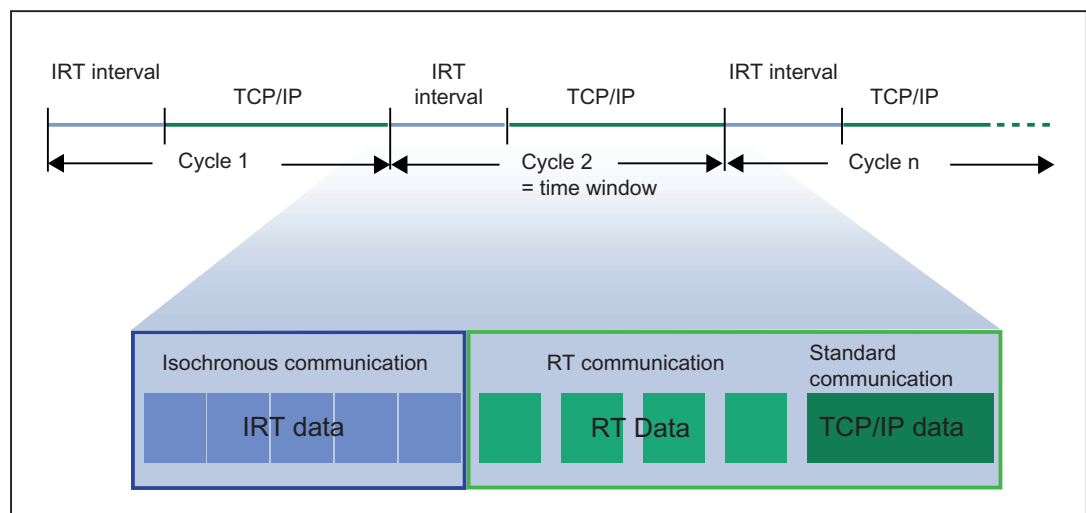


Figure 7-7 PROFINET communication cycle

Isochronous real-time Ethernet

STEP 7 V5.4 and higher can be used to configure PROFINET devices supporting data exchange via isochronous real-time Ethernet (IRT). IRT telegrams 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.

Isochronous operation and mode

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 real-time 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.

7.5.2 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 206).

Table 7-4 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 clock	≥ 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 box 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 box. 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 ms ≤ send cycle clock ≤ 4 ms. The smallest configurable grid is 0.125 ms.

7.5 Configuring PROFINET IO

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 position control cycle clock must always correspond to the PROFIBUS cycle clock. The ratio between the PROFIBUS cycle clock and the PROFINET send cycle clock can be configured.

Example:

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

The PROFIBUS cycle clock can be operated relative to the PROFINET send cycle cycle at a ratio of 1 to 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 7-5 Ratios of system cycle clocks

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

7.5.3 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.

Additional references

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

7.5.4 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)

8.1 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 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.

8.1.1 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 telegrams as well as the used addresses set up.
- Telegrams 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 performed independently of one another.
- Communication connections are established automatically during the configuration of I/O variables on SINAMICS I/Os (telegrams are set up automatically, the I/Os interconnected to the telegram 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 Telegram Configuration dialog box (see Section Telegram configuration (Page 232)), you can deactivate **automatic telegram configuration** and the **automatic telegram 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.
- 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. Symbolic assignment must be deactivated for these methods.

For newly created projects, symbolic assignment is used by default.

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

Symbolic assignment can be activated/deactivated in SIMOTION SCOUT via the "Project" > "Use symbolic assignment" menu.

Activating symbolic assignment later

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. Symbolic assignment is therefore recommended for new projects as of V4.2 and is automatically active. If symbolic assignment is used in a project, telegrams, interconnections and addresses are automatically created by the engineering system by default.

The engineering system sets the "optimal" PROFIdrive telegrams and telegram 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 telegram configurations (e.g. for TB30, TM15 DI/DO, TM31).

Note

If the symbolic assignment is activated later, previously existing telegram settings and BICO interconnections for all SINAMICS telegrams that are set to Standard/Automatic (Communication -> Telegram configuration) are replaced at the next compilation. This may change telegrams and BICO interconnections and delete telegram extensions previously set up manually.

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

To retain the settings that have been made, after the selection of "Use symbolic assignment," the setting "User-defined" must be selected and the check box cleared for automatic telegram setting/address adaptation for the respective message before compilation.

For further details, see the *SIMOTION Runtime Basic Functions* Function Manual.

Assigning a drive later

You can create an axis in SIMOTION SCOUT and assign it to a drive later. 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 see

- *SIMOTION Runtime Basic Functions* Function Manual
- *TO Axis Electrical/Hydraulic, External Encoder* Function Manual

Requirement

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 8-1 Control units that support a symbolic assignment

Module	Supports symbolic assignment
SIMOTION D410-2	As of SIMOTION V4.3
SIMOTION D410	As of SIMOTION V4.2
SIMOTION D4x5-2	As of SIMOTION V4.2
SIMOTION D4x5	As of SIMOTION V4.2
Controller extension <ul style="list-style-type: none"> • CX32-2 • CX32 	As of SIMOTION V4.2
SINAMICS S110 CU305	As of SINAMICS V4.3
SINAMICS S120 <ul style="list-style-type: none"> • CU310-2 • CU310 • CU320-2 • CU320 	<ul style="list-style-type: none"> • As of SINAMICS V4.4 • As of SINAMICS V2.6.2 • As of SINAMICS V4.3 • 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, see the *TO Axis Electrical/Hydraulic, External Encoder* Function Manual.

8.1.2 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 155) and Performing CX32 offline configuration (Page 196)
For offline configuration, all of the components and their order numbers must be known.
 - Online configuration:
Performing D4x5 online configuration (Page 182) and Performing CX32 online configuration (Page 199)
During online configuration, you can download all of the information from the connected DRIVE-CLiQ components to your user project.

Note

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

Section *Configuring a CX32* also describes configuration and 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 (Page 216)
3. Creating an axis with the axis wizard (Page 220)
4. Testing an axis with the axis control panel (Page 227)
5. Activating the infeed (Line Module) (Page 229)
6. Setting up addresses and telegrams (Page 232)
7. Linking an additional encoder (optional) (Page 236)
8. Configuring drive-related I/Os (with symbolic assignment) (Page 243)
9. Configuring the technology (Page 247)
10. Optimizing the drive and controller (Page 255)

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

8.1.3 Important functions for the project handling during commissioning

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

Table 8-2 Functions with their symbols

Symbol	Function	Effect
	Save project and compile changes	Select Save project and compile all to save the entire project and compile the project data (e.g. programs) in an executable code.
	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
	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).
	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).

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.

8.2 Performing offline configuration for the D4x5

8.2.1 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 Section Creating a project and configuring the communication (Page 121).

Procedure

The offline configuration involves the following steps:

- Accessing the drive wizard (Page 156)
- Configuring components (Page 157)
- Downloading the project to SIMOTION D4x5, by means of one of the following options:
 - Downloading to the target system (Page 176)
 - Downloading to the CF card (Page 179)
 - Downloading incl. sources and additional data (Page 180)
 - Archiving a project to the CF (zip file) (Page 181)

Note

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

8.2.2 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

8.2.3 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 *Vf* **is 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.

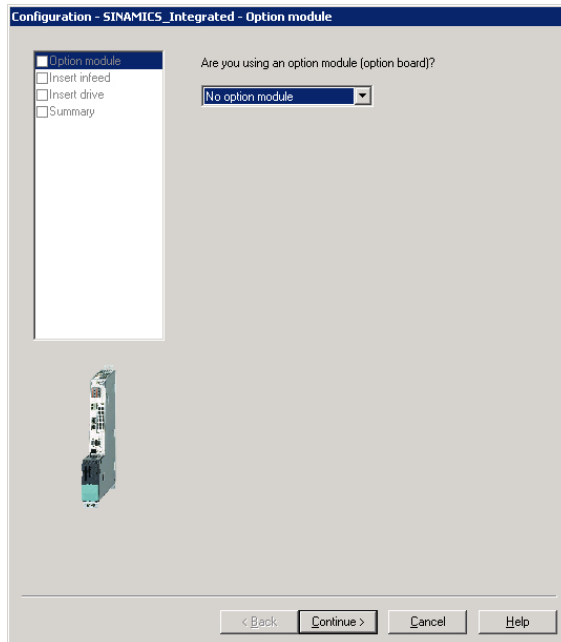


Figure 8-1 Selecting an option module

Note

The TB30 is displayed as a drive object below the Control Unit in the project navigator and can be configured there.

2. 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).

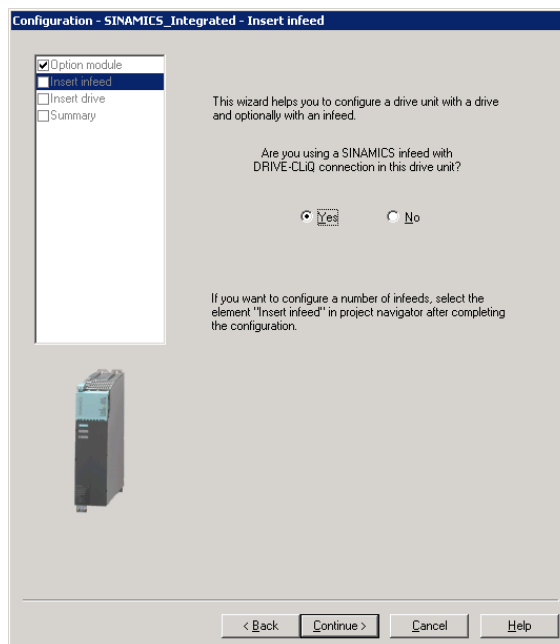


Figure 8-2 Selecting an infeed with DRIVE-CLiQ connection

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).

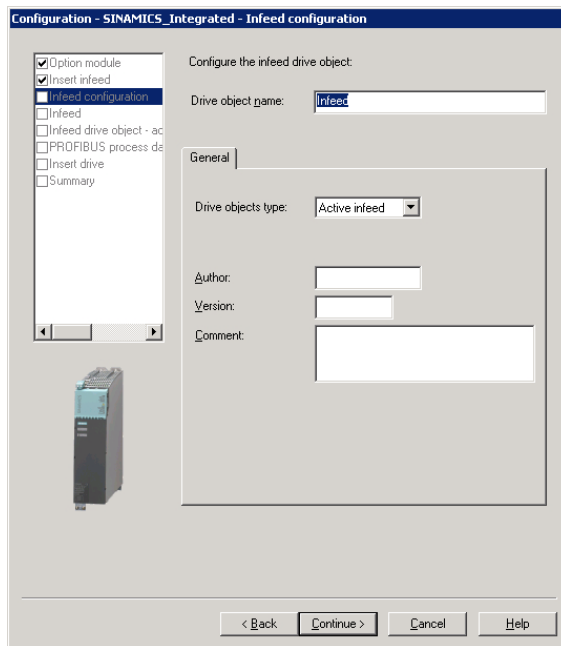


Figure 8-3 Selecting the infeed type

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

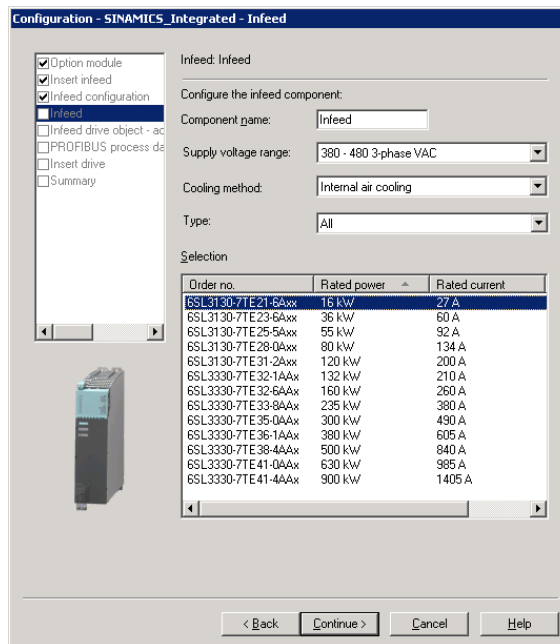


Figure 8-4 Selecting an infeed

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

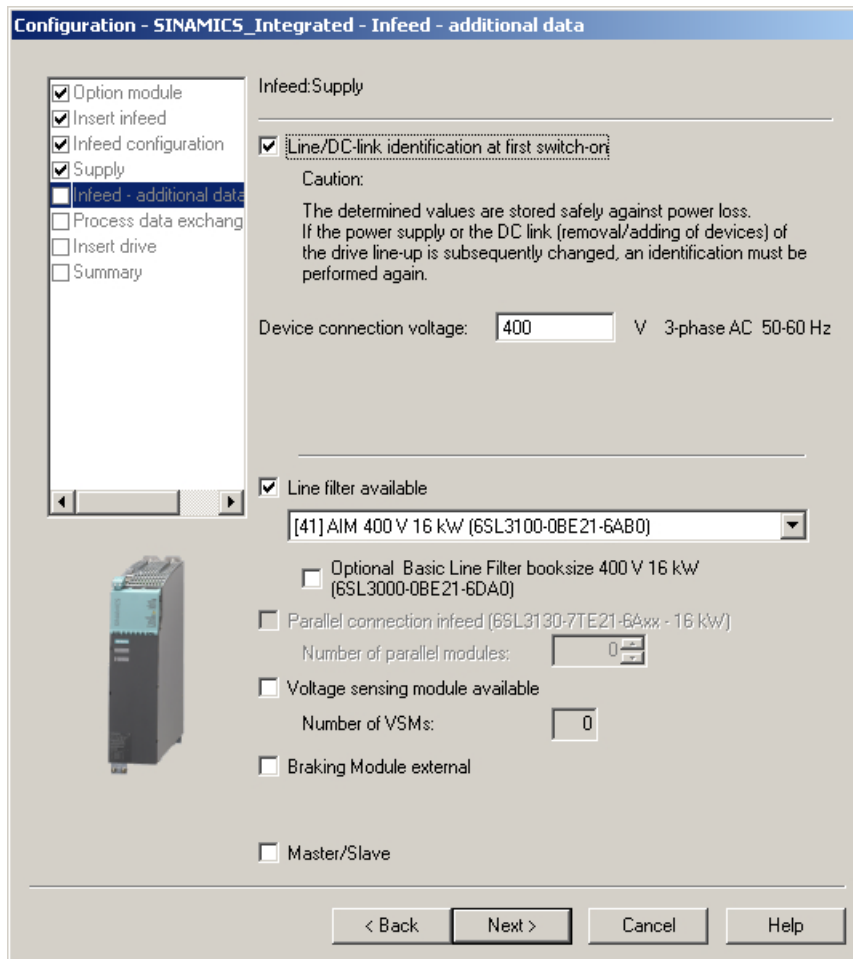


Figure 8-5 Making settings for the infeed

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."

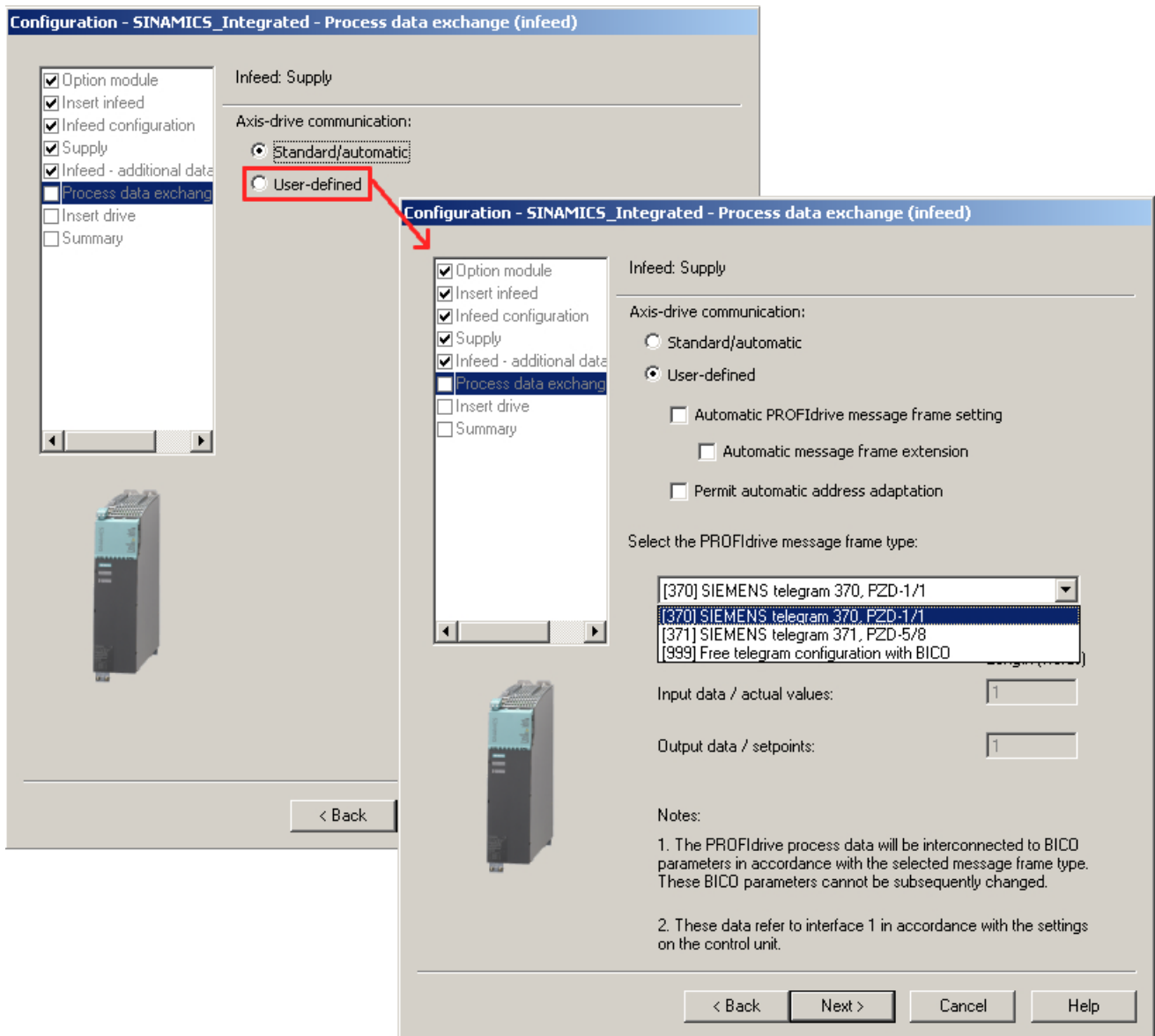


Figure 8-6 Configuring the process data exchange for the infeed

If the automatic communication setting has been selected, SIMOTION SCOUT uses PROFIdrive telegram 370 by default. This telegram 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 229).

If you are using a CX32 controller extension, refer also to the information in Section Interconnecting the infeed "Operation" signal on the CX32 (Page 201).

8.2 Performing offline configuration for the D4x5

If you activate the Line Module with "Free telegram 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.

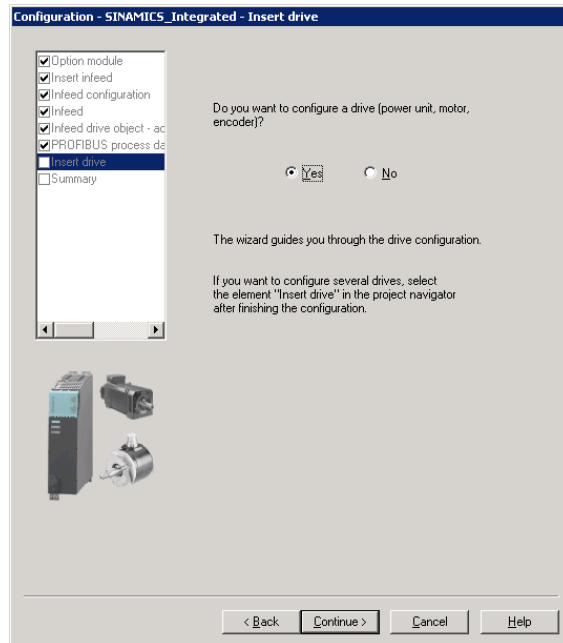


Figure 8-7 Configuring a drive

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

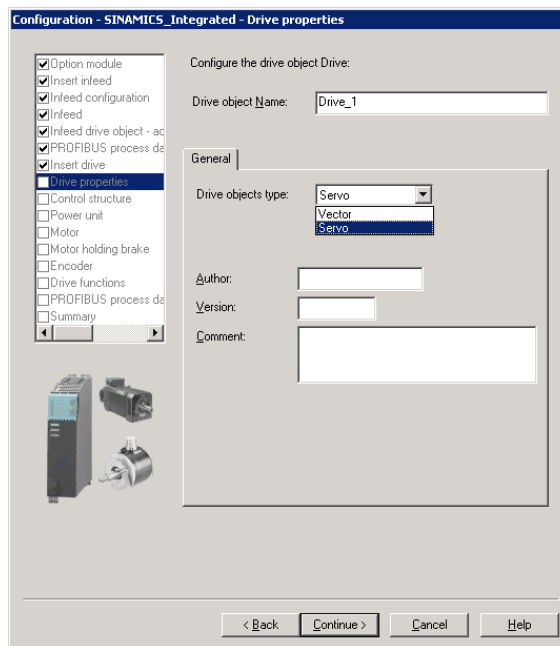


Figure 8-8 Drive properties

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

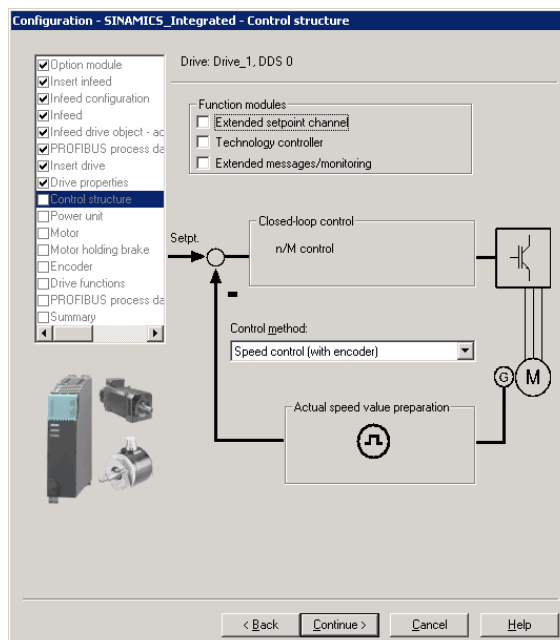


Figure 8-9 Control structure

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

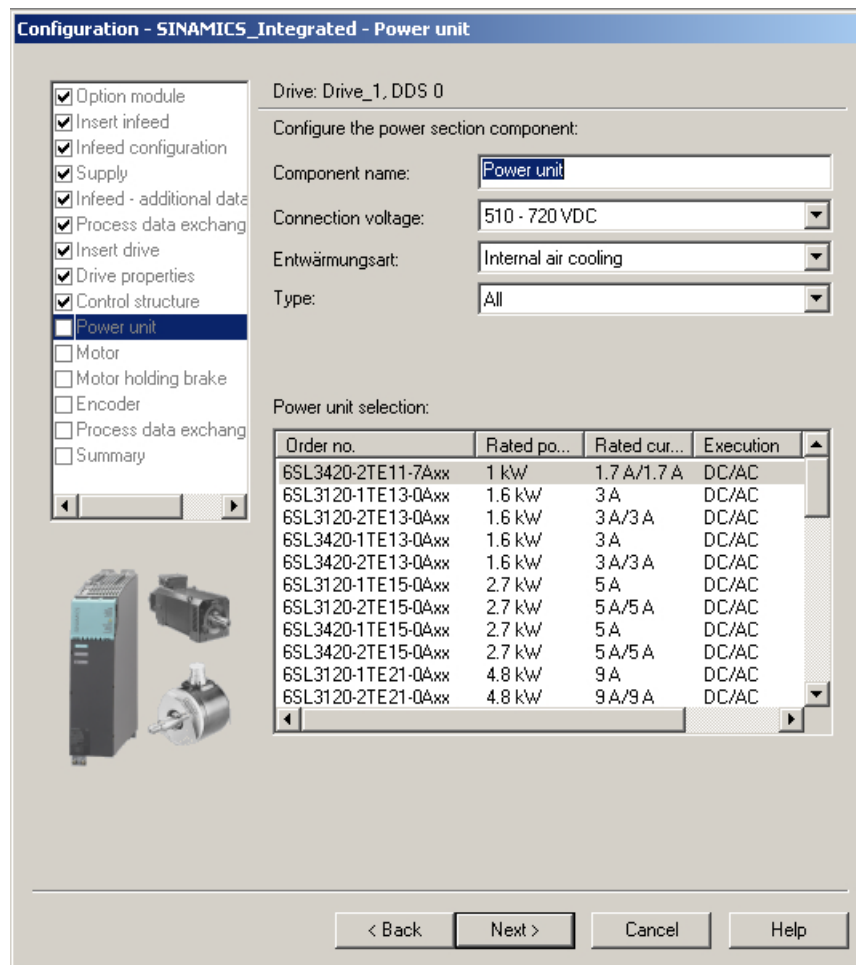


Figure 8-10 Selecting a power unit

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 box allows you to select the source of the infeed's operation signal.

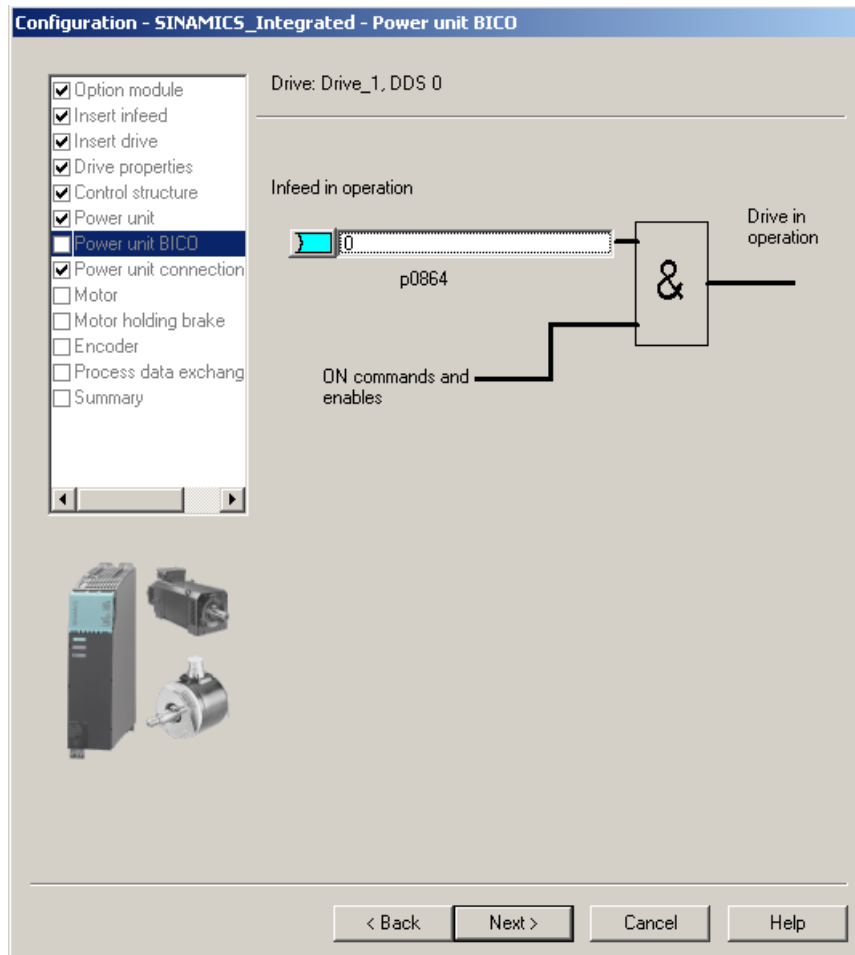


Figure 8-11 Selecting the infeed operation signal

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)

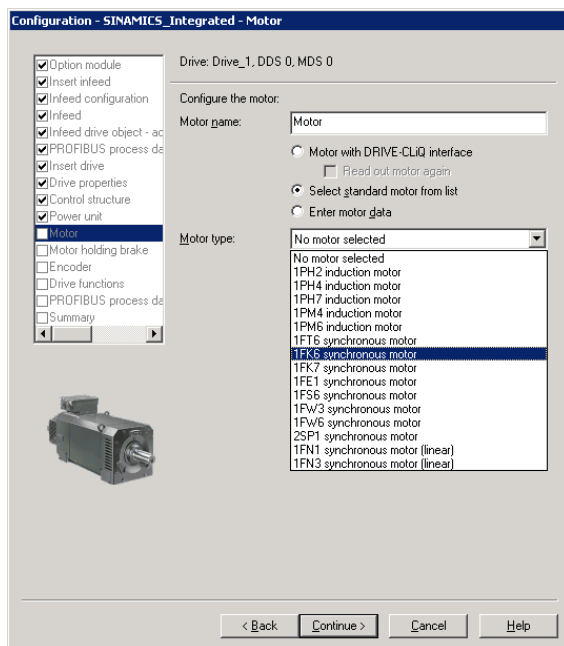


Figure 8-12 Selecting a motor (1)

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.

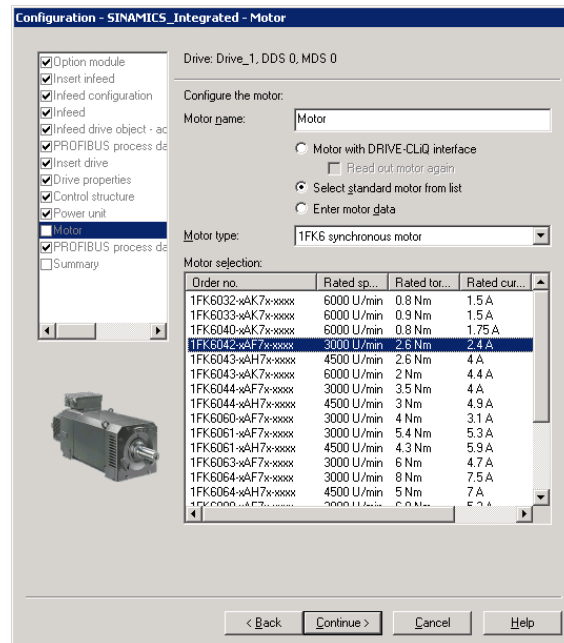


Figure 8-13 Selecting a motor (2)

13. Select a motor holding brake (if installed).

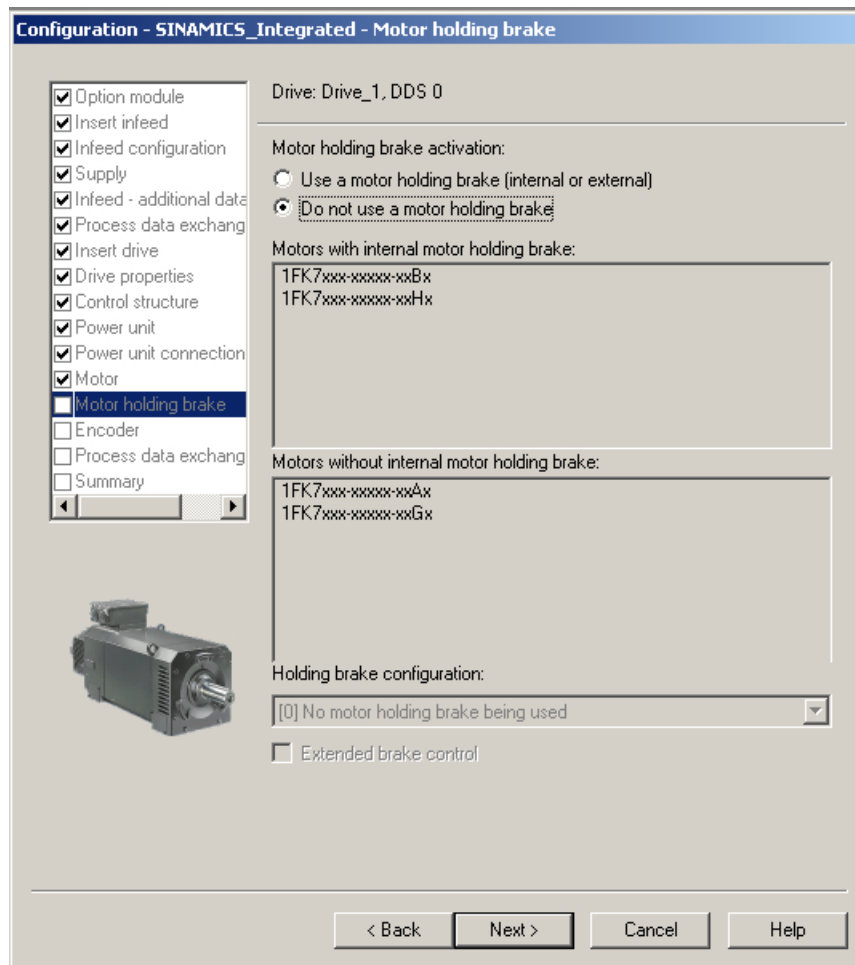


Figure 8-14 Selecting a motor holding brake

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.

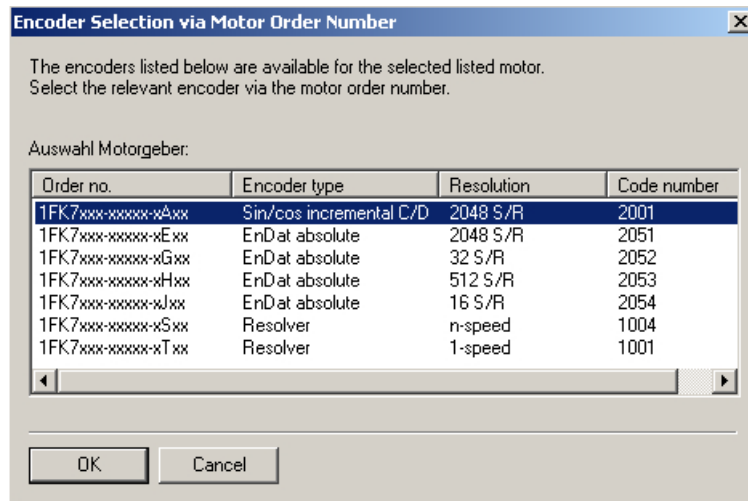


Figure 8-15 Selecting a motor encoder (1)

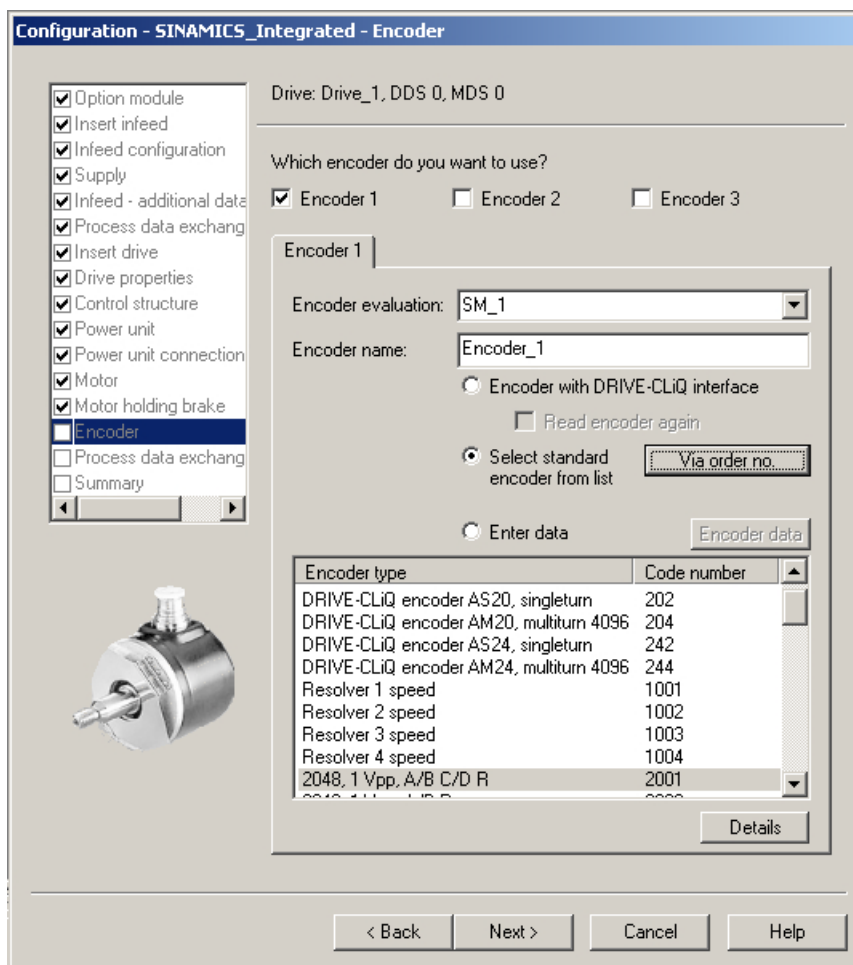


Figure 8-16 Selecting a motor encoder (2)

Note

If required, you can configure a second or third encoder in the "Encoder" dialog box. You can transfer a maximum of 2 encoder values to SIMOTION via the axis telegram.

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 box for selecting Encoder 1 is grayed out and, therefore, inactive).

- 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.

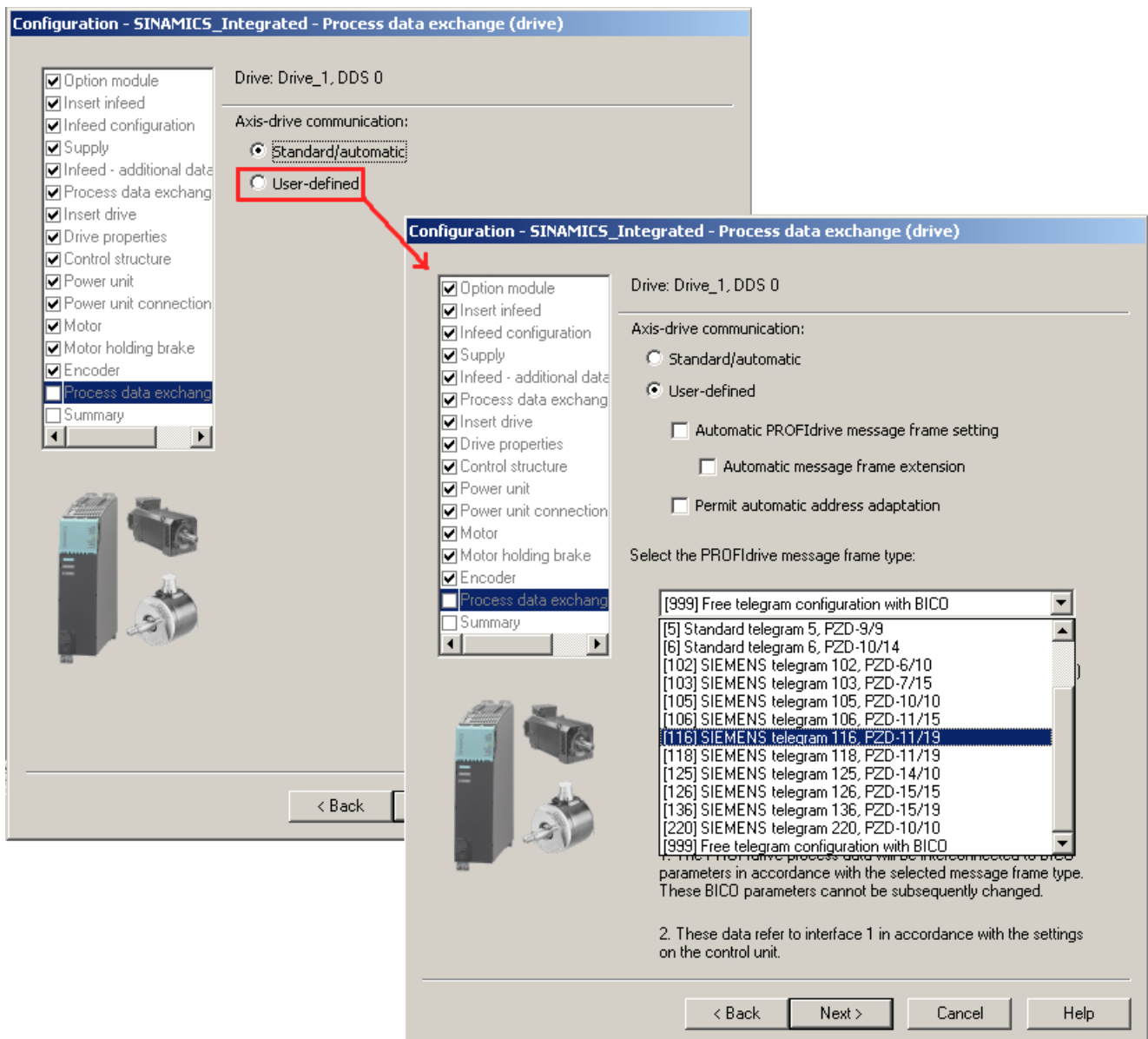


Figure 8-17 Configuring the process data exchange

After you have configured all of the settings in the drive wizard, the "Summary" dialog box displays a list of all settings. You can accept these settings with "Finish" or edit the configuration of individual components using the "Back" button.

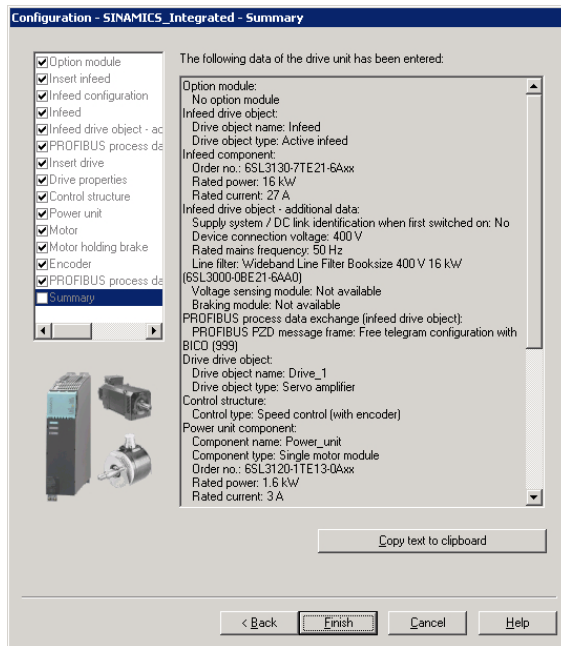


Figure 8-18 Finishing the drive

Result

The configured drive is displayed in the project navigator.

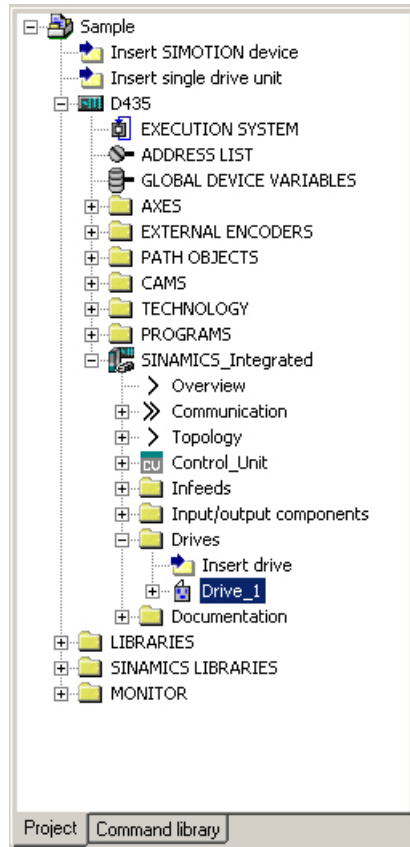


Figure 8-19 Representation in the project navigator

You will find an overview of the configured SINAMICS components under "SINAMICS_Integrated" > "Topology."

8.2 Performing offline configuration for the D4x5

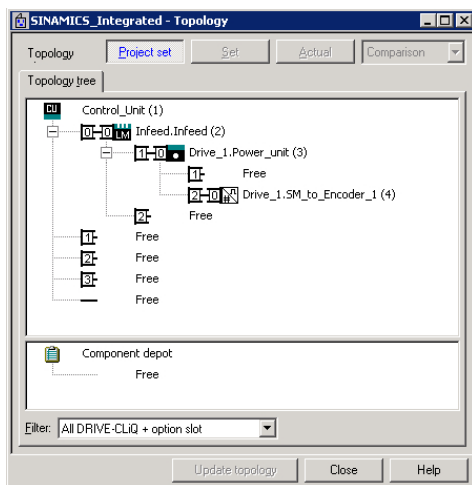


Figure 8-20 Displaying the topology

See also

If you configure the telegrams for the infeed and drive manually, you can find detailed information on the respective telegram types in the following:

- *Motion Control, TO Axis Electrical/Hydraulic, External Encoder* Function Manual
- *SINAMICS S120* Function Manual

8.2.4 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 operating 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 the STOP operating mode.

Procedure

1. Save and compile the project.
2. Go online.

8.2 Performing offline configuration for the D4x5

3. To load the project, perform "Download project to target system". The data must also be saved on the CompactFlash 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".

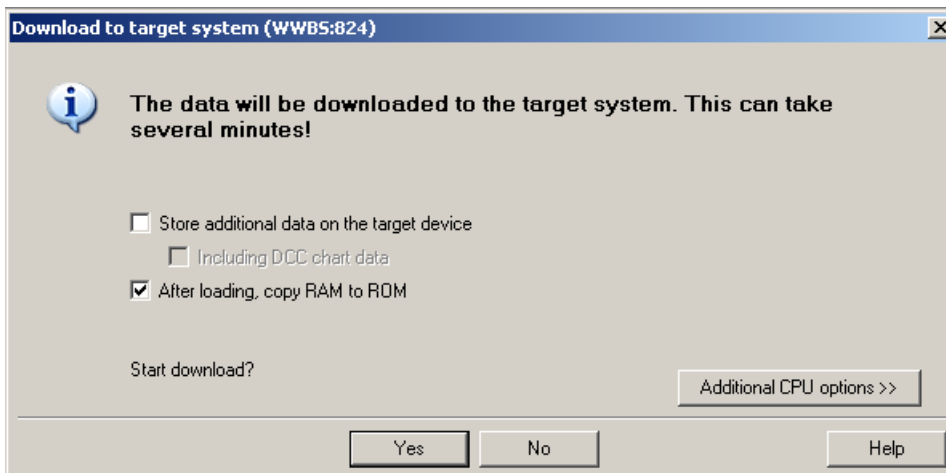


Figure 8-21 Download project to target system

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. During the "Download to target system" process, SIMOTION SCOUT automatically attempts to establish an online connection to SINAMICS Integrated.

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.

8.2.5 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.
4. 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.

8.2.6 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 or downloading to the D4x5. These data are 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" > "Settings" > "Download" > "Store additional data on the target device". Alternatively, this setting can also be made when the data is loaded to the target device/target system.

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 perform servicing work on a commissioned system and have placed a project on your PG/PC. 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 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 Runtime Basic Functions* Function Manual.

8.2.7 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 box, select the SIMOTION project and save it to your drive (PG/PC).
3. Open the project.
4. Go online with the SIMOTION D4x5.
5. 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" ⇒ "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 Runtime Basic Functions* Function Manual.

8.3 Performing online configuration for D4x5

8.3.1 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 the Creating a project and configuring communication (Page 121) section.

Procedure

Online configuration involves the following steps:

- Establishing an online connection (Page 182)
- Starting the automatic configuration (Page 183)
- Editing SINAMICS components (Page 188)
- Downloading a project to SIMOTION D4x5 (Page 188)

8.3.2 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.
4. 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 183).

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.

8.3.3 Starting the automatic configuration

Requirements

You have established an online connection with SINAMICS Integrated.

Procedure

1. In the project navigator, open the "Automatic Configuration" dialog box by selecting "SINAMICS Integrated" > "Automatic Configuration".

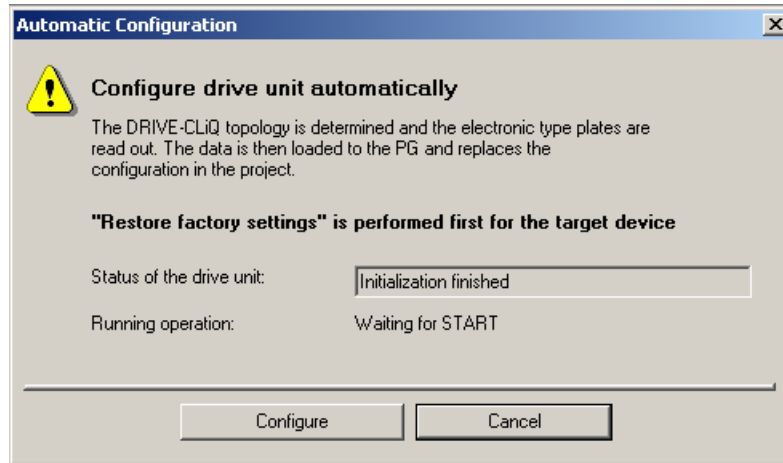


Figure 8-22 Starting the automatic configuration

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.

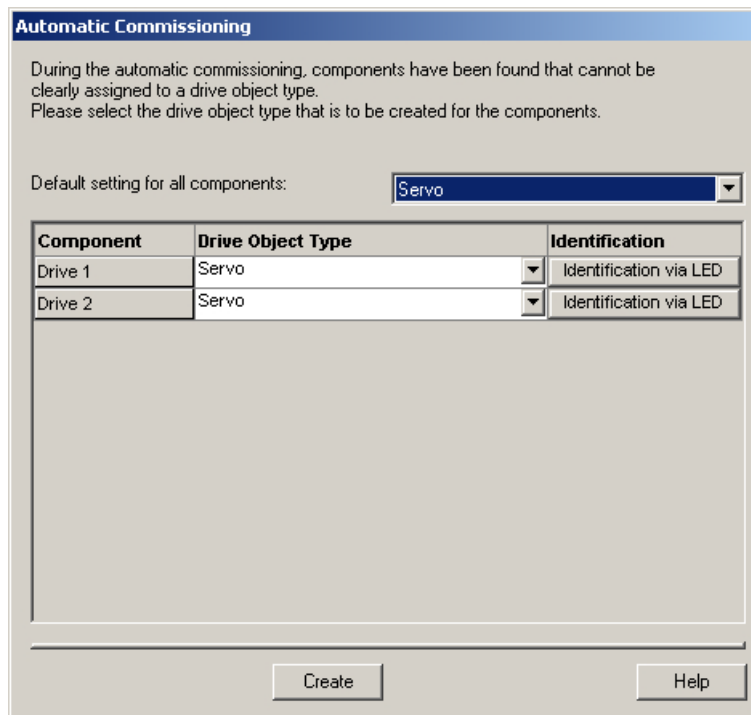


Figure 8-23 Selecting the drive object type

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 CompactFlash and the FW version on the SINAMICS components (DRIVE-CLiQ components, CBE30, PM340, etc.).

The update procedure can take several minutes and is indicated in the "Automatic configuration" dialog box by the following message:

Status of the drive unit: Automatic FW update of DRIVE-CLiQ components

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.

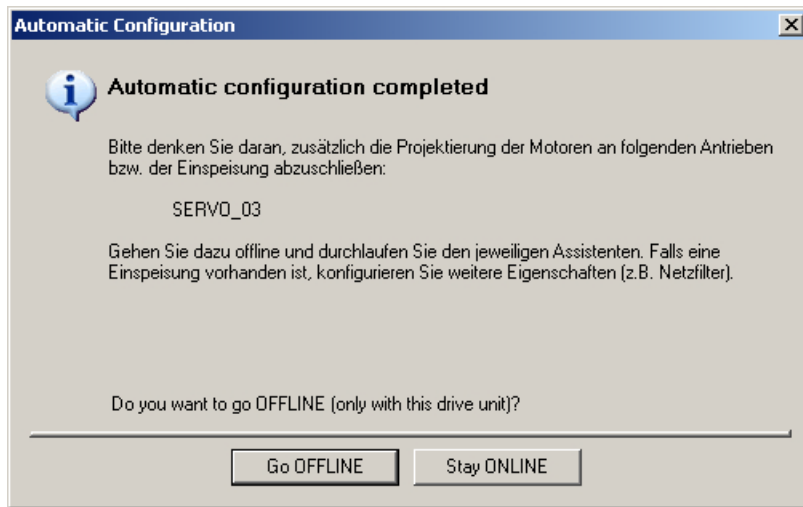


Figure 8-24 Automatic configuration completed

8. Execute the "Copy RAM to ROM ..." function on the D4x5 and the SINAMICS Integrated. This saves the project on the CompactFlash card, meaning that it does not need to be reloaded after switching off and on again.

Result

The DRIVE-CLiQ components loaded to your user project by automatic configuration are displayed in the project navigator.

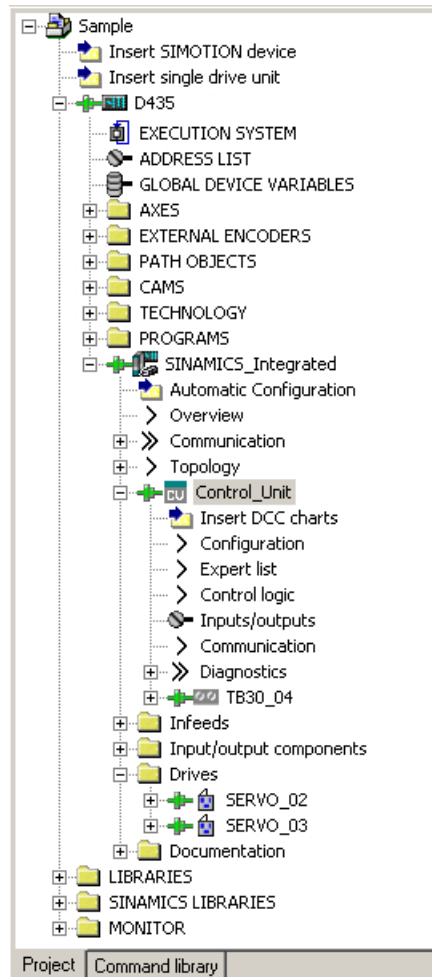


Figure 8-25 Project navigator with real configuration

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 270)

8.3.4 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 155).

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.

8.3.5 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 CompactFlash 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".

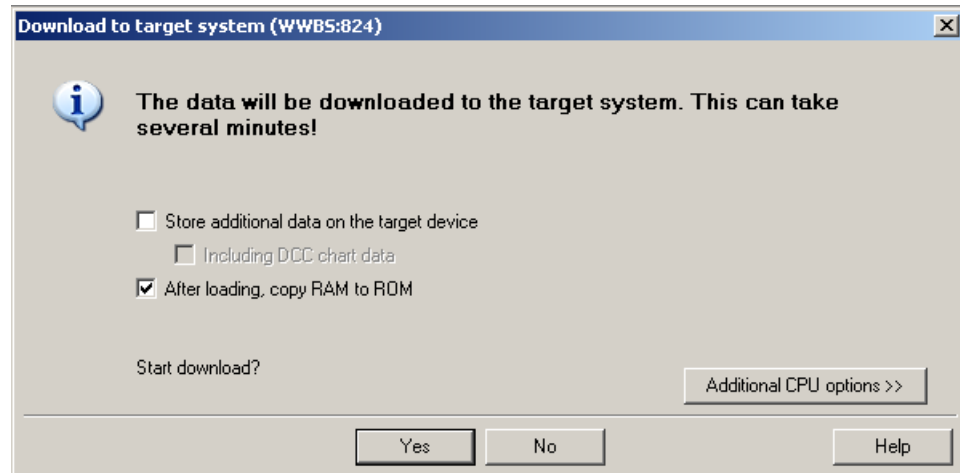


Figure 8-26 Download project to target system

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 the data to HW Config to enable online access to SINAMICS Integrated. During the "Download to target system" process, SIMOTION SCOUT automatically attempts to establish an online connection to SINAMICS Integrated.

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 run "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 255)

8.4 Configuring a CX32

8.4.1 Overview

The SIMOTION CX32 controller extension is a component in SINAMICS S120 booksize format and supports scaling of the drive-end computing functionality of the SIMOTION D435 and D445/D445-1 Control Units. Each CX32 can operate up to six additional servo, four vector or eight *Vfd* 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 CompactFlash 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

8.4.2 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 "Operational" signal on the CX32 (Page 201) describes how to connect 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.

The CX32 configuring tools section describes in detail how to detect if a power-up has been completed under CX32 power-up (Page 200).

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.

Commissioning requirements

To commission a SIMOTION D with CX32, all drive components that 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.

8.4.3 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.

8.4 Configuring a CX32

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).

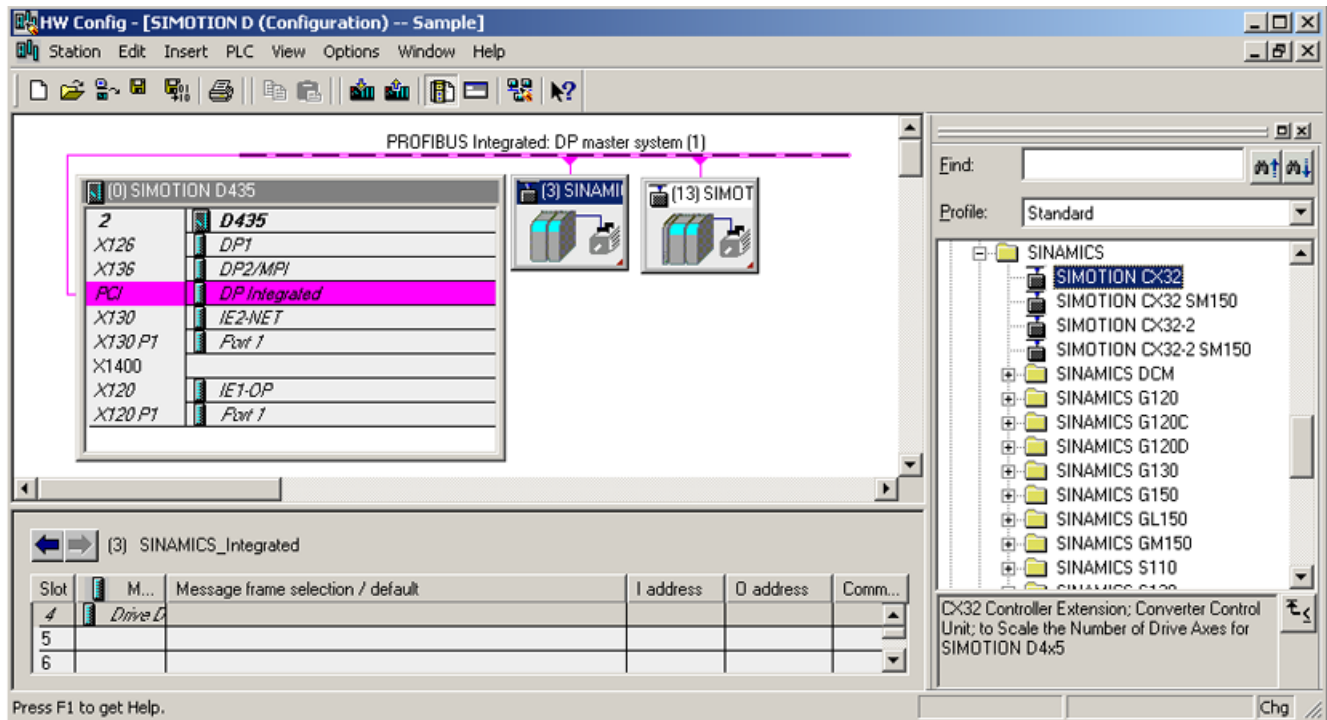


Figure 8-27 Inserting CX32 in HW Config

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.

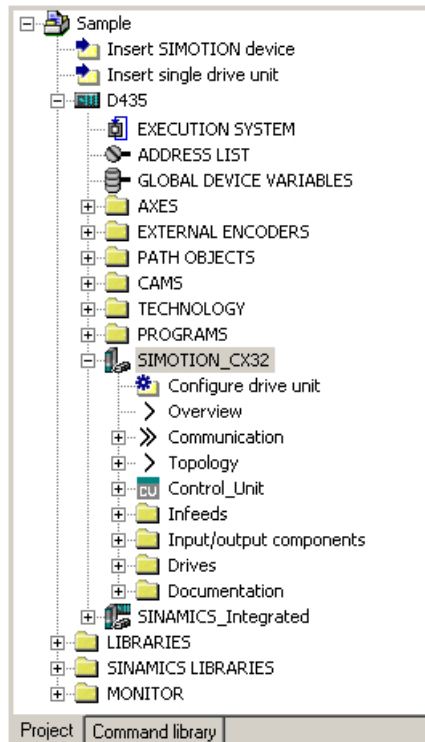


Figure 8-28 CX32 in the project navigator

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 8-3 CX32 PROFIBUS addresses (PROFIBUS 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 157)

Performing CX32 configuration online (Page 199)

Performing CX32 configuration offline (Page 196)

8.4.4 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.

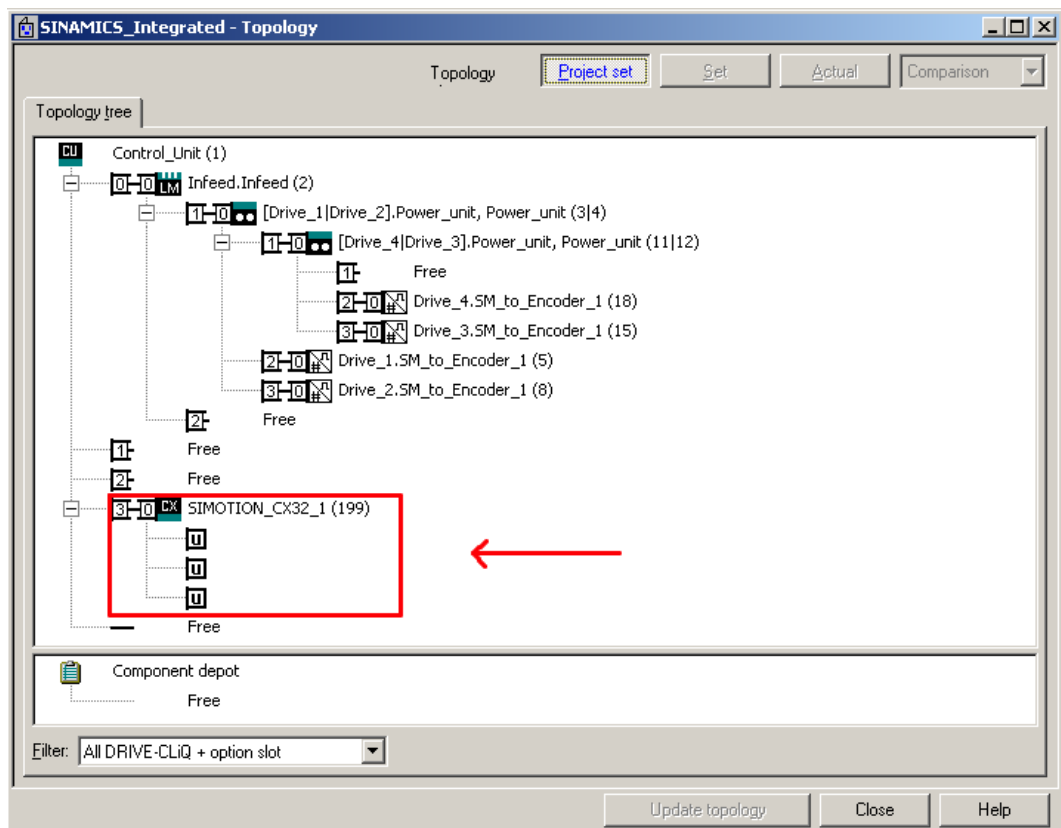


Figure 8-29 SINAMICS Integrated topology

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.

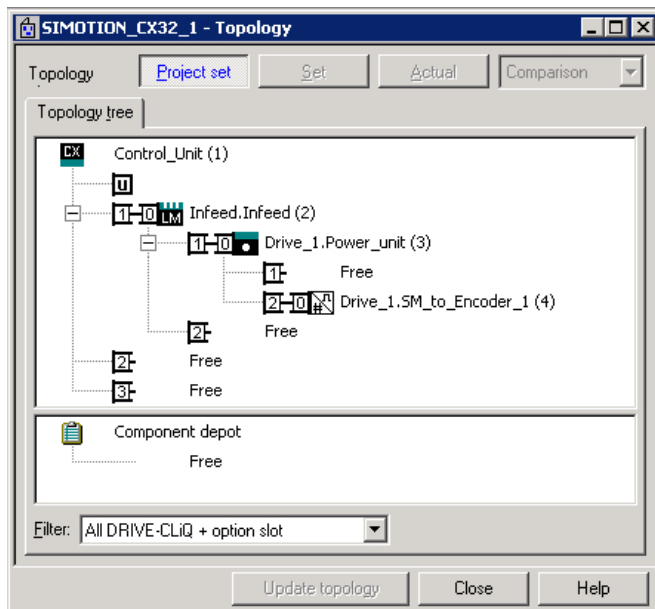


Figure 8-30 CX32 topology

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 203)

8.4.5 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

8.4.5.1 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 191)).
- 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".
8. 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.

See also

CX32 diagnostics (Page 203)

8.4.5.2 Loading a project created offline to the CF card

Loading a project created offline to the CompactFlash 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 CompactFlash card.

Requirement

- You will need a card reader for the SIMOTION D4x5 CompactFlash card.
- Your project, including all SINAMICS Integrated and CX32 drive components, must have been configured already (see Preparing for configuration (Page 191)).
- 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".
3. If a project has already been saved to the CompactFlash 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 CompactFlash 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 Upgrading D4x5/CX32 (Page 204) section.

Note

Topology errors may make it impossible to perform a download, power up a system, or access a CX32 online.

8.4.6 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)

8.4 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 200)

CX32 diagnostics (Page 203)

8.4.7 CX32 configuration instructions

This section contains configuration tips relating to a number of features which are specific to operating CX32 in conjunction with D4x5.

8.4.7.1 CX32 power-up

Powerup times

The CX32 does not require its own CompactFlash card. Both the firmware and parameterization are stored centrally on the SIMOTION D CompactFlash 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.

8.4.7.2 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 "Closed-loop control operation" r0863.0 signal from the Line Module is automatically connected with the "Infeed operation" signal from the drives (Drive 1...n) via p0864.

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.

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,

connect parameter p0864 (drives on CX32) with parameter r8510.0 of the CX32 controller extension.

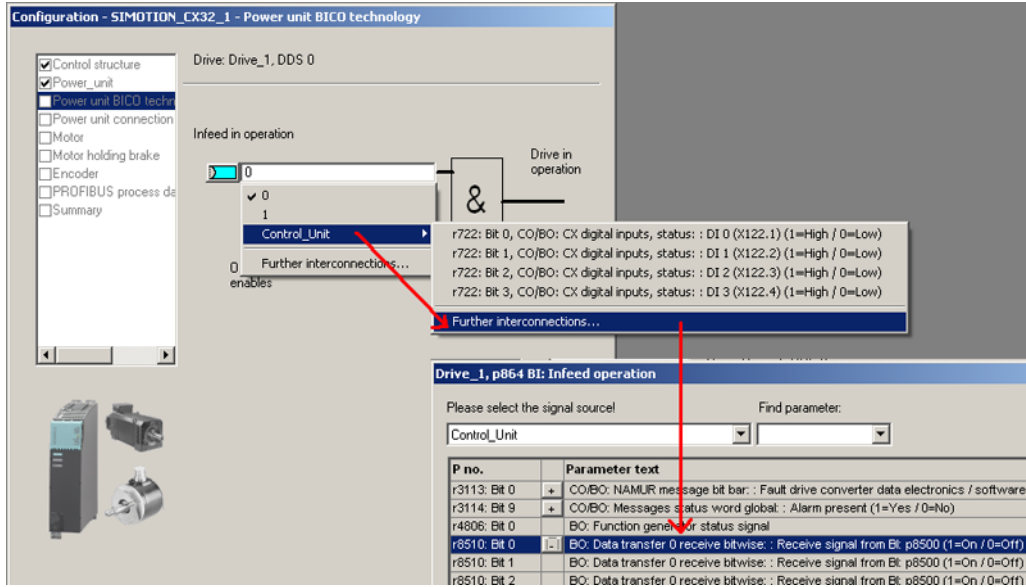


Figure 8-31 Interconnecting the infeed operation signal

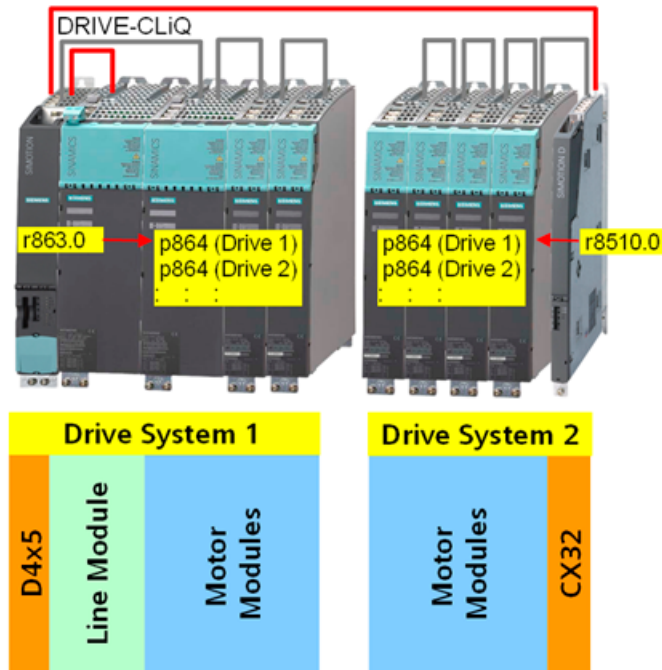


Figure 8-32 Operation signal interconnection (explanatory illustration)

Infeed to CX32

If the infeed is connected to the CX32 and if the ready for operation signal on SINAMICS Integrated is to be connected to a different CX32 or a CU320, proceed as described in Section Using one infeed for several CUs (Page 231).

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.

8.4.7.3 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 for D4x5 remains yellow
- Are RDY LED and DP1 LED on the CX32 yellow and red.
- Can the CX32 not 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. The topology error can now be analyzed using the alarm window and the topology view of SINAMICS Integrated (for example, a component may be missing or in the wrong port).

8.4 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.

8.4.7.4 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" ⇒ "Target device" ⇒ "Device version".

For instructions on upgrading a SIMOTION D see also Section Adapting a project (Updating the project / Replacing the SIMOTION controller) (Page 291).

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.

8.4.7.5 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).

8.5 Additional information on configuring the SINAMICS Integrated

8.5.1 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 Runtime 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 207)).

Note

After T_{DP} has been changed on the PROFIBUS master, the drive system must be switched on (POWER ON).

- Changing the T_I and T_O times
A change to T_I/T_O is required in the case of vector drives, for example, where the T_I/T_O 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.

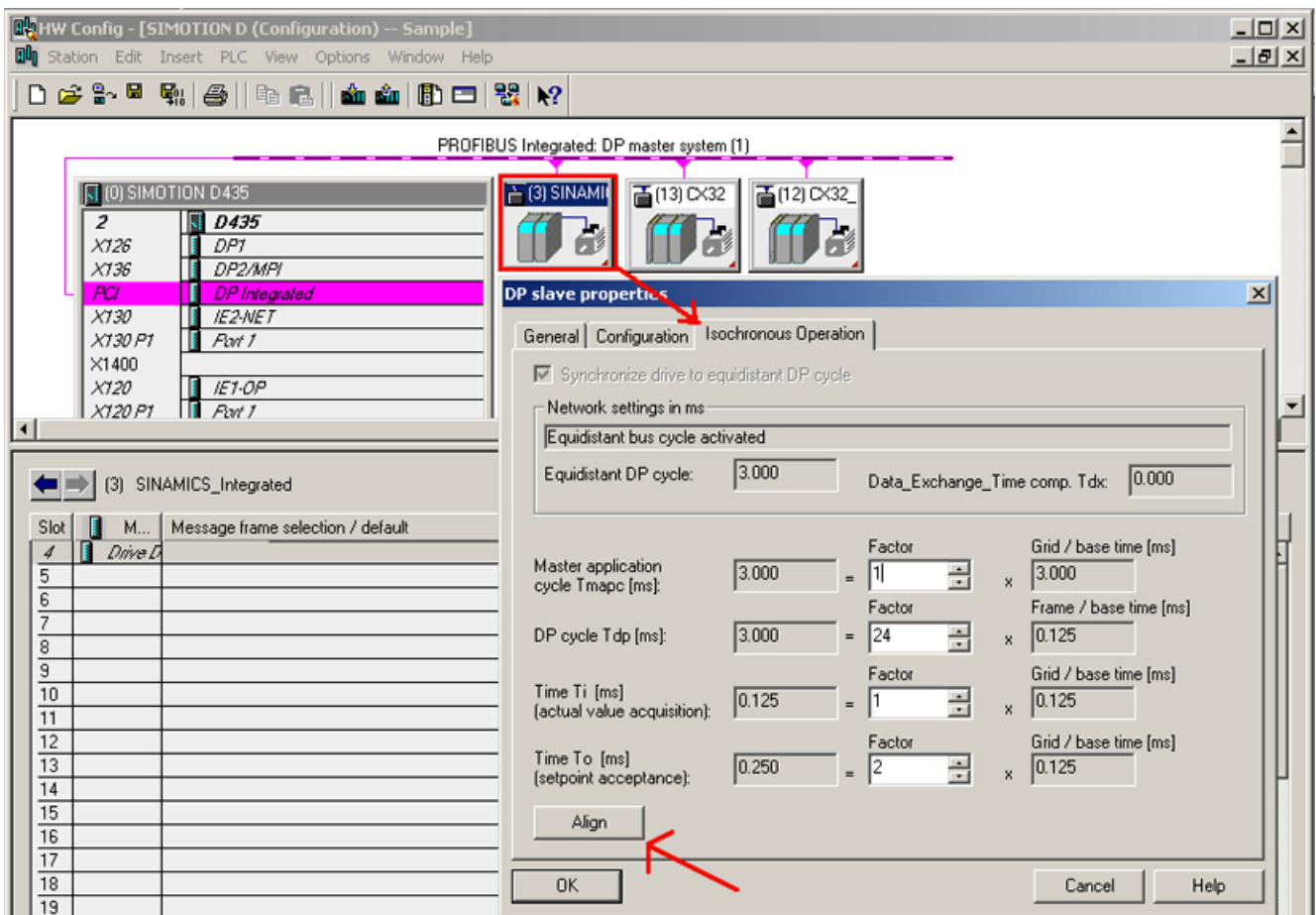


Figure 8-33 HW Config - settings

The times are modified by changing the value in the "Factor" field.

Additional references

For additional information, see the

- *SINAMICS S120* Function Manual
- *SIMOTION Runtime Basic Functions* Function Manual

8.5.2 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.

Therefore, we recommend adopting the following procedure is when using vector drives with SIMOTION D4x5.

Scenario 1: Current and speed controller cycle clock is known

As long as you know the current and speed controller cycle clock, 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 clock.

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 $T_I = T_O =$, enter an integer multiple of the current controller cycle clock.
3. For T_{DP} , enter an integer multiple of the speed controller cycle clock. For drives on the SINAMICS Integrated, T_{DP} must always be $\geq T_O$.
4. 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 cycle clocks 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.
 p0115[0] current controller cycle clock
 p0115[1] speed controller cycle clock
7. If the current and speed controller cycle clocks 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 8-4 Example for power units in booksize format (vector drives)

Example	Settings
1 or 2 vector drives Current controller cycle clock = 250 μ s Speed controller cycle clocks = 1 ms	$T_I = T_O =$ at least 250 μ s $T_{DP} =$ 1 ms (... or 2 ms, 3 ms, etc.) $T_{MAPC} = T_{DP}$
3 or 4 vector drives Current controller cycle clock = 500 μ s Speed controller cycle clocks = 2 ms	$T_I = T_O =$ at least 500 μ s $T_{DP} =$ 2 ms (... or 4 ms, 8 ms, etc.) $T_{MAPC} = T_{DP}$

Note

Vector drives in chassis format can also be operated with a current controller sampling time of 400 μ 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 clock is not known

This procedure is especially suitable for devices in chassis format, as the current and speed controller cycle clock also depends on the relevant device type.

1. 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.
p0115[0] current controller cycle clock
p0115[1] speed controller cycle clock
4. If required, it is now possible to optimize the T_{MAPC} , T_{DP} , T_{I} and T_{O} times in HW Config (see procedure for Scenario 1).

Table 8-5 Recommended cycle clock settings in HW Config

Setting	Explanation
$T_{\text{DP}} = 3.0 \text{ ms}$	$T_{\text{DP}} = \text{DP cycle time}$
$T_{\text{I}} = T_{\text{O}} = 1.5 \text{ ms}$	$T_{\text{I}} = \text{time of actual value acquisition}$ $T_{\text{O}} = \text{time of setpoint transfer}$
$T_{\text{MAPC}} = 3.0 \text{ ms}$	$T_{\text{MAPC}} = \text{master application cycle time}$

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 μs / Using output cams and measuring inputs (Page 215).

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 206)

8.5.3 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" → "Set time".

Alternatively, the clock can be set using the "rtc" system function block.

SINAMICS system runtime (operating hours counter)

Faults and alarms are "time-stamped" based on the system runtime on SINAMICS Integrated of a SIMOTION D, controller extensions and SINAMICS S120 Control Units. 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.

The counter value is saved when the power is switched off. After the drive unit has been switched on, the counter continues to run with the value stored when the power was last switched off.

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 alarms 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 telegram 39x is required for the time synchronization. If the automatic PROFIdrive telegram setting is selected for the Control Unit, this telegram is used automatically.

(See Section Calling the drive wizard (Page 156), Standard/automatic setting)

If the telegrams are specified manually, telegram 39x must be set up. See Section Telegram configuration (Page 232).

So that drive units can be synchronized with the SIMOTION time, they must support telegram 39x and the UTC time format.

For precise time synchronization, the drive unit must also be operated via an isochronous bus on SIMOTION. The SINAMICS Integrated for SIMOTION D and the CX32/CX32-2 controller extension always have an isochronous connection.

The following Control Units support time synchronization:

- SINAMICS Integrated of the SIMOTION D
- CX32/CX32-2 controller extensions
- SINAMICS S120, CU310, CU310-2, 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 shortcut menu in the project navigator.
2. Select the "Properties" entry in the shortcut 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 telegram 39x.

The first time synchronization is performed after the SIMOTION D Control Unit has reached the RUN operating mode.

To compensate for deviations between the SIMOTION and SINAMICS clocks, the time of day is automatically resynchronized at regular intervals.

The user program can use the `_driveStates.allClocksSynchronized` on the device to query whether automatic time synchronization is enabled (=YES) or disabled (=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).

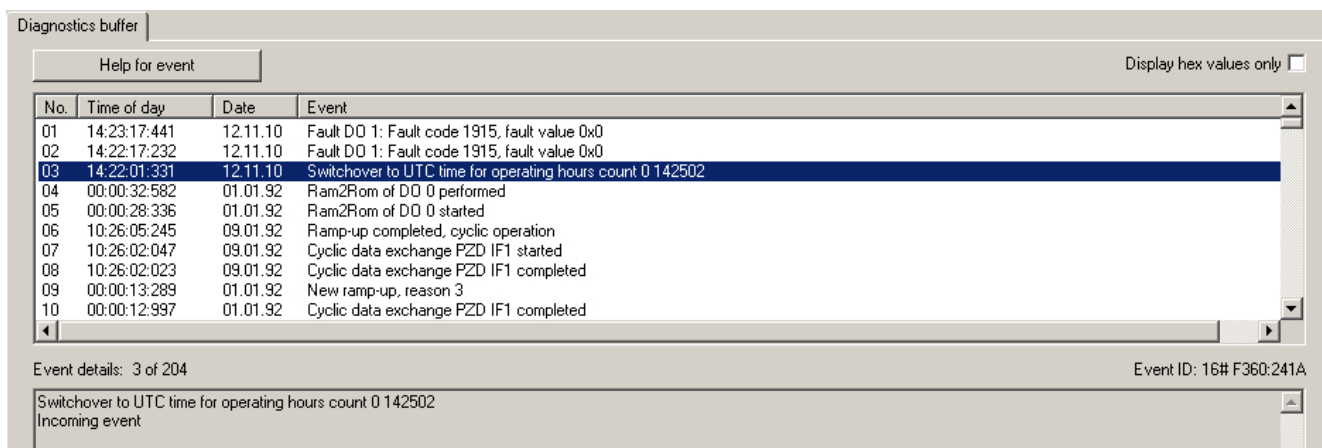


Figure 8-34 Diagnostic buffer entry, time synchronization

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 ≥ 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.

Error correction

If problems occur with time synchronization, this may be due to deactivated symbolic assignment to incorrect configuration information (Fast IO configuration).

For more information, see Section Message frame configuration (Page 232).

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 are corrected on the SINAMICS.
- "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.).

Due to system considerations, 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).

If the drive unit does not have an isochronous connection on SIMOTION, this can result in runtime differences of milliseconds (depending on the set cycle clock ratios).

8.5.4 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 hardware 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 diagnostic buffer entries are displayed first, followed by those for the SINAMICS Integrated and the CX32. The start of the SINAMICS diagnostic buffer entries is identified by the following entry:

```
>>>>> Start of SINAMICS Integrated diagnostic buffer, station address = x <<<<<<
```

You also have the option of viewing the SIMOTION D4x5 and SINAMICS Integrated diagnostic buffers via SIMOTION IT web server.

8.5.5 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 telegrams for data exchange (see Performing the configuration for the D4x5 offline (Page 155)).

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, alarms, controller parameters, motor data, etc.).

As a result, data can be transferred on an "acyclic" as opposed to "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:

- 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 management). 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)

8.5.6 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). EPOS functionality is provided by 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 the SIMOTION IT web server: 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, 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 via Ethernet. Wireless access is also possible in conjunction with WLAN.
- The use of the CU parameter p0972 is restricted with SIMOTION D4x5. CU parameter p0972 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 *Motion Control Basic Functions for Modular Machines*).

NOTICE**Fault on the SIMOTION D4x5 when CU parameter p0972 is used**

With the SIMOTION D4x5, the expert list of the Control Unit in parameter p0972 (drive unit RESET) must not be used for resetting the drive. This results in a fault on the SIMOTION D4x5. All eight status LEDs are flashing red.

Switch the SIMOTION D4x5 off and on again this fault.

8.5.7 Current controller cycle clocks <> 125 µs / use of output cams and measuring inputs

If current controller cycle clocks <> 125 µs 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 p0112 and p0115[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.

8.6 Testing a drive with the drive control panel

Table 8-6 Influence of the current controller cycle clock on the dead time compensation

	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)	<ul style="list-style-type: none"> • 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)	---	---

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.
5. 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. Execute "Project" > "Save 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.


8.6 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.

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
<p>Danger to life from unexpected movement of driven machine parts</p> <p>Make sure this presents no hazard to personnel or property.</p>

Testing a drive with the drive control panel

1. 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.

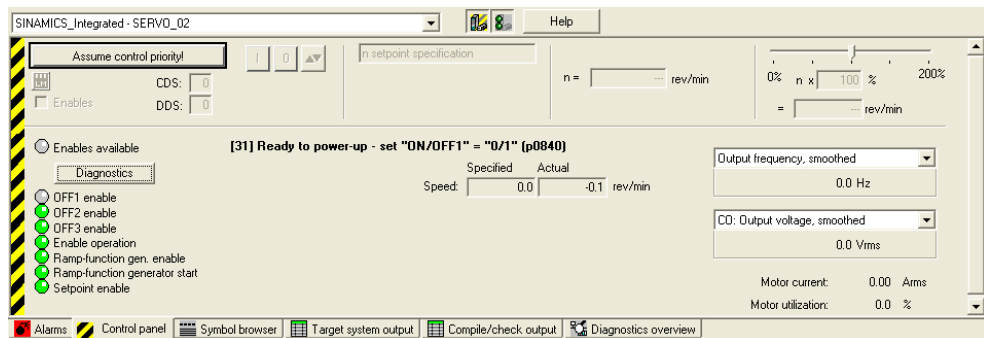


Figure 8-35 Drive control panel

2. To display the control area and axis diagnostics, click the "Show/hide control area" and "Show/hide diagnostics area" buttons.

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 p0864) 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).

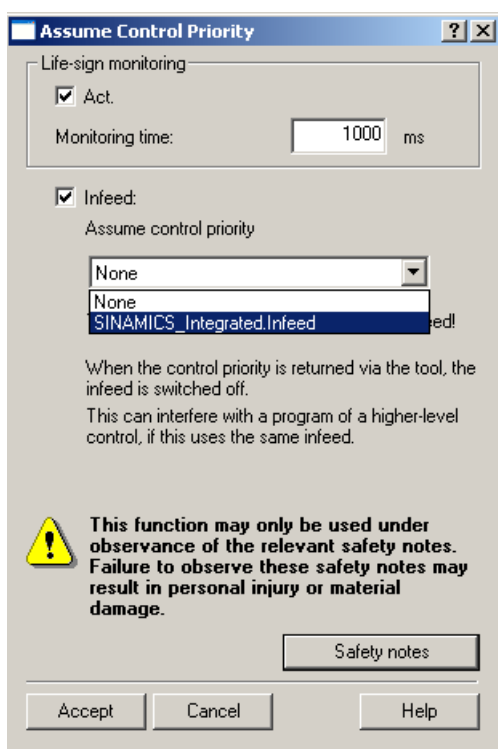


Figure 8-36 Assuming control priority

4. Read the notes and confirm these with "Accept."
5. Activate the "Enables" checkbox to enable the drive. All enables are now set with the exception of ON/OFF1.

6. Enter the desired setpoint in the entry field, and, as a safety setting, slide the scaling to 0%.

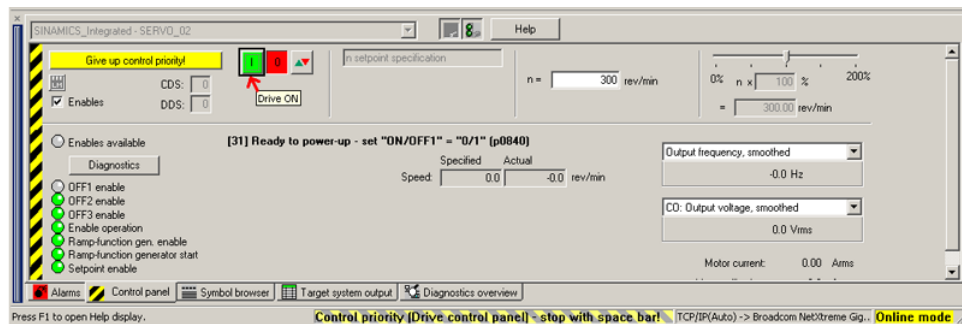


Figure 8-37 Entering a setpoint

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 in "Actual."
8. Click "Drive Off" to stop the drive after you completed 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.

8.7 Creating and testing axes

8.7.1 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. Provided you have completed the configuration at the drive end, we strongly recommend that SINAMICS Integrated is deactivated via "Target system" > "Select target device" in order to accelerate the process.
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 176)

Downloading a project to the CF card (Page 179)

8.7.2 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 fieldbus 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 "Use symbolic assignment" has been activated:

- 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."

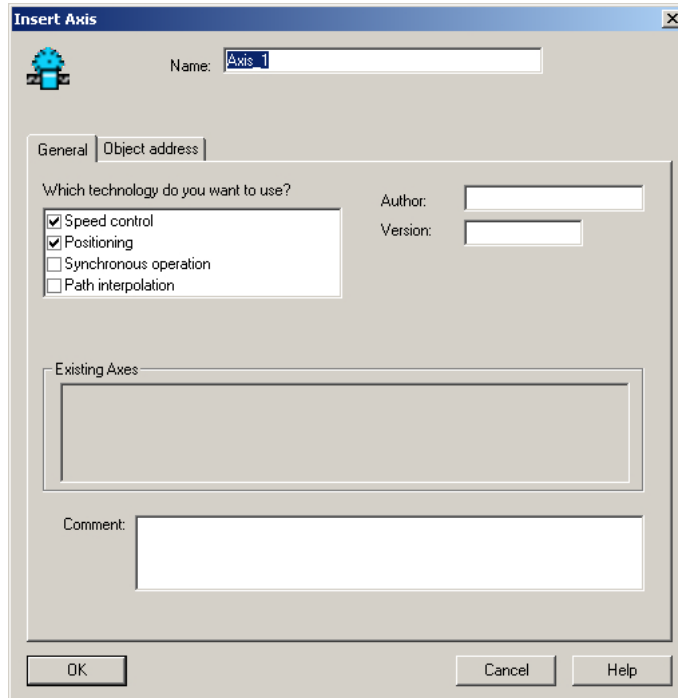


Figure 8-38 Inserting an axis

2. Set an axis type and, if required, configure the units.

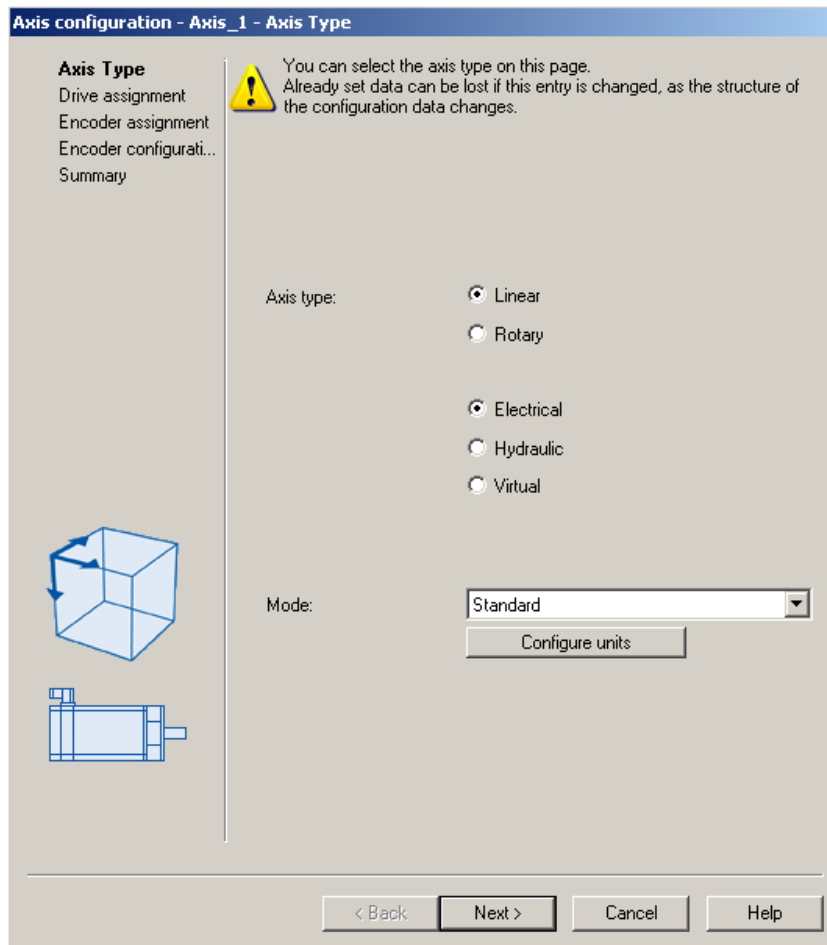


Figure 8-39 Defining the axis type

3. Create a new drive or make the assignment to an existing drive.

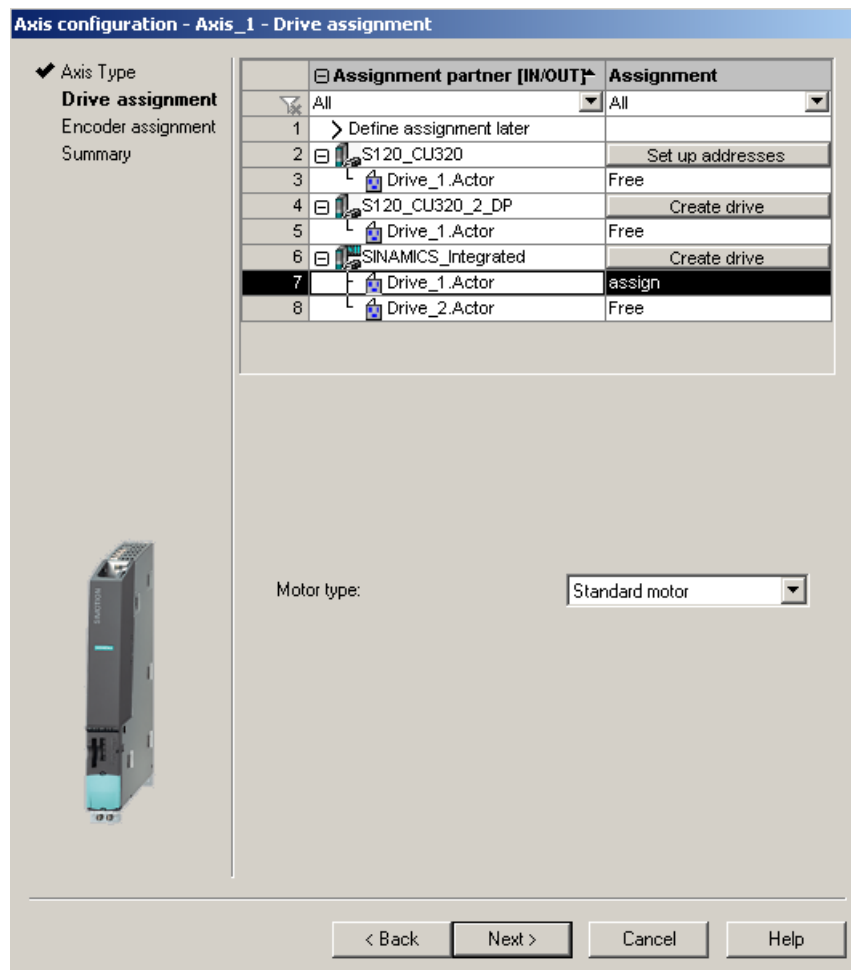



Figure 8-40 Assigning a drive

The following setting options are available for the drive assignment:

- Assign drive
Assigning a previously configured drive
- Define assignment later
The 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.
 - The technology objects to be symbolically assigned later to the drive objects via an interconnection dialog box.

8.7 Creating and testing axes

- **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 "Use symbolic assignment" has been deactivated. 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 firmware 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. Symbolic assignment must be deactivated for these methods.

1. Run through the wizard and enter the settings of your system. The required axis telegrams as well as the addresses used are automatically specified by the engineering system. Telegrams are also extended and interconnections created automatically in the drive depending on the selected TO technology (e.g. SINAMICS Safety Integrated).
2. Click **Finish** to confirm the "Summary" window.
The configured real axis is displayed in the project navigator.

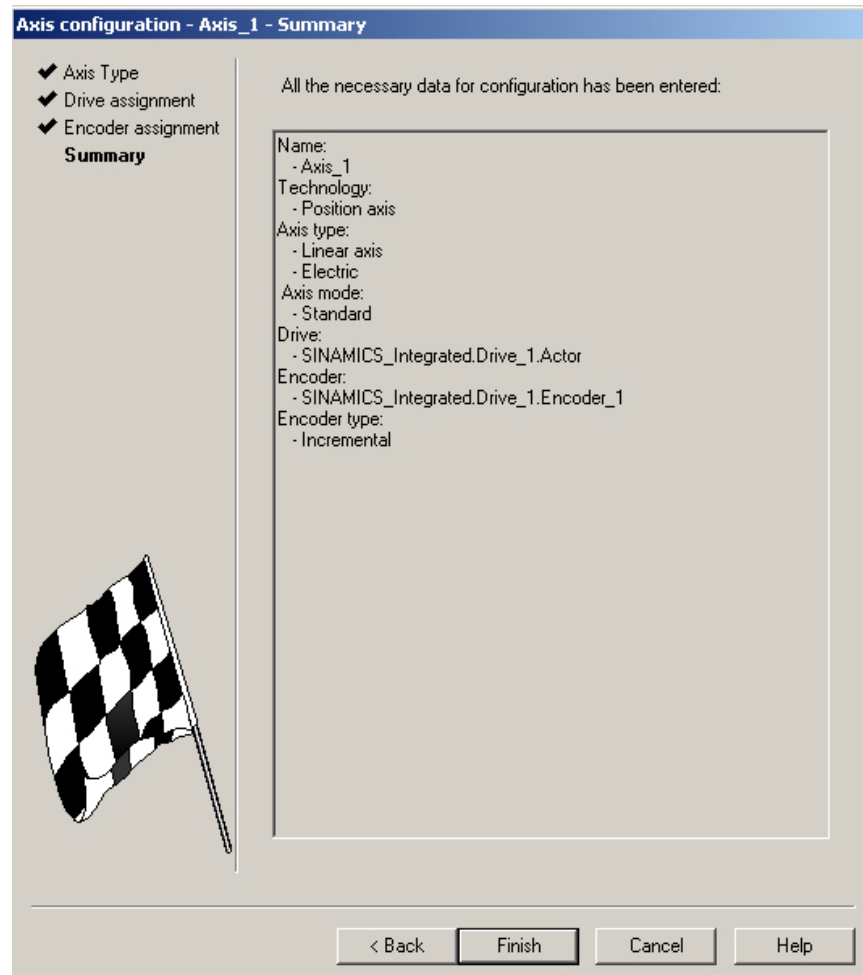


Figure 8-41 Axis wizard summary

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 on the TO axis (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 box, 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 telegram 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 telegram 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 TOs created or from the address list (view of all addresses) by clicking the "... " button.

See also

Downloading a project into the target system (Page 176).

For more information on symbolic assignment, see the *SIMOTION Runtime Basic Functions* Function Manual.

8.7.3 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.

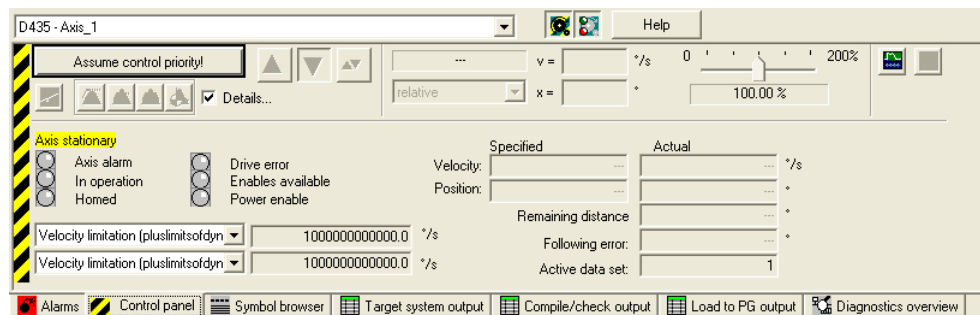


Figure 8-42 Axis control panel

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 box 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 p0864) 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 box 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 229)

8.8 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

8.8.1 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.

8.8 Activating the infeed (line module)

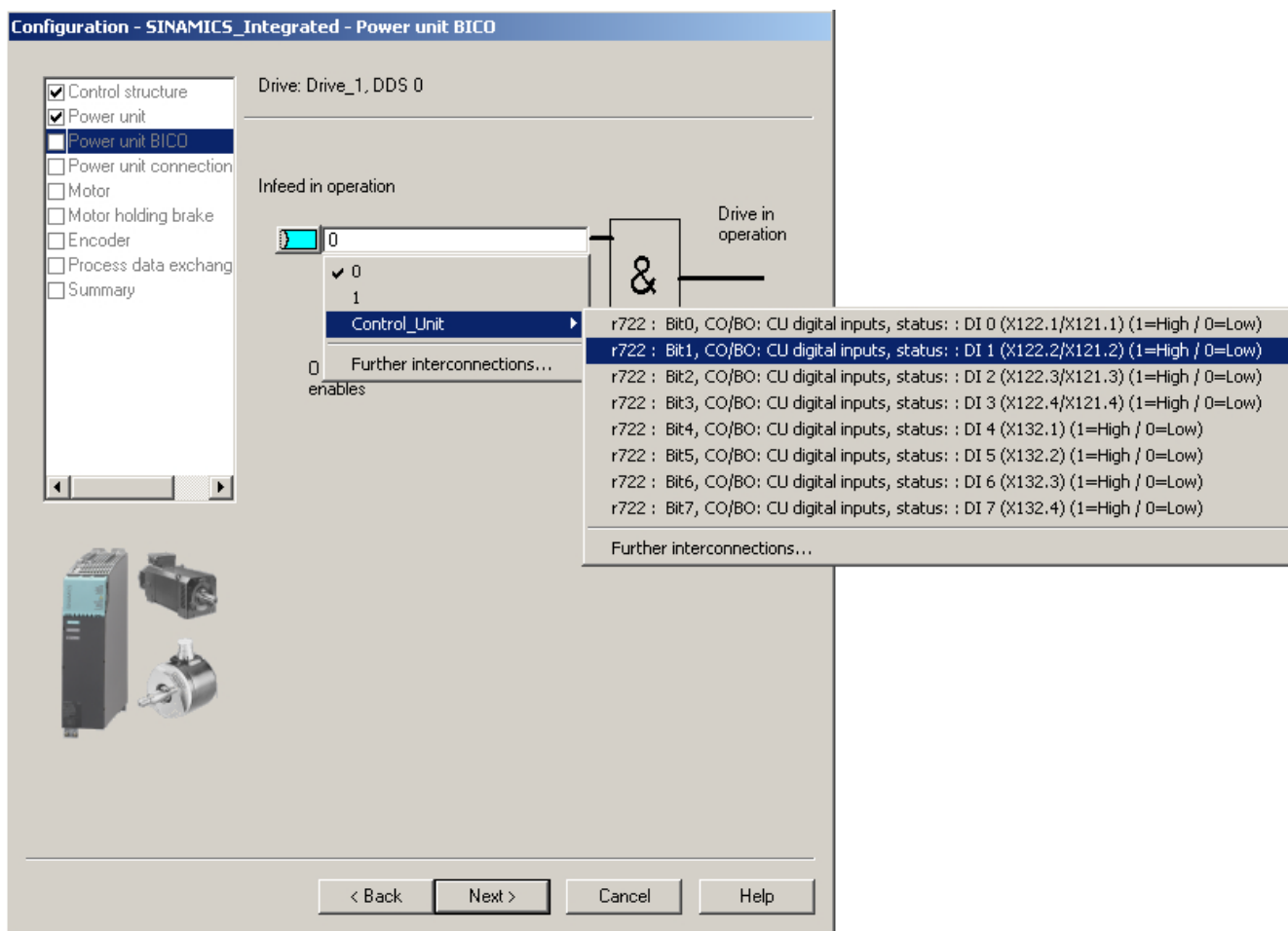


Figure 8-43 Interconnection of the "Infeed in operation" signal

8.8.2 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.

Message frame 370 is set automatically on configuration of Standard/automatic (see Calling the drive wizard (Page 156) section) if "Use symbolic assignment" has been enabled.

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 configured, the infeed signal "Closed-loop control operation, r0863.0" is automatically interconnected to "Infeed operation, p0864" 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" ⇒ "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 the Interconnecting the infeed "Operation" signal on the CX32 (Page 201) section.

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*.

8.8.3 Using one infeed for several CUs

If the infeed is controlled from another Control Unit, then the Ready for operation signal of the infeed (parameter r0863.0) must be connected to parameter p0864 "Infeed operation" of the drive via a digital input/output. If this is not taken into account, the infeed may be damaged.

An interconnection of the Ready for operation signal via PROFIBUS/PROFINET is not recommended because of the delay times (communication, evaluation in controller, etc.).

For a CX32, the Ready for operation signal of an infeed on SINAMICS Integrated can be simply interconnected to the drives of a CX32.

Further information on how to use line modules with the CX32 can be found in the Interconnecting the "Operational" Signal of the Infeed for the CX32 (Page 201) section.

8.9 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 232)
- Without symbolic assignment, the determination of the addresses must be started manually, see Section Message frame configuration (Page 232).

8.9.1 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 232)

8.9.2 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 telegram setting for a drive object should be activated/deactivated
- The automatic telegram extension for a drive object should be activated/deactivated

- The automatic address adaptation for a drive object should be activated/deactivated
- PROFIdrive telegrams should be configured for drive objects
- The addresses should be set up
- Telegrams should be extended manually

Procedure

Proceed as follows:

In the project navigator, open the "Communication" > "Telegram configuration" entry under "SINAMICS_Integrated."

The "SINAMICS Integrated - Telegram Configuration" dialog box is displayed with the PROFIdrive PZD telegrams 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.

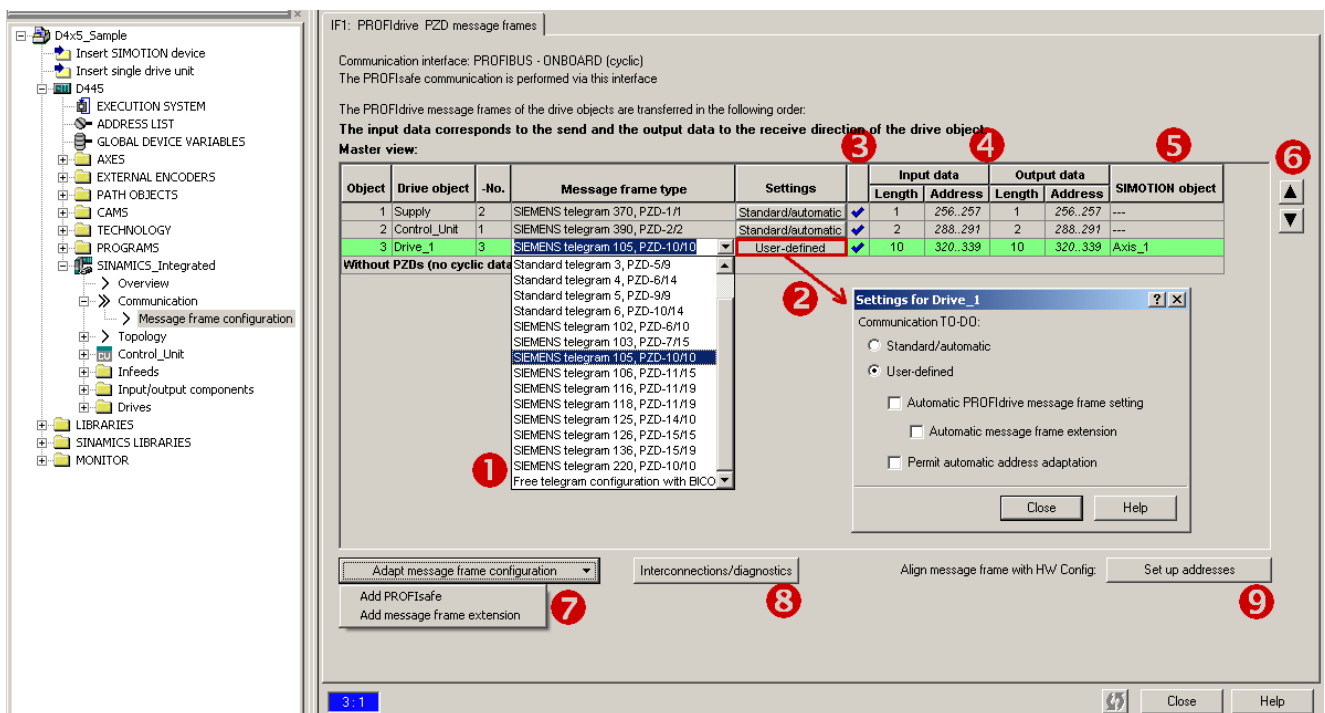














Figure 8-44 Telegram configuration

Table 8-7 Explanation of the figure

Number	Meaning										
1	<p>Selection of a telegram</p> <ul style="list-style-type: none"> The drive telegrams (telegrams 1 ... 6 and telegram 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 telegrams 39x. Telegram 39x is also required for the time synchronization between SIMOTION and SINAMICS. Free telegram configuration with BICO allows you to define your own telegram. Free telegram configuration with p0915/p0916 (for TM15/17). Telegrams 37x for control of the infeed. 										
2	<p>The "Standard/automatic" and "User-defined" settings are only visible if "Use symbolic assignment" is activated. Using the setting "Standard/automatic" is generally recommended.</p> <p>The "User-defined" setting allows the automatic telegram setting, telegram extension, and address adaptation to be deactivated or activated.</p> <ul style="list-style-type: none"> "Automatic PROFIdrive telegram setting" allows the telegram to be set by the system depending on the configured technology (telegram selection, e.g. for infeed, drive, and control unit incl. onboard I/O). "Automatic telegram extension" allows the telegram 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 telegram is extended and the adjacent addresses are already occupied by other telegrams. <p>With TM15/TM17 High Feature, "Automatic PROFIdrive telegram setting", "Automatic telegram extension", and "Automatic address adaptation" cannot be deactivated by design, since for these drive objects the telegram is always set up in accordance with the parameterized terminal functionality (DI, DO, output cam, measuring input) and cannot be extended.</p> <p>"Automatic PROFIdrive telegram setting" and "Automatic telegram extension" must be deactivated if the telegrams are to be configured manually for TM15 DI/DO, TM31, and TB30 and interconnected with BICO.</p> <p>See Section Setting up communication for symbolic assignment (Page 232).</p>										
3	<table border="1" data-bbox="264 1272 1235 1529"> <tr> <td colspan="2" data-bbox="264 1272 1235 1310">The icons in the status column show the following information:</td> </tr> <tr> <td data-bbox="264 1310 327 1370"></td> <td data-bbox="327 1310 1235 1370">The message frame is configured differently in HW Config. You must align it with HW Config.</td> </tr> <tr> <td data-bbox="264 1370 327 1408"></td> <td data-bbox="327 1370 1235 1408">You are using a predefined standard message frame or free BICO interconnection.</td> </tr> <tr> <td data-bbox="264 1408 327 1469"></td> <td data-bbox="327 1408 1235 1469">You are using a modified standard message frame, which you have extended to include additional data.</td> </tr> <tr> <td data-bbox="264 1469 327 1529"></td> <td data-bbox="327 1469 1235 1529">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.</td> </tr> </table> <p>Telegram status</p>	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.
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.										
4	<p>Length: Displays the size of the telegram component.</p> <p>Address: Address area in HW Config. The addresses will be displayed only after the addresses have been set up.</p>										
5	<p>Displays the SIMOTION object that is interconnected to the SINAMICS object (e.g. axis or encoder).</p>										
6	<p>Changing the telegram sequence</p> <p>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 ("???..???").</p>										
7	<p>"Manual" adaptation of the telegram configuration (e.g. when additional data, such as a motor temperature, is to be transferred via the telegram).</p>										

Number	Meaning
8	Display of the individual control and status words of the associated telegram.
9	Setting the addresses (alignment of the addresses with HW Config) Only the addresses of the respective device are determined (no automatic determination of telegrams / BICO interconnections)

Note

If symbolic assignment is deactivated, the following applies:

If the telegrams for drive objects (drives, Terminal Modules, etc.) change, you must set up the addresses again. The addresses are not updated automatically.

Error correction (symbolic assignment deactivated)

Based on the 39x telegram, SIMOTION generates further configuration information (FastIO configuration) for the following functions:

- Time-of-day synchronization SIMOTION ↔ SINAMICS
- Use of onboard I/Os of SIMOTION D, CU, or CX
- Use of cams and global measuring inputs
- System function `_setDriveObjectSTW`

If the telegrams are defined manually (symbolic assignment is deactivated), a telegram 39x must be set up in the telegram configuration. The telegram then has to be aligned with HW Config via "Set up addresses."

If use of the functions stated above is not possible, generate the FastIO configuration anew. For this purpose select in the project tree the affected SIMOTION D Control Unit, the SINAMICS CU or Controller Extension CX and open the "FastIO" > "Create new configuration" shortcut menu with the right mouse button. Then compile the project and load it into the CPU. Perform a restart.

The FastIO configuration is also used for the telegram of the Terminal Modules TM15 and TM17 High Feature. Proceed in the same way if problems occur.

8.10 Linking an additional encoder (optional)

8.10.1 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/CU310-2 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

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 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

8.10.2 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.

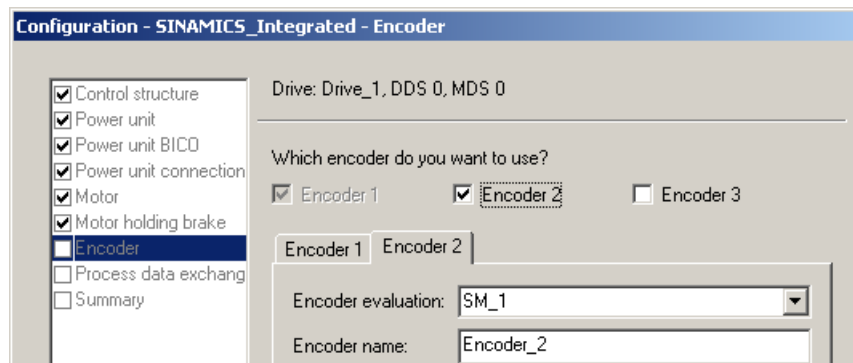


Figure 8-45 Configuration of a second encoder on the drive

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. it is only available on Control Units of the latest generation (e.g. SINAMICS S120 CU320-2, SIMOTION D4x5-2, CX32-2 --- but not for SINAMICS Integrated of a D4x5 and CX32)

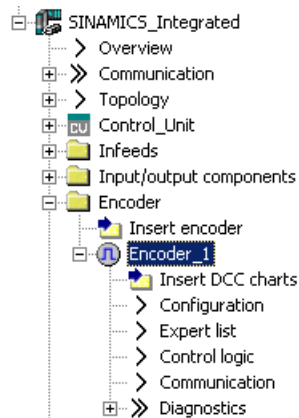


Figure 8-46 Configuration of an encoder as drive object

8.10.3 Additional encoders via PROFIBUS/PROFINET

Additional encoders for the encoder integration can be connected via PROFIBUS or PROFINET. The following options are available:

- Encoder interface using a PROFIdrive message frame (encoder with message frame type 81 and 83)
- 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

8.11 Symbolic assignment of I/O variables (PROFIdrive message frame / drive parameters)

8.11.1 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

8.11 Symbolic assignment of I/O variables (PROFIdrive message frame / drive parameters)

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.

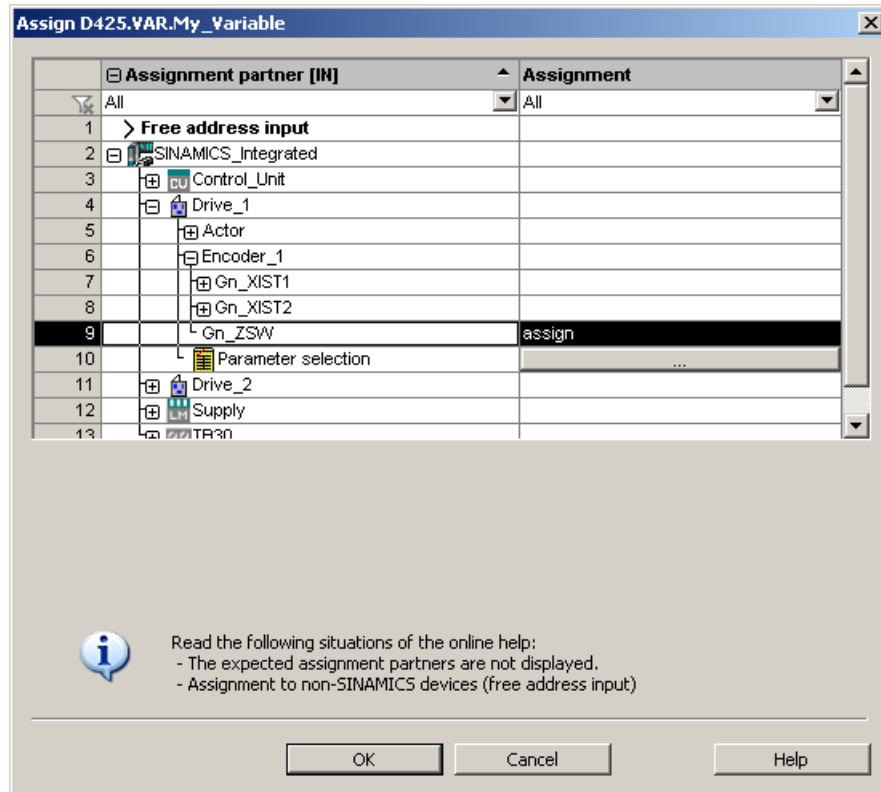



Figure 8-47 Assignment of I/O variables to the PROFIdrive message frame

8.11.2 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

1. Open the assignment dialog box from the address list (view of all addresses).
The assignment dialog box opens with the corresponding assignment partners.
2. Click the  button in the parameter selection line to open the parameter list.

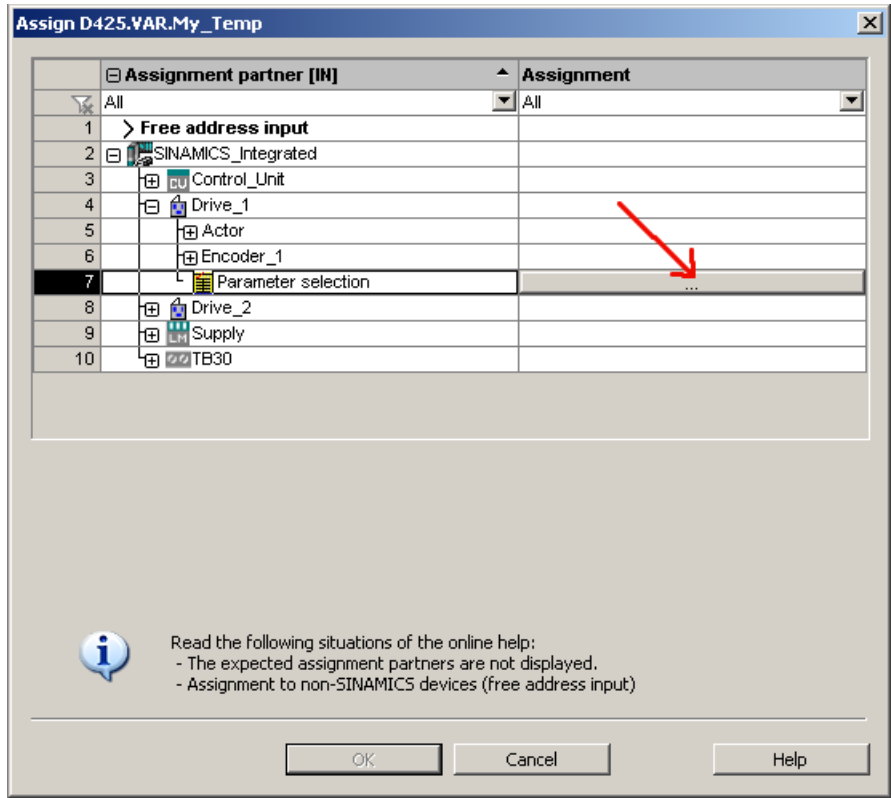


Figure 8-48 Assignment dialog box for drive parameters

8.11 Symbolic assignment of I/O variables (PROFdrive message frame / drive parameters)

3. Select the desired signal source (e.g. DO drive). Then select the required parameter.

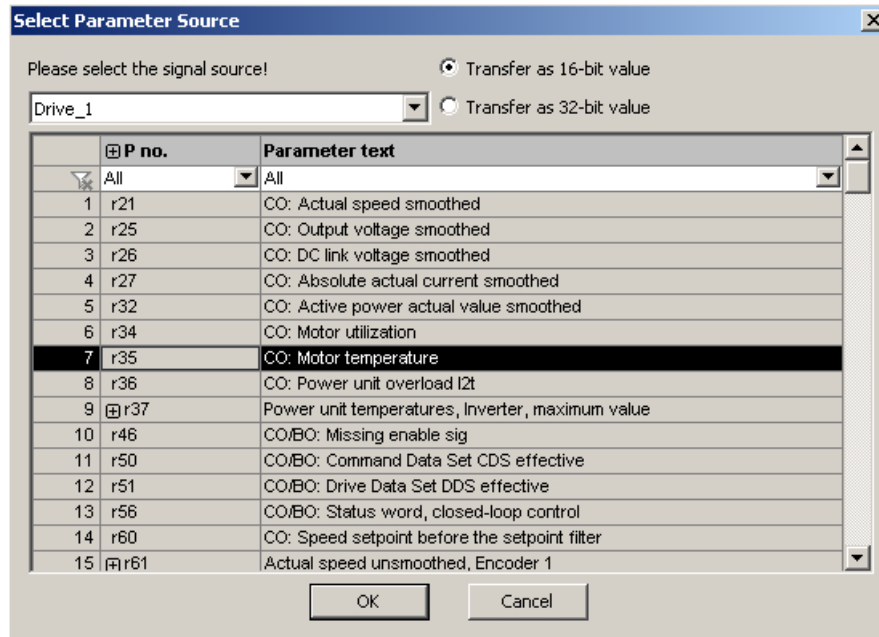


Figure 8-49 Dialog box for the DO and parameter selection

4. Click "OK" to accept the selection.

- The desired SINAMICS parameter is assigned to the I/O variable in the interconnection dialog box.

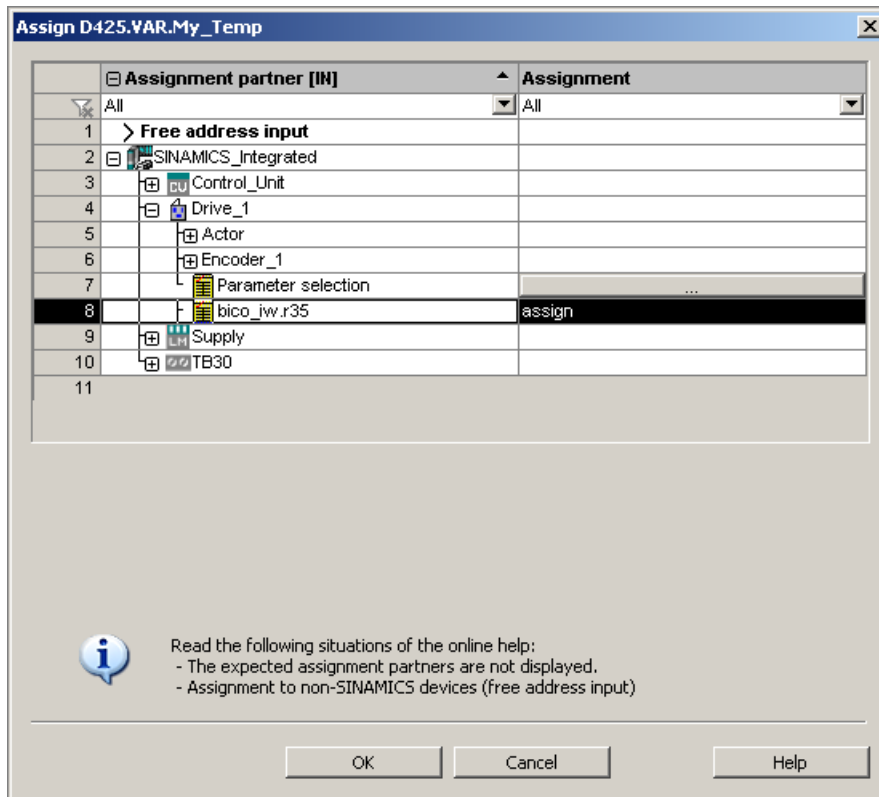


Figure 8-50 Assigned drive parameters

- 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>	WORD	Input	All CO parameters (BICO source)
BICO_QW.<parameter number>	WORD	Output	All CI parameters (BICO sink)
BICO_ID.<parameter number>	DWORD	Input	All CO parameters (BICO source)
BICO_QD.<parameter number>	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].

8.12 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 149))

The symbolic assignment simplifies the configuration significantly:

Table 8-8 Comparison of configuration with/without symbolic assignment

	With symbolic assignment	Without symbolic assignment
Configuring telegrams	So that SIMOTION can use SINAMICS I/Os, the required telegrams are created automatically	Telegrams must be set manually (either predefined telegram (e.g. 39x) or free telegram configuration)
BICO interconnections	The required BICO interconnections are made automatically (I/Os are interconnected to telegram)	With predefined telegrams (e.g. 39x), the BICO interconnections are made automatically With free telegram 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 232)	Addresses must be set up manually, see also Section Telegram configuration (Page 232)

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 341).

8.12 Configuration of drive-related I/Os (with symbolic assignment)

Procedure

The configuration of the I/Os is divided into 2 basic steps:

1. Configuration of the I/O terminals (Page 244). The functionality of an I/O channel is configured (e.g. configuration of a DI/DO as digital output)
2. Configuration of the technology objects and I/O variables (Page 247).
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 measuring input, only symbolic assignments of the type MI (measuring input = measuring input input) are offered for selection.

The required telegrams and the interconnection are then set automatically by the engineering system.

8.12.1 Configuration of the I/O terminals

The following table provides an overview of the configuration options for the I/O terminals of various modules.

Table 8-9 Overview of the configuration of the I/O terminals

Module	Use of the I/Os by		Configuration of the I/O terminals	Supports symbolic assignment
SIMOTION	SINAMICS			
SIMOTION D4x5-2 • X122/X132 • X142	• X ¹⁾ • X	• X • -	• On the drive unit (CU) • On the D4x5-2 (HW Config)	As of SIMOTION V4.2
SIMOTION D4x5	X ¹⁾	X	On the drive unit (CU)	As of SIMOTION V4.2
CX32-2, CX32	X ¹⁾	X	On the drive unit (CU)	As of SIMOTION V4.2
SINAMICS S110 CU305	X ¹⁾	X	On the drive unit (CU)	As of SINAMICS V4.3
SINAMICS S120 • CU310 • CU310-2 • CU320 • CU320-2	X ¹⁾	X	On the drive unit (CU)	• As of SINAMICS V2.6.2 • As of SINAMICS V4.4 • As of SINAMICS V2.6.2 • As of SINAMICS V4.3
TB30, TM15 DI/DO, TM31	X ¹⁾	X	On the drive unit (TB30 or TM)	Yes
TM41	X ¹⁾	X	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 supports symbolic assignment only for encoder interfaces (not symbolic assignment for 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 245)
- Configuration of the CX32/CU3xx/TB30/TMxx I/O terminals (Page 246)

8.12.1.1 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)"

8.12 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)"

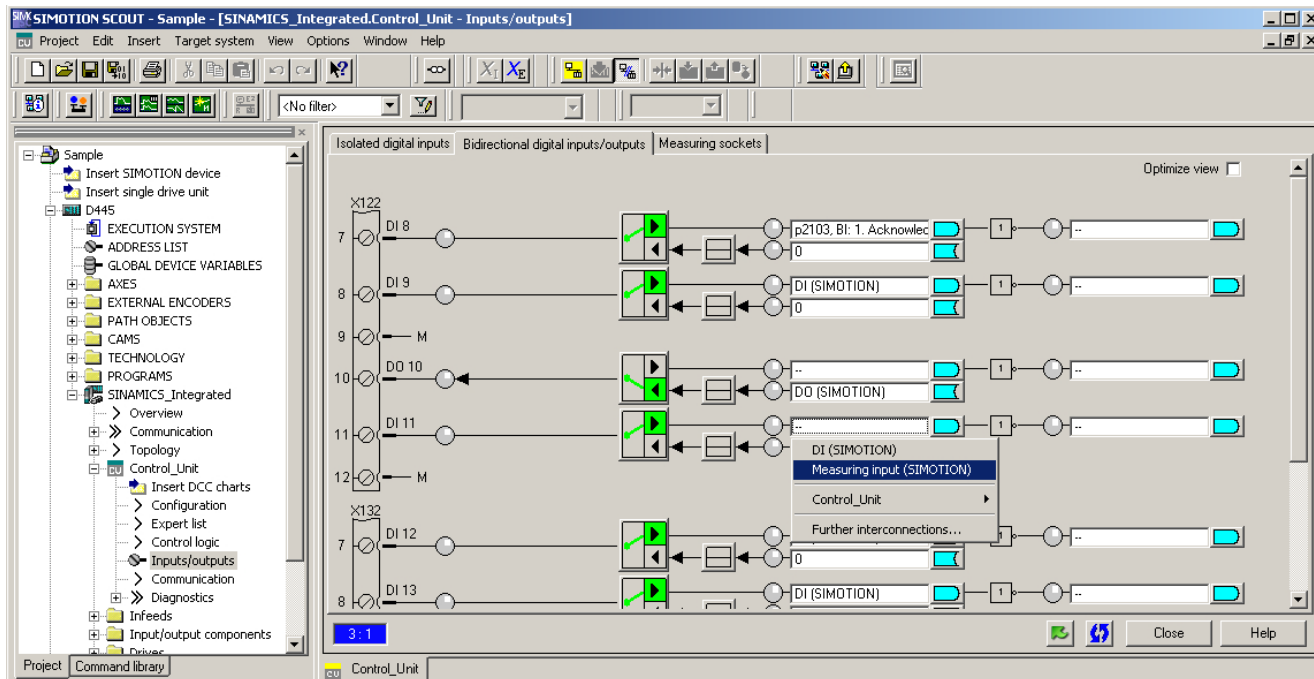


Figure 8-51 Configuration of the D4x5 I/Os (terminal X122/X132)

8.12.1.2 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 245)

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 149)

8.13 Configuration of the technology objects and I/O variables

8.13.1 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 8-10 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 341) 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 341) 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")

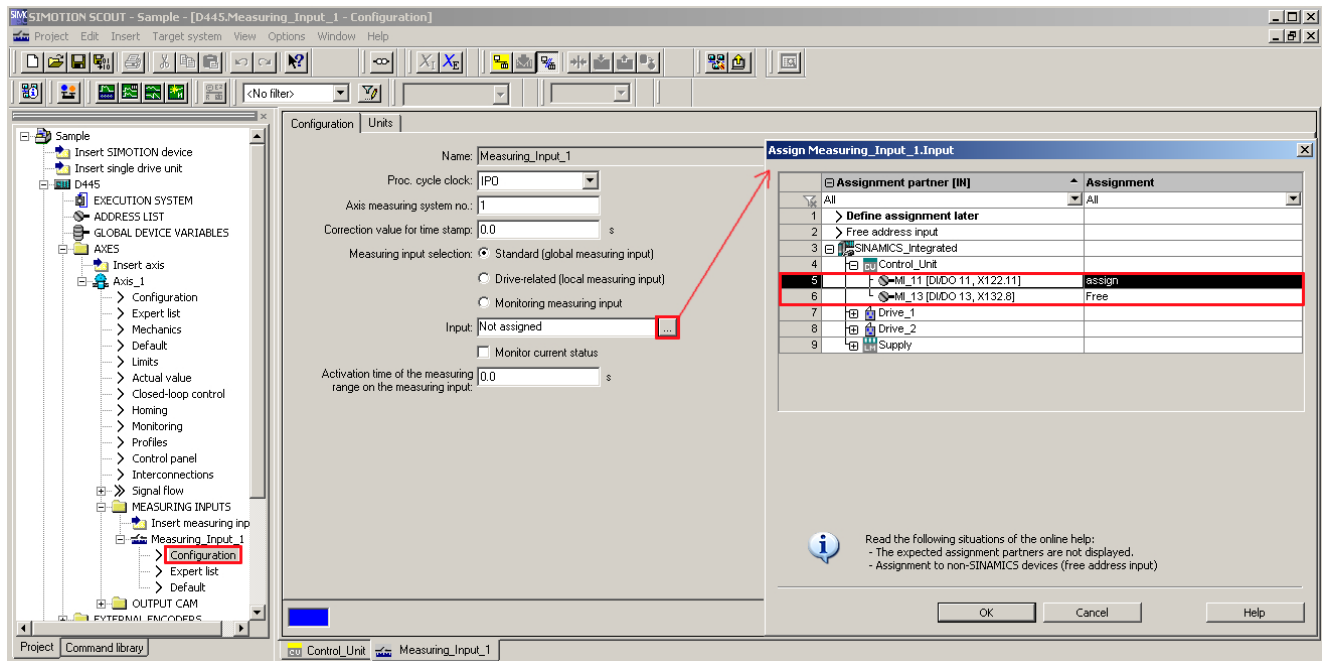


Figure 8-52 Configuration of a global measuring input for the D4x5

Detailed information on the configuration of the TO measuringInput can be found in the *SIMOTION Output Cams and Measuring Inputs Function Manual*.

8.13.2 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 341) in the appendix
- *SIMOTION Output Cams and Measuring Inputs Function Manual*

8.13.3 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:

Table 8-11 TO outputCam / TO camTrack output types

Cam output on...	Explanation
Output cam output (CAM)	<p>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.</p> <p>Supported hardware:</p> <ul style="list-style-type: none"> • SIMOTION D4x5-2 (terminal X142): Resolution 1 μs • TM17 High Feature: Resolution 1 μs • TM15: Typical resolution 125 μs (DRIVE-CLiQ cycle clock) • D410-2 (DI/DO 8 to 15): Typical resolution 125 μs
High-speed digital output (DO)	<p>The cam output is performed via onboard outputs of the SIMOTION CPU. The output is via a hardware timer and the cam output is achieved with a resolution with respect to time < servo cycle.</p> <p>Supported hardware:</p> <ul style="list-style-type: none"> • SIMOTION D4x5 (terminal X122, X132) • SIMOTION D410 (terminal X121) • SIMOTION C240, C240 PN (terminal X1)
Standard digital output (DO)	<p>The output cam calculations are performed in the processing cycle (IPO or IPO2 cycle or in the servo cycle). Actual cam output is performed in servo cycles. The resolution with respect to time of the cam output is generally reduced by the output cycle of the I/O used.</p> <p>The resolution is therefore dependent as follows:</p> <ul style="list-style-type: none"> • For the standard I/O (e.g. ET 200), on the cycle time of the bus system (PROFIBUS DP / PROFINET I/O) • 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: <ul style="list-style-type: none"> – cu.p0799 (CU inputs/outputs sampling time) for the onboard outputs – p4099 (TMxx inputs/outputs sampling time) for TB30, TM15 DI/DO, TM31, and TM41 <p>Supported hardware:</p> <ul style="list-style-type: none"> • Onboard outputs (SIMOTION D, controller extension CX, SINAMICS control unit CU3xx) • Centralized I/O (SIMOTION C) • Distributed I/O via PROFIBUS DP/PROFINET I/O (e.g. ET 200, ...) • Drive-related I/O (TM15, TM15 DI/DO, TM17 High Feature, TM31, TM41, TB30)

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")

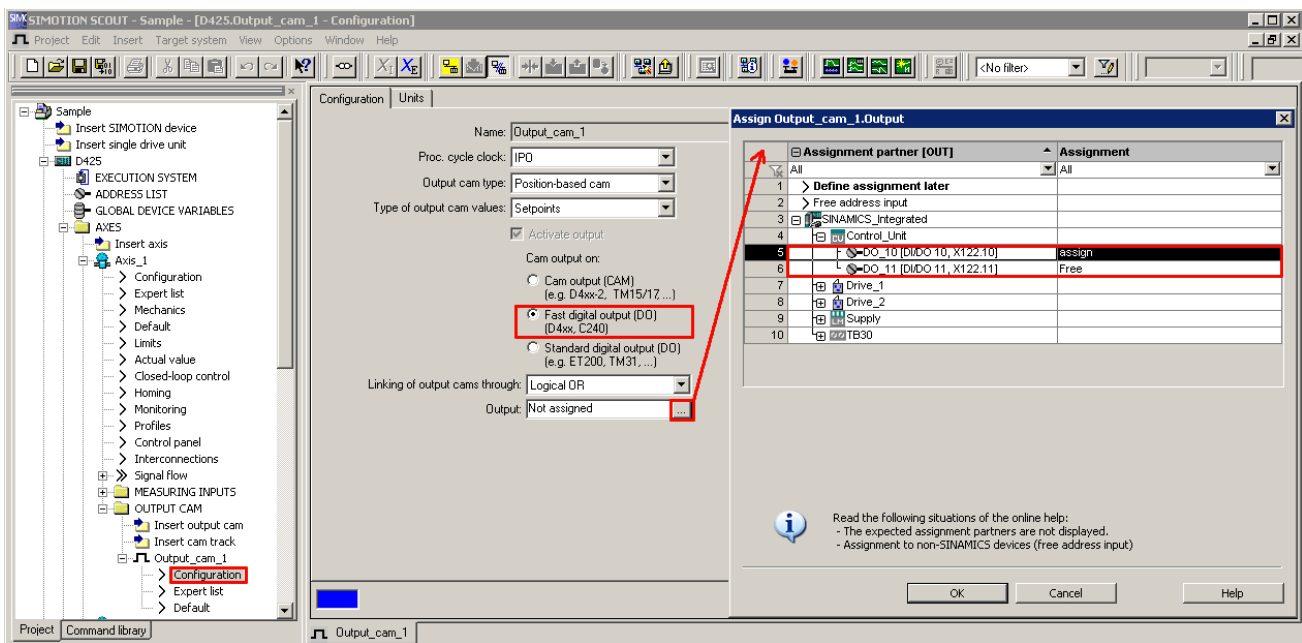


Figure 8-53 Configuration of an output cam for the D4x5

Detailed information on the configuration of the TO outputCam / TO camTrack can be found in the *SIMOTION Output Cams and Measuring Inputs* Function Manual.

8.13.4 Configuration of the I/Os (variables / TO axis)

You have two options for assigning I/O terminals to an I/O variable:

- Assignment via preferential link (e.g. DI_0 [DI 0, X122.1])
To do this, you must use the SIMOTION preferential link for the corresponding input/outputs of the SINAMICS DO. The BICO link is automatically executed.
- Assignment via PZD (e.g. via DI_0_15 or DO_0_15).
Please note for these signals that the BICO interconnection is not executed, although a message frame of the appropriate length is generated.

Interconnection via preferential link

The I/O variables are configured via the address list. Components that support a symbolic assignment can be configured without I/O addresses.

Preferential links are displayed as assignment targets in the assignment dialog box. (E.g. DI_0 [DI 0, X122.1]). The links are assigned by means of direct selection of the corresponding terminal signal.

Components that do not support symbolic assignment (e.g. standard PROFIBUS I/O) are configured via I/O addresses.

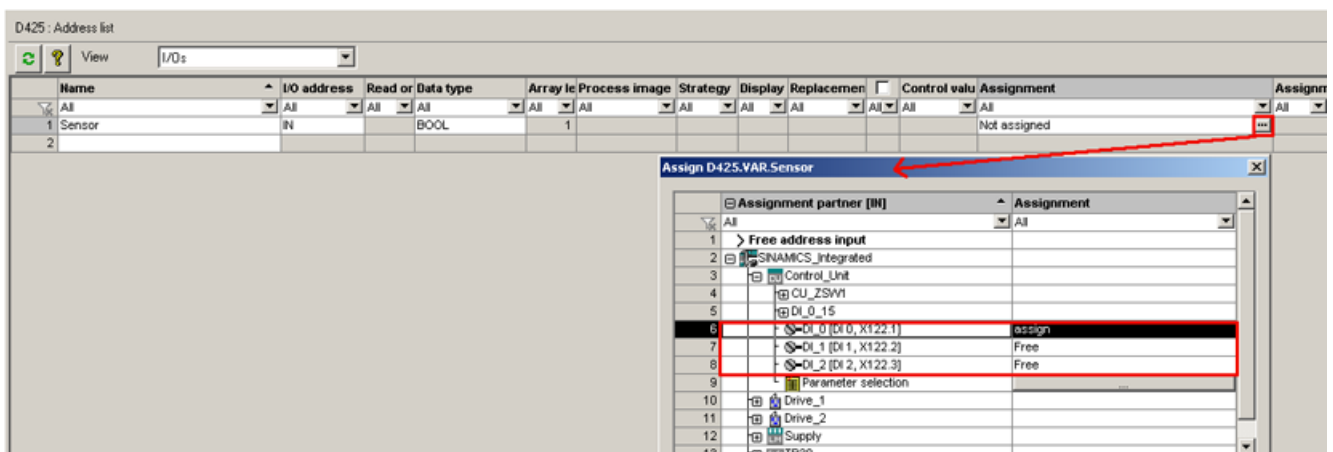


Figure 8-54 Address list

Interconnection via PZD

In principle, assignment via PZD is also supported (e.g. via DI_0_15 or DO_0_15). Please note for these signals that the BICO interconnection is not executed, although a message frame of the appropriate length is generated.

For this purpose, switch to the "Communication" dialog box for the relevant SINAMICS DO. You can now see the individual bits of the PZD (e.g. I_Digital or O_Digital) listed there. Interconnect the corresponding bit of the PZD with a signal.

Alternatively, you can assign SIMOTION to an I/O channel in terminal configuration (e.g. by selecting "DI (SIMOTION)", see Configuration of the D4x5 I/Os (terminal X122/X132) (Page 245) Section.

TO Axis

The symbolic assignment of I/Os is also supported by the TO axis (e.g. for a HW limit switch).

Replacement values for I/O variables

Replacement values cannot be specified for input variables of the BOOL data type. If you do require replacement 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 replacement value.
The appropriate bit of the replacement value must then contain the replacement value for the BOOL variable.
In the same way, you can assign a replacement value to a BICO parameter.

For various SINAMICS drive objects, higher-level types are available for the assignment of replacement values.

Name	Data type	Array le	Process image	Strategy	Display	Replacemen	Control valu	Assignment	Assignnr	Comment
All	BOOL	All	All	All	All	All	All	All	All	All
1 Sensor	BOOL	1						SINAMICS_Integrated.Control_Unit.DI_0 [DI 0, X122.1]	4	Set up
2 All_inputs	WORD	1		Ersatzw...	HEX	16#00_00		SINAMICS_Integrated.Control_Unit.DI_0_15	4	Set up
3										

Figure 8-55 Configuration of replacement values

8.14 DMC20/DME20 DRIVE-CLiQ hub

8.14.1 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*.

8.14.2 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.
2. 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.

8.15 TM41 Terminal Module

8.15.1 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.

8.15.2 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**.

8.15.3 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 a 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.

8.16 Optimizing drive and closed-loop controller

8.16.1 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.

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 259) and Manual speed controller optimization (Page 260) in this manual).

8.16.2 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 K_p and the integral time T_n 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.

8.16.3 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).

8.16 Optimizing drive and closed-loop controller

- 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 ($\text{PositionTimeConstant} = 1/K_v$).
- 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 K_v factor is to be transferred.
7. Click "Accept values" to transfer the calculated K_v 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.

8.16.4 Measuring functions, trace, and function generator

Drive optimization

Drive optimization is part of commissioning and can be performed with SIMOTION SCOUT.

Note

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).

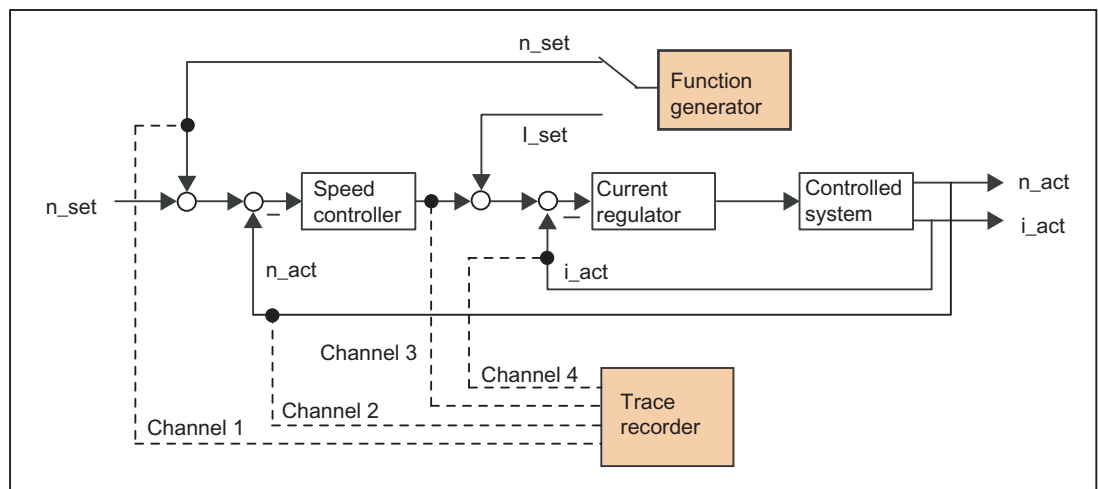


Figure 8-56 Optimizing a controller

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 jump at current controller
- Reference frequency response at current controller

8.16 Optimizing drive and closed-loop controller

- Setpoint jump at speed controller
- Disturbance variable jump 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*.

8.16.5 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.
2. Click  to call the "Measuring Functions" dialog box. The activated Service function is displayed via the LEDs (RUN flashes green at 2 Hz and SU/PF flashes yellow at 2 Hz)
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".

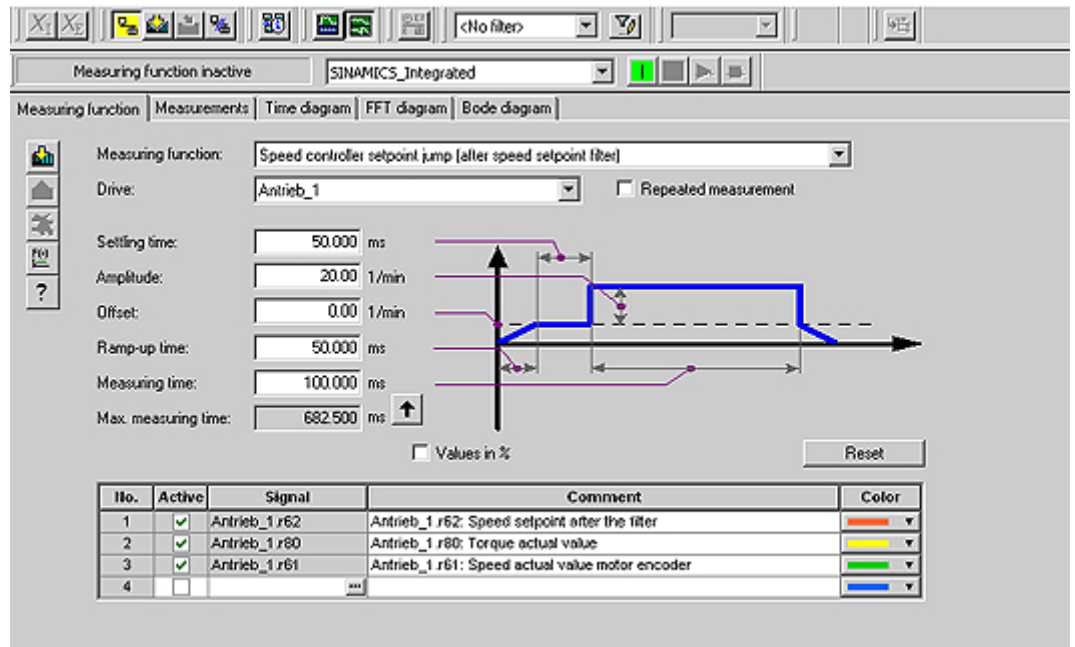


Figure 8-57 Speed controller measuring function

Four channels can be traced. Certain channels are preassigned, depending on the measuring function.

- Download the changes to the drive by clicking  (Download parameter assignment).

Starting the measuring function

- Click "Assume control priority" to assume control priority.
Read the notice that appears and click "Accept" to confirm.
- 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.
4. The traced signals are represented on the "Time diagram" tab.



Figure 8-58 Time diagram before parameter change

Adjusting the P-gain

You can adjust the P-gain of the controller to optimize the transient response.

1. 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 box.
2. Enter an appropriate value in the "P-gain" field and the "Integral time" field.

Note

The values entered take immediate effect.

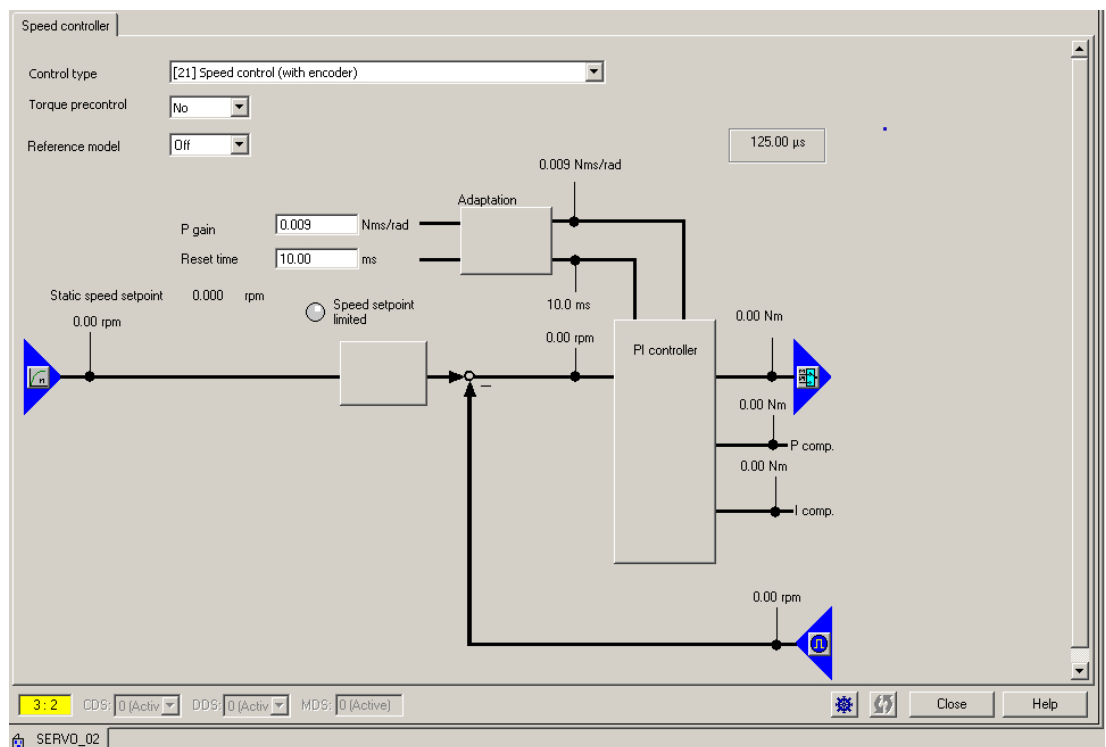


Figure 8-59 Entering P-gain

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 8-60 Measurement with modified P-gain

8.17 Downloading and saving SIMOTION 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 "volatile data" area of the SIMOTION D4x5:

- Configuration data
- Programs
- Parameterization
- Technology packages

The hardware configuration of SIMOTION D4x5 and the retain variables are also saved to the "non-volatile SIMOTION 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" > "Load CPU / drive unit to target device" only loads the data of the selected device / drive element to the target device.

The content of the "volatile SIMOTION data" area is lost when the SIMOTION D4x5 is switched off.

Additional information on the SIMOTION SCOUT Engineering System can be found in the *SIMOTION SCOUT* Configuration Manual.

Saving 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 SIMOTION data" area
- Current data values are copied to the "volatile SIMOTION data" area, depending on the settings in SIMOTION SCOUT.

Note

The "Copy RAM to ROM" command **cannot** be used to save the current values of retain variables to the CF card.

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 switches) or the SIMOTION IT web server
See Section Backup of diagnostic data and non-volatile SIMOTION data (Page 330).

With the SCOUT functions "Save variables" and "Restore variables," you also have the option of backing up to your PC and restoring data that were 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 102)

8.18 Deleting data

8.18.1 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 266)
- Deleting user data on CompactFlash card (Page 269)
- Setting SINAMICS Integrated to the factory settings (Page 270)
- Setting SIMOTION D4x5 to the default settings (Page 270)
- Deleting/restoring non-volatile SIMOTION data (Page 336)

8.18.2 Overall reset of SIMOTION D4x5

Introduction

During the memory reset, the memory of the SIMOTION D4x5 and the non-volatile SIMOTION data in the SRAM (with the exception of the communication configuration (baud rates, network addresses, etc.), are deleted. The data on the CF card is retained during the memory reset.

You must perform a memory reset of SIMOTION D4x5:

- If you want to undo changes made to user data (programs, configuration data, parameter assignments) which you have not backed up by means of the "Copy RAM to ROM" 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 SIMOTION 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 switch on the SIMOTION D4x5.

Data deleted on memory reset

The following data are 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 are deleted during a memory reset and must therefore be readjusted after the memory reset.

Data retained during memory reset

The following data are retained during a memory reset:

- TCP/IP parameters and DP parameters
- Diagnostic buffer
- Data saved with the **_savePersistentMemoryData**, **_saveUnitDataSet** or **_exportUnitDataSet** system functions and the "Copy RAM to ROM" function.
If backup files (PMEMORY.XML/PMEMORY.BAK) backed up with **_savePersistentMemoryData** exist, the data in these files is restored to the non-volatile SIMOTION data after the memory reset. The user can therefore perform a memory reset to force the backed up non-volatile SIMOTION 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 "volatile SIMOTION 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

The SIMOTION device for which overall reset is to be performed must be online.

1. Open the "Control Operating State" dialog box in SIMOTION SCOUT. Select the "Target system" > "Control operating state" menu command. Or click on "Control Operating State" on the toolbar.
2. Switch the SIMOTION device for which memory reset is to be performed to STOP in the "Control Operating State" dialog box.
3. Select the SIMOTION device under "Memory reset (MRES)." Click the "Run" button. Confirm the command by clicking "Yes."
The memory reset will now be performed.

Memory reset with the mode switch

You can perform a memory reset with the mode switch if you are offline with the SIMOTION D4x5.

NOTICE

Damage from electrostatic discharge

The rotary switch can be destroyed by static electricity.

Operate the rotary switch only with an insulated screwdriver.

Comply with the ESD rules.

Proceed as follows to reset the memory:

1. Place the mode switch in the STOP position (switch setting 2, see figure below).

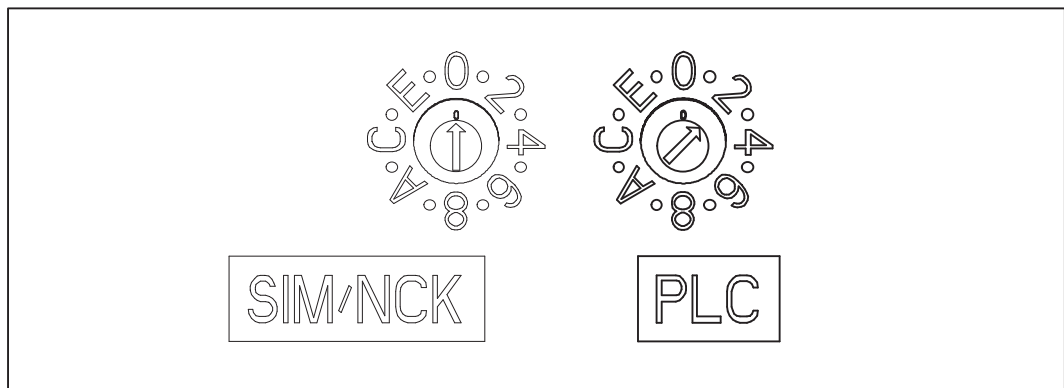


Figure 8-61 Memory reset with the mode switch (STOP position)

2. 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 selector 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 memory reset when the STOP LED lights up steady yellow.

Note

If you do not return the mode switch 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 switch back to the required operating mode.

NOTICE**Unintentional restoration of the default settings instead of memory reset**

Note that the MRES position (switch position 3) during power-up causes the default settings to be restored. See Section Setting SIMOTION D4x5 to the default settings (Page 270).

Make sure you do not accidentally switch the power supply OFF/ON in the MRES selector setting, as this restores the default settings instead of performing the desired memory reset.

8.18.3 Deleting user data from CF card

Overview

Deletion of the user data from the CompactFlash Card is necessary, for instance, if you wish to load another (new) project to the CompactFlash Card and therefore find it necessary to delete the existing user data for an old project (e.g. unit data sets) from the CompactFlash 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 CompactFlash 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 CompactFlash 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 299)

8.18.4 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.

8.18.5 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. This will delete the following data:

- Non-volatile SIMOTION data in the SIMOTION device
- The backup copy of non-volatile SIMOTION data on the CF card (PMEMORY.XML/PMEMORY.BAK)
- User data in the "volatile SIMOTION data" area and on the CF card
- The communication configuration (IP and DP parameters) on the CF card is set to the factory settings.

The licenses on the CF 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).
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 state.

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. The existing IP settings for the CBE30 are restored to the default settings.

8.19 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.

8.20 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

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)

8.20 Configuring Safety Integrated functions

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.

Further information on support of the SINAMICS Safety Integrated functions on the TO axis can be found in the *TO Axis Electric/Hydraulic, External Encoder* Function Manual.

Required hardware

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 8-12 SIMOTION D4x5 quantity structures

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

Control Unit	Maximum number of servo drives when safety function is activated			
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) PROFIBUS with PROFIsafe:

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) PROFINET with PROFIsafe:

The maximum permissible quantity structure for the D4x5 is 64 drives (< V4.2 SP1 HF1: 42 drives) with Safety Integrated function (sum of drives on SINAMICS Integrated, CX32 and SINAMICS Control Units).

The maximum drive quantity structure depends on other factors. For example with $T_I = 125 \mu s$, a maximum of four motor modules may be operated with Safety Integrated extended functions on a DRIVE-CLiQ line. Additional drive components (e.g. line modules, terminal modules, encoders, etc.) can also reduce the maximum drive quantity structure.

Recommendation:

With the SIZER configuration tool, you can easily configure the SINAMICS S110/120 drive family including SIMOTION.

For further information refer to

- *SINAMICS S120* Function Manual (FM1), Section *Rules for wiring with DRIVE-CLiQ*
- *SINAMICS S120 Safety Integrated* Function Manual

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).

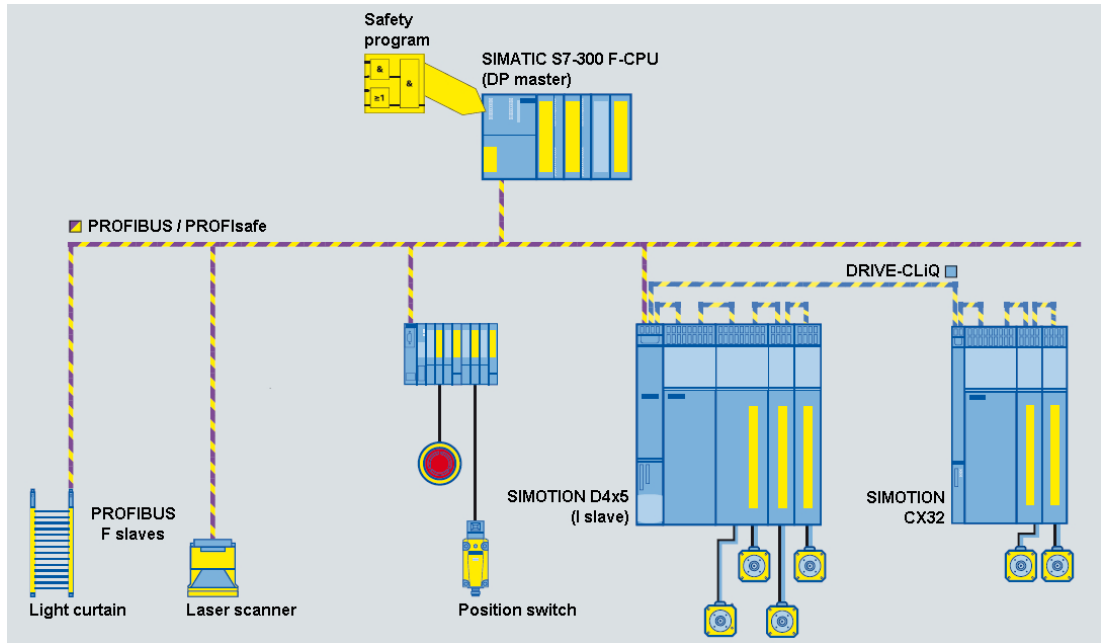


Figure 8-62 SIMOTION D, control of F functions via PROFIBUS with PROFI-safe

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
See also application example at (<http://support.automation.siemens.com/WW/view/en/38701812>).

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

8.21 Migration D445 to D445-1

8.21.1 Overview

Features

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 8-63 SIMOTION D445-1 Control Unit

Requirements

Components		Comment
Designation	Version	
SIMOTION SCOUT	as of V4.1 SP2	Full support for SIMOTION D445-1 configuration

	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 upgrading firmware, see the Performing a firmware and project upgrade (Page 303) Section.
SIMOTION D445-1 hardware	as of hardware version A	Order number 6AU1445-0AA00-0AA1
CompactFlash cards (CF cards) supported by SIMOTION D445-1	- - -	1-GB CF Card (6AU1400-2PA03-0AA0) 1-GB CF Card (6AU1400-2PA02-0AA0) 1-GB CF Card (6AU1400-2PA01-0AA0) 1-GB CF Card (6AU1400-2PA00-0AA0) 512-MB CF Card (6AU1400-2NA00-0AA0) 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 ≥ V4.1 SP2 HF3.

You will find detailed information on the compatibility relationships for the CF card, boot loader version, SIMOTION D hardware and SIMOTION firmware version in the software compatibility list. You can find this list both in the documentation that comes with the SIMOTION SCOUT DVD under \1_Important\Germany\Kompatibilitaet\... and on the Internet (<http://support.automation.siemens.com/WW/view/en/18857317>).

8.21.2 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.

8.21.3 Compatibility

As of V4.1 SP2, SIMOTION D445-1 (6AU1445-0AA00-0AA1) is upwardly compatible for use with SIMOTION D445 (6AU1445-0AA00-0AA0).

SIMOTION D445-1 cannot be run with a firmware version < V4.1 SP2, and it signals a "Request general reset" status with a slowly flashing yellow STOP LED.

Project ↔ Firmware ↔ 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 CompactFlash 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 CompactFlash 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 CompactFlash card with a firmware version as of V4.1 SP2 HF3 can be used in both D445 and D445-1 Control Units.

Note

A CompactFlash 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

SIMOTION D445-1 is supplied by default with a double fan/battery module (SIMOTION D445: fan/battery module with single fan).

Service and maintenance

9.1 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 285)
 - Removal and replacement of the SIMOTION D4x5 (Page 286)
 - Replacing DRIVE-CLiQ components (Page 288)
 - 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 290)
- 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 291)
 - Backing up user data (Save variables) (Page 291)
 - Upgrading a user project to the new SCOUT version (Page 294)
 - Platform replacement via XML export/import (Page 295)
 - Preparing the device replacement (Page 296)
 - Device replacement in HW Config (Page 298)
 - Upgrading technology packages (Page 299)
 - Upgrading the device version of SINAMICS S120 control units (Page 301)
 - Upgrading a library (Page 302)
 - Save project, compile and check consistency (Page 303)
- Performing a firmware and project update
 - Upgrading the CF card's boot loader (Page 303)
 - Update - preparatory measures (Page 304)
 - Update via SIMOTION IT web server (Page 305)
 - Upgrade via device update tool (upgrading SIMOTION devices) (Page 305)
 - Upgrade via CF card (Page 310) with the steps:
 - Backing up the CF card data (Page 310)
 - Firmware upgrade via CF card (Page 311)

- Upgrading the SINAMICS (Page 312)
- Downloading the project to the target system (Page 313)

The upgrade data are generated with the SCOUT function "Start device update tool" and then transferred to the SIMOTION D4x5 via CF card or upgrade file for the SIMOTION IT web server. 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 updates.

Please also observe the information on handling the CompactFlash Card.

- Changing the CompactFlash card (Page 314)
- Writing to a CompactFlash card (Page 315)
- Formatting the CompactFlash card (Page 316)
- Boot loader on the CompactFlash card (Page 316)
- Recommended method of handling CF cards (Page 317)
- Card reader for CF cards (Page 317)

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 updating components depends on various factors.

When you update a project, how you proceed will depend on the which parts are affected by the version change.

- 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 contain 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.

9.1 Overview

Overview of upgrade options

Action/measure	Upgrading a project				Replacement of the SIMOTION controller		Activity affects
	Main version	Service pack or hotfix version	PROFINET version	SINAMICS version	Device replacement via HW Config	Platform replacement via XML export/import	
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	C240 → D445-2 D410 → D445-2 D445 → D445 (S120) → (SM150)	SIMOTION SCOUT/project
Creating backup copy (project/CompactFlash)							
Backing up user data (backing up variables)	only if required				only if required	only if required	
Upgrading a user project to the new SCOUT version							
Platform replacement via XML export/import	The target version (= version of the device into which import is performed) is also specified when the platform is replaced						
Preparing the device replacement							
Device replacement in HW Config							
Upgrading technology packages (TP)	4)	4)			4)		
Upgrading device version of SINAMICS S120 CUs				Only as required for external CUs			
Upgrading a library	Libraries are version-dependent				Libraries can be device-dependent	Libraries can be device-dependent	
Save/compile project; check consistency							
Run firmware and/or project update							
Upgrading the boot loader on the CompactFlash card	Check whether the new version requires a new boot loader ²⁾				Check whether a new device ³⁾ requires a new boot loader		Memory card/target hardware
Update - preparatory measures							
Upgrade via IT DIAG	Selecting between the three update methods				only possible if valid firmware is located on the CompactFlash card	only possible if valid firmware is located on the CompactFlash card	
Update using the device update tool							
Update via CompactFlash card							
Backing up the CompactFlash card data							
Firmware update using a CompactFlash card							
Upgrading SINAMICS ⁵⁾							
Downloading project to the target system ¹⁾							

■ not relevant □ 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 updated automatically. The user can directly specify a TP
- 5) SINAMICS components are upgraded/downgraded to the component version of the CF Card. Ensure that LED codes are observed. Following an upgrade, a POWER ON/OFF is required

Figure 9-1 Upgrade options

9.2 Replacing modules (spare part scenario)

9.2.1 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 6AU1435-0AA00-0AA0 can be replaced by a SIMOTION D435 with the order number 6AU1435-0AA00-0AA1.
- A SIMOTION D435 with the order number 6AU1435-0AA00-0AA1 **cannot** be replaced by a SIMOTION D435 with the order number 6AU1435-0AA00-0AA0.

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.

Table 9-1 Options for deleting the retain data

Option	Reference to description	Notes
Module memory reset	See Section SIMOTION D4x5 memory reset (Page 266)	Controller via mode selector (position "3" MRES). Is available on all SIMOTION platforms.
Deleting and restoring non-volatile SIMOTION data	See Section Deleting/restoring non-volatile SIMOTION data (Page 336)	Controller via Service switch (position "1"). Is only available on SIMOTION D.

NOTICE

Unintentional restoration of the default settings instead of memory reset

With a Power OFF/ON, "Restore default settings" is performed instead of "Memory reset" in switch position "3" (MRES) of the mode switch.

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 270)

9.2.2 Removal and replacement of the SIMOTION D4x5

Removing the Control Unit

NOTICE

Damage to property can occur

Installing or removing SIMOTION D410 with power connected can result in undefined states in your system. Damage to property can occur in your automation solution as a result.

For this reason, only ever install or remove SIMOTION D410 with the power source disconnected.

When configuring a system therefore always comply with the relevant standards and safety regulations, which are mandatory in any case.

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.
4. 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 non-volatile SIMOTION data to the CF card during operation.

The user program can back up the contents of the non-volatile SIMOTION data to the CF card with the `_savePersistentMemoryData` system function. 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 SIMOTION data by setting the service selector switch or by using the SIMOTION IT web server; for details, see Section Diagnostic data and non-volatile SIMOTION data (Page 329).

NOTICE

Loss of data due to failure to make backup copies

Non-backed-up non-volatile SIMOTION data can be lost on hardware replacement (module defect), for example, if the current value of the retain variables have not been backed up and replaced by their initial values again.

Back up the non-volatile SIMOTION data on the CF card.

NOTICE

Repeat referencing necessary after absolute encoder overflow

If an absolute encoder overflow occurs after `_savePersistentMemoryData`, the actual position value is no longer correct after the non-volatile SIMOTION data are restored.

In this case, homing (absolute encoder adjustment) must be repeated.

See also

Parts replacement for SIMOTION D4x5 (Page 285)

9.2.3 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.



 DANGER
Danger to life due to live parts and other energy sources
De-energize the module before you start any work.

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.
- When 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.

Note

In this case, incorrect insertion of components is no longer monitored.

Automatic upgrading/downgrading (firmware update)

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 firmware update, please read the messages and alarms in the SIMOTION SCOUT detail window.

9.2 Replacing modules (spare part scenario)

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 firmware update has been carried out on components connected to the SIMOTION D/CX32 or that all components have completed the firmware update.

Go offline once all the firmware 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

9.2.4 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 CompactFlash card to the new CompactFlash card. Proceed as described in the sections below to write your project to the new CompactFlash card:

- Changing the CompactFlash card (Page 314)
- Writing to a CompactFlash card (Page 315)

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>).

9.3 Adapting a project (Updating the project / Replacing the SIMOTION controller)

9.3.1 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 application cases can be found in Figure 9-1 Upgrade options (Page 284).

See also

Overview (Page 281)

9.3.2 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 310)

9.3.3 Backing up user data (backup variables)

Overview

With the SCOUT functions "Save variables" and "Restore variables", you have the option of backing up and restoring data that were 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 "Save variables" function creates XML files which are stored in a folder of your choice.

The following types of data can be backed up:

9.3 Adapting a project (Updating the project / Replacing the SIMOTION controller)

- 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 that is \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`) remain valid even after a version upgrade.

SIMOTION 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 the SIMOTION IT web server, See also the Diagnostic data and non-volatile SIMOTION data (Page 329) Section.
-

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.

9.3 Adapting a project (Updating the project / Replacing the SIMOTION controller)

1. Open the project.

When you open the project, a window appears with a message that the project you are opening was created with a different SCOUT version, as well as a query asking whether you want to perform an upgrade.

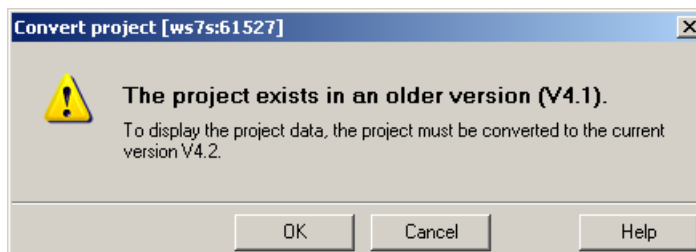


Figure 9-2 Prompt asking whether you want to update the project

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).

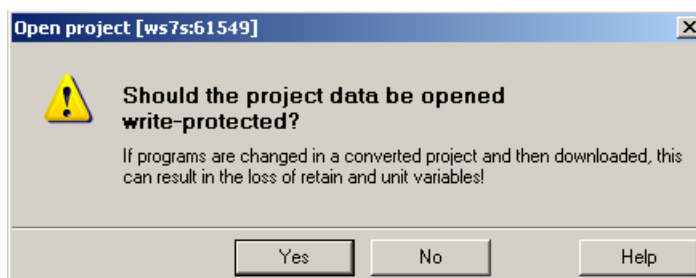


Figure 9-3 Prompt as to whether the project should be opened as write-protected


Open write-protected means: The project remains consistent. The data are 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 operating mode) and execute the **Save variables** SCOUT function. The retain variables (interface and implementation) and the user files (saved with `_saveUnitDataSet` or `_exportUnitDataSet`) are backed up on 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 using 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.

9.3.4 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

1. 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".



Figure 9-4 Prompt as to whether the project should be upgraded

2. 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 write-protected).

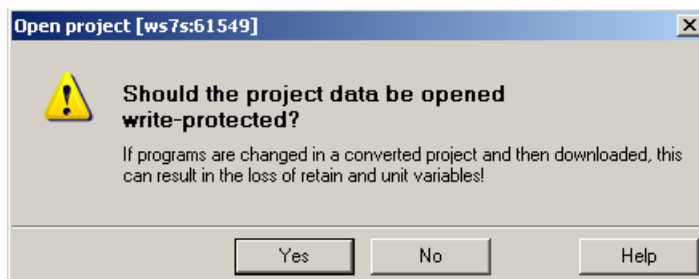


Figure 9-5 Prompt as to whether the project should be opened write-protected

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.

Open write-protected:

9.3 Adapting a project (Updating the project / Replacing the SIMOTION controller)

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" > "Old project format" > "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.

9.3.5 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.
4. 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".

9.3.6 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 ⇒ 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)
 → 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 191).
2. Number of CX32s
 If the replacement is with a D4x5 that only supports fewer 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.
3. 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 232).

TIP for synchronous grouping

If you use device-dependent ST libraries, then the upgrade can be accelerated through the following procedure:

1. 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 302).
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.

9.3.7 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 box 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 by a D435), proceed as described in the Removal and replacement of the SIMOTION D4x5 (Page 286) Section.

Note

Due to the modeling of the standard Ethernet interfaces as PROFINET Basic interfaces (PN/IE), it is not possible to downgrade the SIMOTION D4x5 Control Units from V4.3 to versions < V4.3.

9.3.8 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 ...".

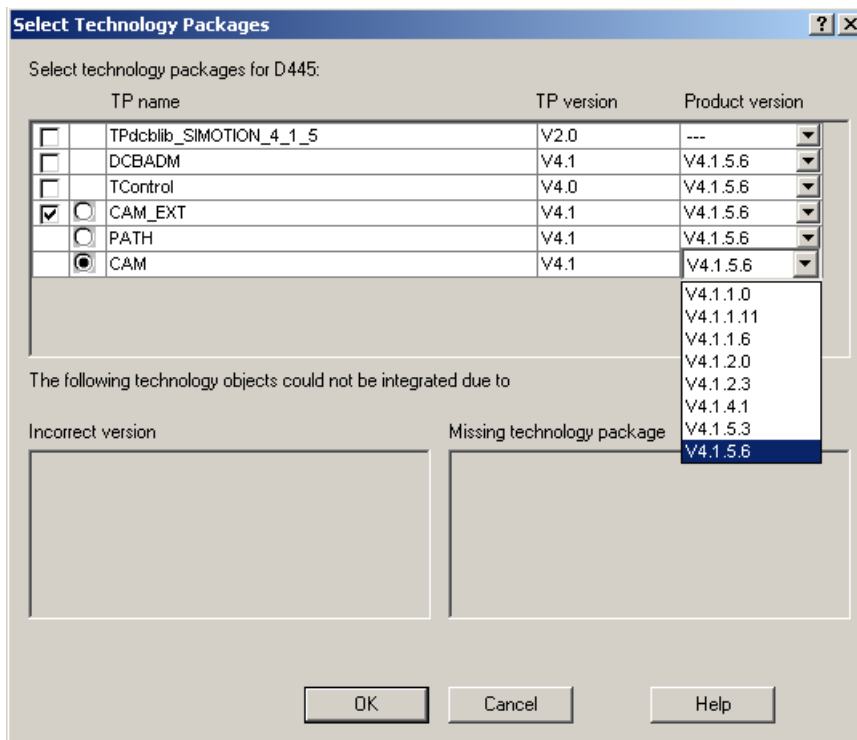


Figure 9-6 Select technology packages

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.
2. Select the "Replace product versions of the technology packages" option from "Additional CPU options" 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 269)

9.3.9 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:

9.3 Adapting a project (Updating the project / Replacing the SIMOTION controller)

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.

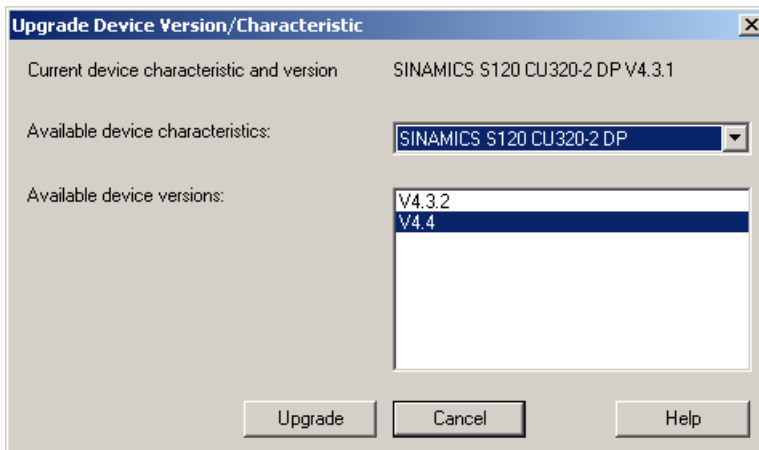


Figure 9-7 Upgrading the device version

3. Select the desired device version/characteristic and click "Upgrade". This upgrades the SINAMICS S120 control unit.

9.3.10 Upgrading a library

Depending on the configured properties of the libraries used in the project (device-dependent or device-independent), an upgrade of the libraries may be required if the SIMOTION device or the device version changes.

1. Open the LIBRARIES 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.
4. Select the SIMOTION device and the technology packages for which the library is to be valid.
5. Close the dialog box with "OK".

Note

Please also observe the information on device-dependencies in the SIMOTION SCOUT online help.

9.3.11 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.

9.4 Performing a firmware and project update

9.4.1 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. You can find this list both in the documentation that comes with the SIMOTION SCOUT DVD under \1_Important\German\Kompatibilitaet\... and on the Internet under (<http://support.automation.siemens.com/WWW/view/en/18857317>).

9.4.2 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 update on the SIMOTION D.

- Update via SIMOTION IT web server (Page 305)
- Upgrade via device update tool (upgrading SIMOTION devices) (Page 305)
- Upgrade via CF card (Page 310)

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 updates.

Requirement (firmware update)

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!
Back up the data before starting an upgrade.

Requirement (project update)

You have updated 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 291).

9.4.3 Update via SIMOTION IT web server

The SIMOTION D features an integrated web server.

In addition to customized web pages and comprehensive device/diagnostic information, SIMOTION IT web server also allows you to update the firmware and project using a standard PC with a web browser.

As of firmware version V4.2, it is no longer necessary to purchase licenses for the web server (IT DIAG license) and for 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 the web server if the CF card contains a firmware version < V4.1 SP2. In this case you should use the D410 or D4x5 firmware archive.

You will find detailed information in the *SIMOTION IT Diagnostics and Configuration Diagnostics Manual*.

See also

Adapting a project (Updating the project / Replacing the SIMOTION controller) (Page 291)

9.4.4 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

9.4 Performing a firmware and project update

- Retain data and unit data are 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 upgrade 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 are 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
 - Upgrade file for the SIMOTION IT web server
- 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 time.
- 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 hardware version.

The following hardware is required to upgrade a SIMOTION D4x5 using a USB stick:

Table 9-2 Hardware required for USB stick updates

Module	Order No.	Minimum hardware release required ¹⁾
SIMOTION D425	6AU1425-0AA00-0AA0	F ²⁾
SIMOTION D435	6AU1435-0AA00-0AA0	Update via USB stick not supported
SIMOTION D435	6AU1435-0AA00-0AA1	F ²⁾
SIMOTION D445	6AU1445-0AA00-0AA0	A
SIMOTION D445-1	6AU1445-0AA00-0AA1	A

¹⁾ The hardware version is listed on the SIMOTION D type plates.

²⁾ Modules with hardware version C to E can be upgraded (upgrade to BIOS ≥ 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 update 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.
3. Switch the module on and wait until the BIOS update has been carried out. The BIOS update 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
<p>Destruction of the BIOS due to interruption of the BIOS update</p> <p>A BIOS update must not be interrupted under any circumstances. With this in mind, do not switch the module off until the BIOS update is complete. A damaged BIOS will require expensive repair work to be carried out at the plant.</p>

5. A successful BIOS update is also displayed in the diagnostic buffer at the next power-up.

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 must be in the "0" position.
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).
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.

9.4 Performing a firmware and project update

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 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 state of the device).
 - If the upgrade 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 will be deleted.

4. 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 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 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 update 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 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:

- Firmware update running: RDY LED flashes slowly (0.5 Hz)
- Firmware 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 firmware update has been performed on components connected to the SIMOTION D/CX32 or that all components have completed the firmware update.

Once the firmware update 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

You will find detailed information on upgrading devices in the *Upgrading SIMOTION Devices* operating instructions.

9.4.5 Upgrade via CF card

9.4.5.1 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 backing up and subsequently restoring data on the CF card depends on whether licenses and/or other retain data and user data that will be required again in the future are located on the CF card.

Case 1: The CF card contains no licenses and no retain data or user data that will be required in the future

You do not need to take any steps in this case. Delete the content of the CF card and update the firmware as described.

Case 2: 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 (<http://www.siemens.com/automation/license>). You will need the hardware serial number printed on the CF card. In the Web License Manager, you have the option of displaying the associated license key.

Case 3: The CF card contains retain data / user data that is still required in the future

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 SIMOTION IT 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 "Save 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`) remain valid even after a version upgrade.

9.4.5.2 Firmware upgrade via CF card**Procedure**

Proceed as follows to perform the upgrade:

1. Switch off the power supply to the D4x5.
2. 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.

9.4 Performing a firmware and project update

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 310)).
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.

9.4.5.3 Upgrading SINAMICS

Depending on the settings, the SINAMICS components are also automatically upgraded to the component version of the CF card with a firmware update of the SIMOTION D.

In order for a FW update to be performed for all components, the components must be correctly connected in accordance with the configured topology.

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:

- Firmware update running: RDY LED flashes slowly (0.5 Hz)
- Firmware 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 firmware update has been performed on components connected to the SIMOTION D/CX32 or that all components have completed the firmware update.

Go offline once all the firmware updates have been completed. POWER ON the upgraded/downgraded components.

Updating the firmware of the SINAMICS components

The SINAMICS components' firmware is updated automatically, depending on the setting of parameter p7826.

- p7826 = 0: Upgrade/downgrade deactivated
- p7826 = 1: Upgrade and downgrade (factory setting)
- p7826 = 2: Upgrade only

Note

The automatic firmware update via p7826 = 1 (update and downgrade) must not be deactivated when using Safety Integrated.

If you are updating 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 update.
The list displays the current firmware version of the devices.
5. Click "Firmware update" to download the new firmware to the devices. To do so, you must select all components whose firmware is to be updated.
6. When the firmware update 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 update to take place. The firmware cannot be updated if the components have not been configured.

You can also update the firmware using the expert list. See the *SINAMICS S120* Commissioning Manual for a description of how to do this.

9.4.5.4 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 303).

Requirement

The firmware required is located on the CompactFlash card; for information, see Firmware upgrade using a CompactFlash card (Page 311) Section.

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 CompactFlash 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.

9.5 SIMOTION Compact Flash card

9.5.1 Changing the CompactFlash Card

Requirement

NOTICE
Damage to the CompactFlash card from electrical fields or electrostatic discharge
The CompactFlash card is an ESD-sensitive component.
De-energize the SIMOTION D4x5 device before inserting or removing the CompactFlash card. SIMOTION D4x5 is in a de-energized state when all the LEDs are OFF.
Comply with the ESD rules.

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.

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.

9.5.2 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.
2. 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.

9.5.3 Formatting the CompactFlash card

You can format a faulty CF card, for example.

Before formatting the CF card, please see the notes in the Backing up the CF card data (Page 310) Section.

The procedure for formatting the CF card is as follows:

1. Insert the CF card into a CF 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 boot loader.

Note

The CF card must only be formatted with FAT or FAT16, and must not be formatted with FAT32 or NTFS. Note that CF cards for SIMOTION D410-2 and D4x5-2 can be formatted with FAT32.

See also

Bootloader on the CompactFlash card (Page 316)

9.5.4 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 error profile: All 8 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 SIMOTION SCOUT to the CF card.

Note

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."

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. You can find this list both in the documentation that comes with the SIMOTION SCOUT DVD under \1_Important\German\Kompatibilitaet\... and on the Internet under (<http://support.automation.siemens.com/WW/view/en/18857317>).

Note

Note that CF cards for SIMOTION D410-2 and D4x5-2 can have a different boot loader.

9.5.5 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.

NOTICE
<p>Damage to the CompactFlash card from electrical fields or electrostatic discharge</p> <p>The CompactFlash card is an ESD-sensitive component.</p> <p>De-energize the SIMOTION D4x5 device before inserting or removing the CompactFlash card. SIMOTION D4x5 is in a de-energized state when all the LEDs are OFF.</p> <p>Comply with the ESD rules.</p>

- 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.

9.5.6 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 connector

Order number: 6FC5 335-0AA00-0AA0

Diagnostics

10.1 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.

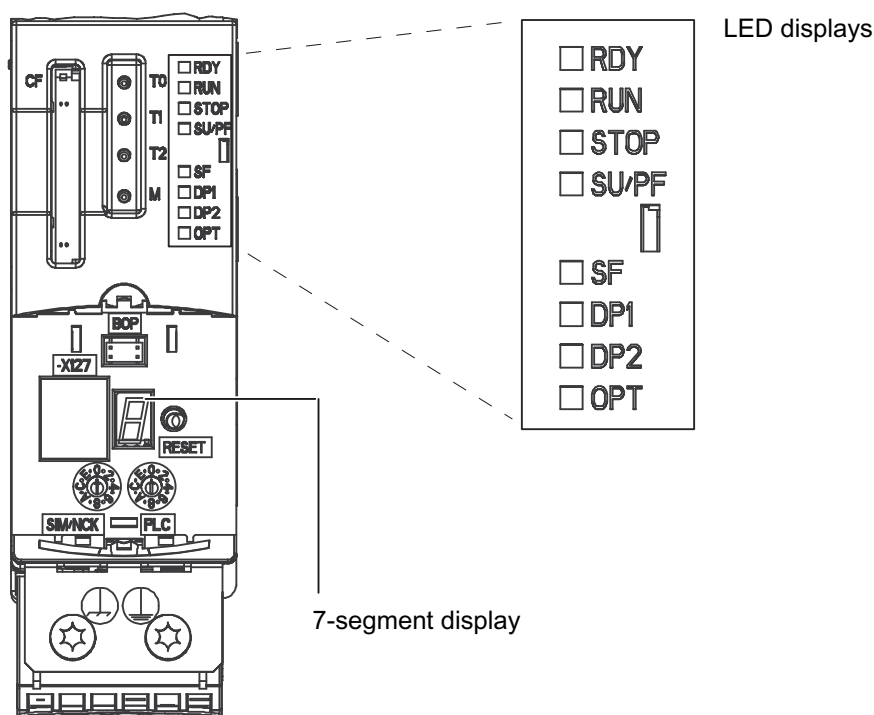


Figure 10-1 7-segment and LED displays on the D4x5

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

10.1.1 SIMOTION D4x5 and SINAMICS Integrated 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 10-1 LED displays

Meaning	LED display							
	RDY	RUN	STOP	SU/PF	SF	DP1	DP2	OPT
Power-up	1 (yellow)	1 (yellow)	1 (yellow)	1 (yellow)	1 (yellow)	1 (yellow)	1 (yellow)	1 (yellow)
Power-up of the D4x5 without CF card or with CF card without valid operating system (possibly incorrect / missing defective boot loader).	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 firmware).	0.5/1 (red)	0	0	0	0	0	0	0
BIOS update	Λ (red)	x	x	x	x	x	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	Λ (yellow)	x	x	x	x	x	x	x
RUN	X	1 (green)	0	0	x	x	x	x
Transition from RUN - STOPU	X	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

Meaning	LED display							
	RDY	RUN	STOP	SU/PF	SF	DP1	DP2	OPT
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	x	x
Request for memory reset by the D4x5 itself or via the mode switch	x	0	0.5/1 (yellow)	0	x	x	x	x
Memory reset in progress ¹⁾	x	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	X	1 (red)	x	x	x
"FAULT" state (7-segment display shows "F"). For details, see "7-segment display" and "Special operating modes"	Λ (red)	Λ (red)	Λ (red)	Λ (red)	Λ (red)	Λ (red)	Λ (red)	Λ (red)
HOLD mode 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	x	0.5/1 (green)	1 (yellow)	1 (yellow)	x	x	x	x
"RESET" state (7-segment display shows "8") For details, see "7-segment display" and "Special operating modes"	2/1 (red/ yellow)	x	x	x	x	x	x	x
DCP flashing (for interface X120, X130, X1400) This function is used to check the correct assignment to a module and its interfaces. DCP flashing of the module activated in HW Config under "Target system" > "Ethernet" > "Edit Ethernet node" > Button "Browse" > "Flashing" button	x	x	x	x	2/1 (red)	x	x	x
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

Meaning	LED display							
	RDY	RUN	STOP	SU/PF	SF	DP1	DP2	OPT
Module identification (identification via LED) selected via SCOUT or with p0124[0]=1. ⁴⁾	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	x	x	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	x	x	x	0	0	x
At least 1 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): <ul style="list-style-type: none"> • Failure of a connected IO device • At least one of the assigned I/O devices cannot be addressed • Incorrect or no configuration. 	x	x	x	x	x	x	x	2/1 (red)

Meaning	LED display							
	RDY	RUN	STOP	SU/PF	SF	DP1	DP2	OPT
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 update tool)								
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
Bootling 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	1 (red)	x	x	x	x	x	x	x
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 diagnostic data and non-volatile 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

- ¹⁾ The LED state appears only very briefly due to the speed at which the "memory 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).
- ⁴⁾ The RDY LED of SIMOTION D4x5 does not flash yellow/green as in the case of CUs, but instead lights up yellow constantly.

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.

Table 10-2 States of the 7-segment display

State	Meaning
8	Module in the RESET state (RESET button pressed; overtemperature; faulty/disconnected fan/battery module)
8. (Middle segment of the "8" flickers)	Power-up of the SIMOTION D4x5 has failed Possible cause: Incorrect boot loader on the CF card
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

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.

10.1.2 LED displays of the PROFINET interface

Position of the PN interface of the CBE30

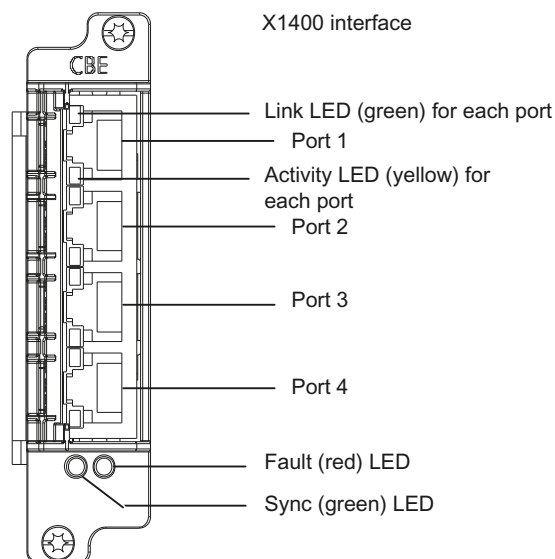


Figure 10-2 CBE30 front view

LED displays

Table 10-3 Meaning of the 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.

Name	Color	State	Meaning
		On	<p>PROFINET interface bus fault</p> <ul style="list-style-type: none"> • No physical connection to a subnet/switch. • Incorrect transmission rate • Full duplex transmission is not activated
		Flashing (2 Hz)	<ul style="list-style-type: none"> • Failure of a connected I/O device • At least one of the assigned I/O devices cannot be addressed. • Incorrect or no configuration.
SYNC ¹⁾	Green	Off	<p>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).</p> <p>If IRT data 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.</p>
		On	<p>The PROFINET interface has synchronized to the send cycle clock of PROFINET IO with IRT</p> <p>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.</p> <p>If no IRT data have been configured for SIMOTION, this state indicates that only the PROFINET interface has synchronized to the send clock of PROFINET IO with IRT. The PROFINET interface is then used to forward the IRT data.</p>
		Flashing (2 Hz)	<p>The PROFINET interface has synchronized to the send cycle clock of PROFINET IO with IRT</p> <p>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.</p>

¹⁾ If no IRT has been configured, then generally no synchronization will be made to the send cycle clock. LED is off.

10.1.3 LED displays of the Ethernet interface

The Ethernet ports are equipped with LEDs to display Link and Activity.

Table 10-4 State of the Link and Activity LEDs

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 data exchange
	Flickers yellow	Data exchange Data is being received or sent on port x.

10.1.4 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.

10.1.4.1 Behavior of the LEDs during booting of the CX32

Table 10-5 Load software 1

LED		State	Comment
RDY	DP1		
Red	Red	Reset	Hardware reset
Red, 2 Hz	Red	Error	<ul style="list-style-type: none"> • D4x5 CompactFlash card not inserted or • Load software 2 has not been installed on the D4x5 CompactFlash card or is defective.

Table 10-6 Load 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 10-7 Firmware

LED		State	Comment
RDY	DP1		
Off	Off	Initializing	–
Alternating	Alternating	Running	See the table below

10.1.4.2 Behavior of the LEDs after booting of the CX32

Behavior of the LEDs after booting

Table 10-8 Control unit - description of the LEDs after 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	–	

LED	Color	State	Description, cause	Remedy
		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.	-
		0.5 Hz flashing light	Full cyclic communication has not yet taken place. Possible causes: <ul style="list-style-type: none"> • 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

10.2 Diagnostic data and non-volatile SIMOTION data

10.2.1 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 SIMOTION data (retain data) to the CompactFlash card, see the Backup of diagnostic data and non-volatile SIMOTION data (Page 330) Section.
- Back up HTML pages (including the most up-to-date content) to the CompactFlash card for diagnostic purposes; for information, see Section Diagnostics via HTML pages (Page 334)
- Restore backed-up non-volatile SIMOTION data (retain data), see the Deleting/restoring non-volatile SIMOTION data (Page 336) Section for this purpose.

10.2.2 Backup of diagnostic data and non-volatile SIMOTION data

10.2.2.1 Diagnostic data

Following a fault on a SIMOTION device, diagnostic data (e.g. diagnostic buffer content, up-to-date content of HTML pages, etc.) can provide important information on the cause of the fault. For this purpose, such data can be backed up to the CF card using a simple operation (e.g. by setting a switch on the D4x5).

You then have the following options for the diagnostic data:

- Fetching them from the CF card using a card reader
- You can load it with the SIMOTION IT web server or by FTP

You can also use them for diagnostic purposes or provide Technical Support with them 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 331)
 - Using SIMOTION IT web server;
The web server also offers the option of fetching 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 332).
 - Using a service selector switch
 - Controlling diagnostic data creation using an INI file stored on the CF card

10.2.2.2 Non-volatile SIMOTION data (retain data)

In addition to the diagnostic data, non-volatile SIMOTION data (retain data) is also saved on the CompactFlash card. You can use this in situations where the non-volatile SIMOTION data has not been saved on the CompactFlash card using the **_savePersistentMemoryData** system function, and you wish to restore the non-volatile SIMOTION data after a CPU has been replaced.

Note

While the non-volatile data is stored in the "...USER/SIMOTION" directory as a "PMEMORY.XML" backup file using the **_savePersistentMemoryData** system function, backing up diagnostic data and non-volatile data stores the data in the "...\USER\SIMOTION\HMI\SYSLOG\DIAG" directory.

10.2.2.3 Procedure for backing up during operation

Procedure

The advantage of backing up diagnostic data and non-volatile SIMOTION data during operation is that enhanced diagnostic information via HTML pages and TO alarm information is available.

Data are backed up:

- Using "Diagnostics > Diagnostics Files" in SIMOTION IT web server; see Section Back up diagnostic data and non-volatile SIMOTION data via the web server (Page 338)
- Via the service selector switch (see the description below).

Service selector switch

To back up diagnostic data and non-volatile SIMOTION data using a service selector switch, proceed as follows:

1. 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 SIMOTION data can be created in STOP, STOPU, and RUN modes.

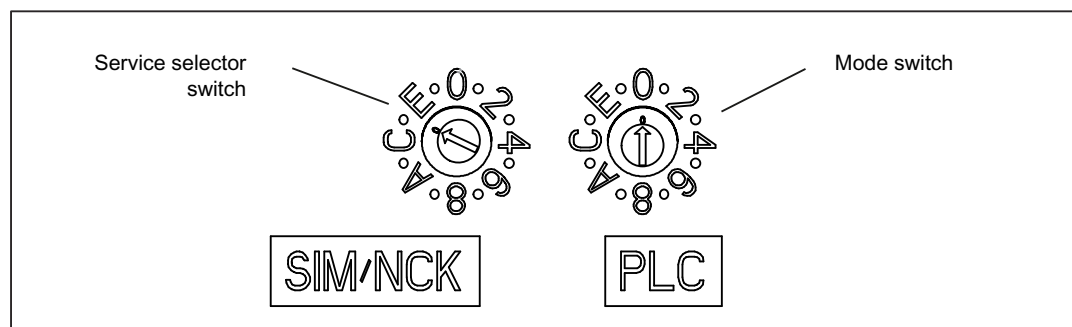


Figure 10-3 Mode switch and service selector switch

2. The diagnostic data and non-volatile SIMOTION data are 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 10-9 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

10.2.2.4 Procedure for backing up during startup

Procedure

Backing up diagnostic data and non-volatile SIMOTION data "during power-up" provides you with diagnostic information **without HTML pages / TO alarm information**.

Backing up during startup is particularly advisable for SIMOTION devices that cannot run or have crashed.

Diagnostic data and non-volatile SIMOTION data are backed up

- Using a service selector switch or
- Using an INI file stored on the CF card.

The procedure for each is described below.

Service selector switch

Data are backed up using a service selector switch as follows:

1. 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).

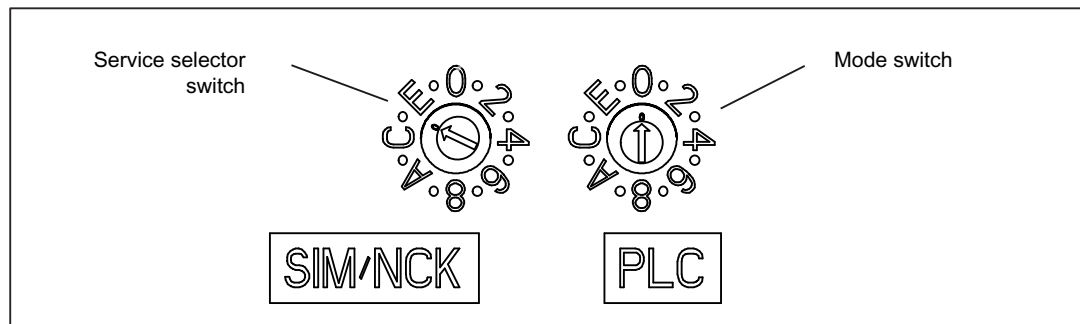


Figure 10-4 Mode switch and service selector switch

2. Switch the D4x5 off and back on again.
3. Wait for the device to start up.
The diagnostic data and non-volatile SIMOTION data are backed up to the CF card during power-up, provided that this is still possible and is not prevented by hardware defects, for instance. 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 10-10 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 directory of the CF card

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 directory of the CF card.
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 non-volatile SIMOTION 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 instance.
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.

Table 10-11 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

Note

To suppress startup in diagnostics mode again, you must delete the simotion.ini file from the CF card.

10.2.2.5 Storing data

Storing diagnostic data and non-volatile data

You can find diagnostic data and non-volatile data on the CF card in the \USER\SIMOTION\HMI\SYSLOG\DIAG directory.

Copy these data and transfer them to Technical Support when requested to do so. A standard card reader can be used to transfer the diagnostic data from the CF card via standard SIMOTION IT web server pages or via FTP.

The following data are stored:

Table 10-12 Diagnostic data on the CF card

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) You can restore the backed up non-volatile SIMOTION data "via an operator action" after a CPU has been replaced. (See Section Deleting/restoring non-volatile SIMOTION data (Page 336).)
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).
HTML page	If the diagnostic data are backed up, the URLs are requested from the text file (DIAGURLS.TXT) and stored as HTML pages together with their content. (See Section Diagnostics for HTML pages (Page 334)). Note: The HTML pages 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.

Note

Use HTML pages if you wish to back up diagnostic data in plain-text format. HTML pages enable user-friendly diagnostics. In addition to the standard SIMOTION IT web server pages, you have the option of creating your own HTML pages (e.g. for the axis status or for machine diagnostics). Customized diagnostics pages are particularly suitable for application problems, as you can define the contents yourself.

10.2.3 Diagnostics via websites

In the "DIAGURLS.TXT" text file, located in the ...\\USER\\SIMOTION\\HMI\\SYSLOG\\DIAG directory, you can specify HTML files whose status will be stored on the CF card when diagnostic data are 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 SIMOTION IT web server pages, it is possible to store customized pages. Information on creating pages of this type can be found in, for example, Utilities & Applications.

The screenshot shows the SIMOTION D445 diagnostic buffer interface. The top bar includes the Siemens logo, the device name 'D445', and the date/time 'Thu Sep 02 07:12:04 2010'. Below this, the 'Messages & Logs' section is active, with a 'Refresh' button. A navigation menu on the left includes options like Home, Device Info, Diagnostics, Messages & Logs (selected), Machine Overview, Manage Config, Settings, Files, and User's Area. The main area displays a table of diagnostic events with columns for Nr, Time, Date, and Event. A 'Show Hex Values' checkbox is visible in the top right of the table area.

Nr	Time	Date	Event
1	07:09:49.198	02.09.10	One or more runtime software licenses missing
2	07:07:01.780	02.09.10	Operating mode RUN reached
3	07:07:01.744	02.09.10	Operating mode transition from STARTUP to RUN: Start
4	07:07:01.744	02.09.10	Operating mode STARTUP reached
5	07:07:01.723	02.09.10	Operating mode transition from STOP_U to STARTUP: Start
6	07:07:01.690	02.09.10	Operating mode STOP_U reached
7	07:07:01.678	02.09.10	Operating mode transition from STOP to STOP_U: Start
8	07:00:56.242	02.09.10	PROFIBUS DP 3: Station return, node 3
9	07:00:49.426	02.09.10	Operating mode STOP reached
10	07:00:47.425	02.09.10	User programm being loaded, mode: 3

Figure 10-5 Diagnostic buffer with generated diagnostic data

The following points must be noted for the DIAGURLS.TXT file:

- A DIAGURLS.TXT file containing the standard web pages is automatically created if you have not stored your own DIAGURLS.TXT file.
- Standard web pages are entered "without" specifying a path (e.g. "devinfo.mcs" for the standard web page "devinfo.htm").
- Standard web 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 1 file name may be used per line.
- Empty lines are not permitted (an empty line will be interpreted as the end of the list).

10.2 Diagnostic data and non-volatile SIMOTION data

- No distinction is made between upper-case and lower-case letters.
- It does not matter whether you use "\" or "/" in the path name.

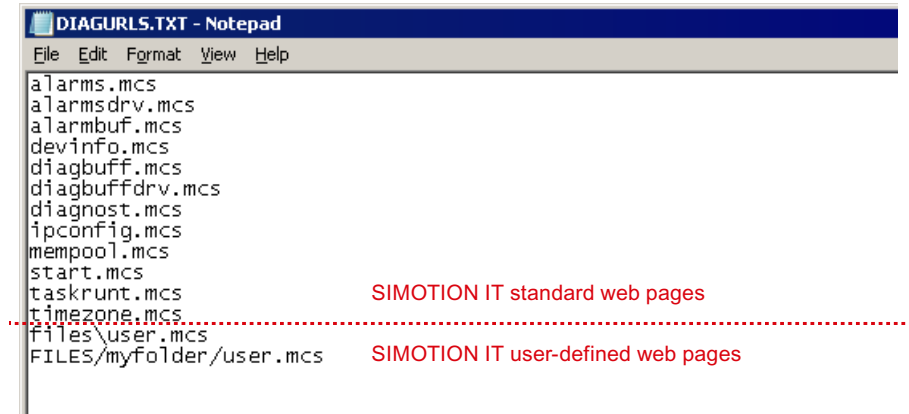


Figure 10-6 Depiction of DIAGURLS.TXT editor

Additional references

You will find detailed information on device and diagnostic information of the SIMOTION IT web server in the *SIMOTION IT Diagnostics and Configuration Diagnostics Manual*.

10.2.4 Deleting/restoring non-volatile SIMOTION data

Requirement

The diagnostic data and non-volatile SIMOTION data has been backed up to the CF card, see Section Backup of diagnostic data and non-volatile SIMOTION data (Page 330).

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 SIMOTION data" setting (switch position "1").
The positions of the mode selector are not relevant (i.e. the set operating mode remains unchanged).

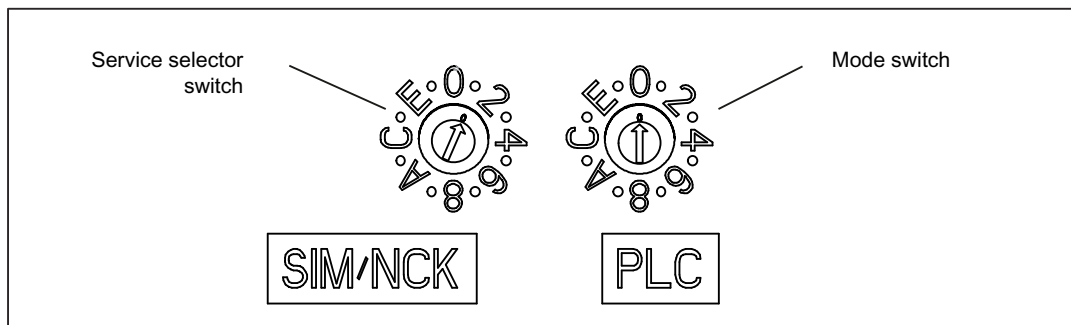


Figure 10-7 Switch position 1 for deleting/restoring non-volatile data

3. Allow the D4x5 to power up; the non-volatile SIMOTION data are 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 CF card, this will be restored (rather than the "PMEMORY.XML" file saved to the "\USER\SIMOTION\HMI\SYSLOG\DIAG" directory by "Back up diagnostic data and non-volatile SIMOTION data").

The order of priority for restoration is as follows:

- /USER/SIMOTION/PMEMORY.XML
- /USER/SIMOTION/PMEMORY.BAK
- /USER/SIMOTION/HMI/SYSLOG/DIAG/PMEMORY.XML

If, for example, you want to restore data backed up via the switch/web server, you may have to delete existing PMEMORY.XML and PMEMORY.BAK backup files in the \USER\SIMOTION \ directory on the CF card.

Note

When the "Delete/restore non-volatile SIMOTION data" switch position is selected, the non-volatile SIMOTION data of the D4x5 is first deleted and then restored from the PMEMORY backup file.

1. Once the D4x5 has powered up, switch it off.
2. Reset the service selector switch to its original setting.
3. Switch the D4x5 back on.

10.2.5 Back up diagnostic data and non-volatile SIMOTION data via the web server

SIMOTION devices provide a web server with already prepared standard web 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.

Diagnostic data and non-volatile SIMOTION data can be backed up via the web server. The home page of the web server is opened by entering the IP address of the SIMOTION device in the address line of the browser; e.g. <http://169.254.11.22>

This opens the home page of the web server. To back up diagnostic data and non-volatile SIMOTION data, call the "Diagnostic files" page from the "Diagnostics" menu.

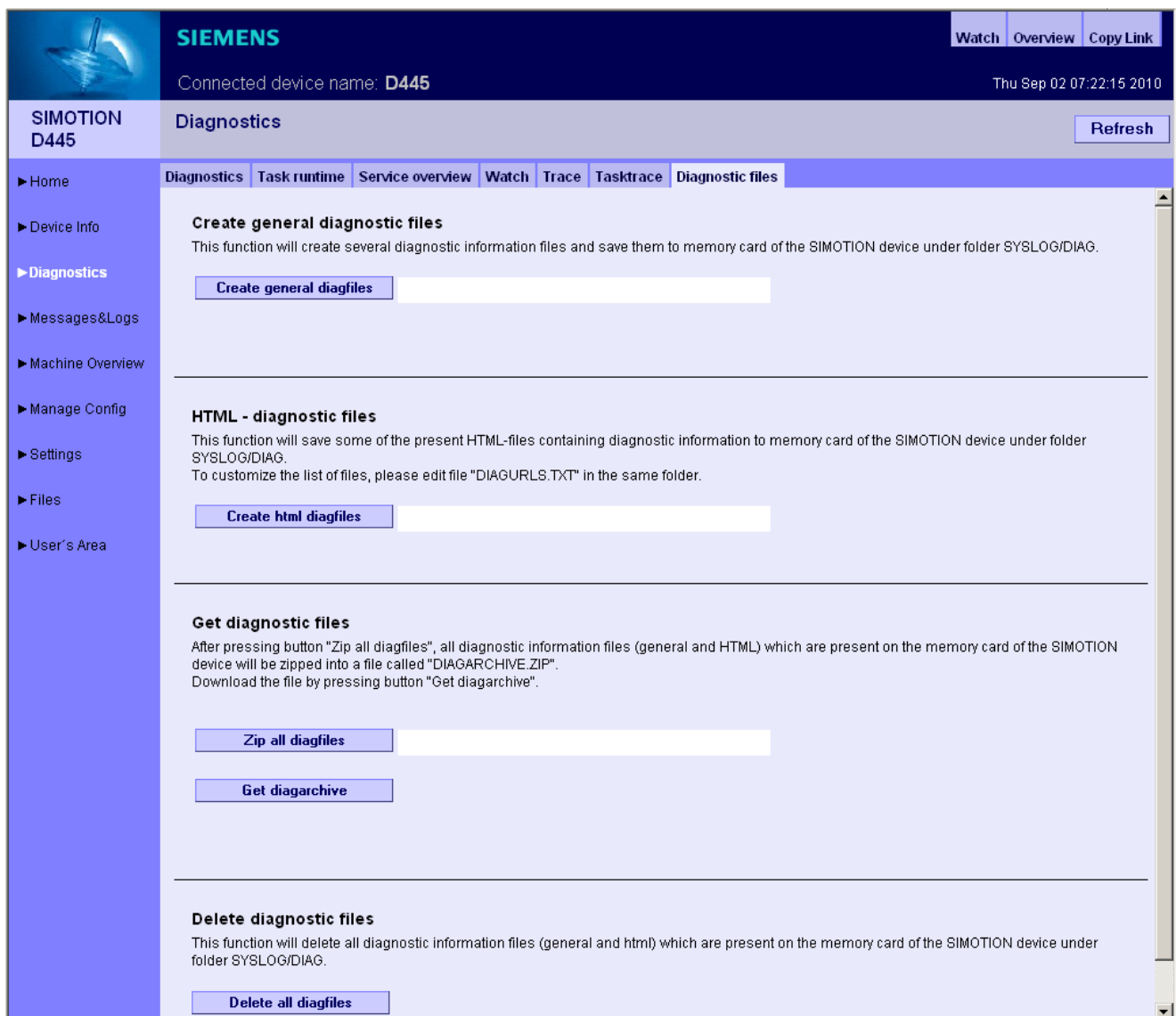


Figure 10-8 SIMOTION IT web server

Table 10-13 Functions on the "Diagnostic files" HTML page

Button	Function
Create general diagfiles	This button saves the diagnostic data and non-volatile SIMOTION data to 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 330).
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.

The diagnostic data and non-volatile SIMOTION data on the CF card can be found in the following directory: \\USER\\SIMOTION\\HMI\\SYSLOG\\DIAG.

Additional references

You will find detailed information in the *SIMOTION IT Diagnostics and Configuration Diagnostics Manual*.

10.3 Additional service and diagnostics options

10.3.1 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*.

10.3.2 Diagnostics via the SIMOTION IT web server

The SIMOTION D features an integrated web server.

In addition to customized web pages and the option of performing firmware and project updates, SIMOTION IT web server provides comprehensive device and diagnostic information that can be called using a standard PC with a web browser.

As of firmware version V4.2, it is no longer necessary to purchase licenses for the web server (IT DIAG license) and for SIMOTION OPC-XML.

Additional references

You will find detailed information in the
SIMOTION IT Diagnostics and Configuration Diagnostics Manual.

Configuration of drive-related I/Os (without symbolic assignment)

A

A.1 Overview

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 342)

Information on the configuration can be found

- For global measuring inputs (with symbolic assignment) in Section Configuration of global measuring inputs (Page 247)
- For local measuring inputs in the appendix, in Section Configuration of local measuring inputs (Page 344)

Additional references

Further information and programming examples for configuring drive-related I/Os without symbolic assignment can be found

- At the following Internet address (<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.

A.2 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.

Table A-1 Comparison of local and global measuring inputs

	Local measuring input	Global measuring input
Hardware supported	D410, D410-2, D4x5, D4x5-2 (terminal X122/X132), CX32, CX32-2, CU310, CU310-2, CU320, CU320-2	TM15, TM17 High Feature, D410, D410-2, D4x5, D4x5-2 (terminal X122, X132, X142), CX32, CX32-2, CU310, CU310-2, CU320, CU320-2
Measurement procedure	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 measuring input TO in 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 measuringInput by means of symbolic assignment or the hardware address.
Measuring input TO setting: Single measurement (Measurement jobs must be issued individually for each measurement. Several interpolation cycle clocks lie between two measurements.)	Yes	Yes

	Local measuring input	Global measuring input
Measuring input TO setting: Cyclical measurement (The measurement is activated just once and runs cyclically until deactivated.)	No	Yes D410, D410-2, D4x5, D4x5-2 (terminal X122, X132), CX32, CX32-2, CU310, CU310-2, CU320, CU320-2: The minimum interval between two measurements is 3 position control cycle clocks (max. 2 edges per measurement). D4x5-2 (terminal X142), TM17 High Feature: The minimum interval between two measurements is 1 position control cycle clock (max. 2 edges per measurement). TM15: No cyclic measurement available
Use of multiple measuring input TOs on one axis/encoder. They 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

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	D410-2, CU310-2	D4x5-2 - X122/X132 - X142	TM15	TM17 High Feature
Max. number of measuring input inputs	3	6	4	8	- 8 - 8	24	16
Can be configured as a local measuring input	x	x	x	x	- 8 - 0	-	-
Can be configured as a global measuring input	x	x	x	x	- 8 - 8	x	x

A.3 Configuring local measuring inputs

Properties

Local measuring inputs are always permanently assigned to an axis (drive). They are configured separately for each drive. The drive and the measuring 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.

Procedure

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 p0728 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.

Table A-3 Local measuring inputs, required settings in the expert list

	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	p0488[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
	p0488[1] (measuring input 1 input terminal, encoder 2)		
	p0488[2] (measuring input 1 input terminal, encoder 3)		
	p0489[0] (measuring input 2 input terminal, encoder 1)		
	p0489[1] (measuring input 2 input terminal, encoder 2)		
	p0489[2] (measuring input 2 input terminal, encoder 3)		

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 the TO measuring input


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

CE marking


	<p>Our products satisfy the requirements and protection objectives of the EC Directives and comply with the harmonized European standards (EN).</p>
---	---

Electromagnetic compatibility

Standards for EMC are satisfied if the EMC Installation Guideline is observed.

SIMOTION products are designed for industrial use in accordance with product standard DIN EN 61800-3, Category C2.

cULus Approval

	<p>Listed component mark for United States and the Canada Underwriters Laboratories (UL) according to Standard UL 508, File E164110, File E115352, File E85972.</p>
---	---

You can find more information on the respective device on the Internet at <http://database.ul.com/cgi-bin/XYV/template/LISEXT/1FRAME/index.htm>. Enter the first 7 characters of the order number under **Keyword**. Then click **Search**.


EMC

<p>KOREA</p>	<p>이 기기는 업무용(A급) 전자파적합기기로서 판매자 또는 사용자는 이 점을 주의하시기 바라며, 가정외의 지역에서 사용하는 것을 목적으로 합니다.</p> <p>For sellers or other users, please keep in mind that this device is an A-grade electromagnetic wave device. This device is intended to be used in areas other than home.</p> <p>The EMC limit values to be observed for Korea correspond to the limit values of the EMC product standard for variable-speed electric drives EN 61800-3 of Category C2 or the limit value class A, Group 1 to CISPR11. By implementing appropriate additional measures, the limit values according to category C2 or limit value class A, Group 1, are observed. For this purpose, additional measures, such as e.g., the use of an additional RFI suppression filter (EMC filter) may be necessary. In addition, measures for EMC-compliant configuration of the plant are described in this Manual and/or the Configuration Manual "EMC Installation Guideline". Please note that ultimately it is always the label on the device that provides the decisive information on the compliance with standards.</p>
---------------------	---

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>).

C-Tick

AUSTRALIA	
	D425, D435, D445, D445-1 meets the requirements of the AS/NZS CISPR 22.

B.2 SIMOTION D4x5 device-specific notes

Note regarding SIMOTION D

Note

The product standard EN 61800-3 describes the EMC requirements placed on "Variable-speed 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.

The same installation instructions apply for the SIMOTION D4x5/CX32 Control Units as for the SINAMICS S120 CU320 Control Units with regard to EMC.

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.

ESD guidelines

C.1 ESD definition

What does ESD mean?

Electrostatic sensitive devices (ESDs) are individual components, integrated circuits, modules or devices that may be damaged by either electrostatic fields or electrostatic discharge.



NOTICE

Damage caused by electric fields or electrostatic discharge

Electric fields or electrostatic discharge can result in malfunctions as a result of damaged individual parts, integrated circuits, modules or devices.

- Only pack, store, transport and send electronic components, modules or devices in their original packaging or in other suitable materials, e.g. conductive foam rubber or aluminum foil.
- Only touch components, modules and devices if you are first grounded by applying one of the following measures:
 - Wearing an ESD wrist strap
 - Wearing ESD shoes or ESD grounding straps in ESD areas with conductive flooring
- Only place electronic components, modules or devices on conductive surfaces (table with ESD surface, conductive ESD foam, ESD packaging, ESD transport container).

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.

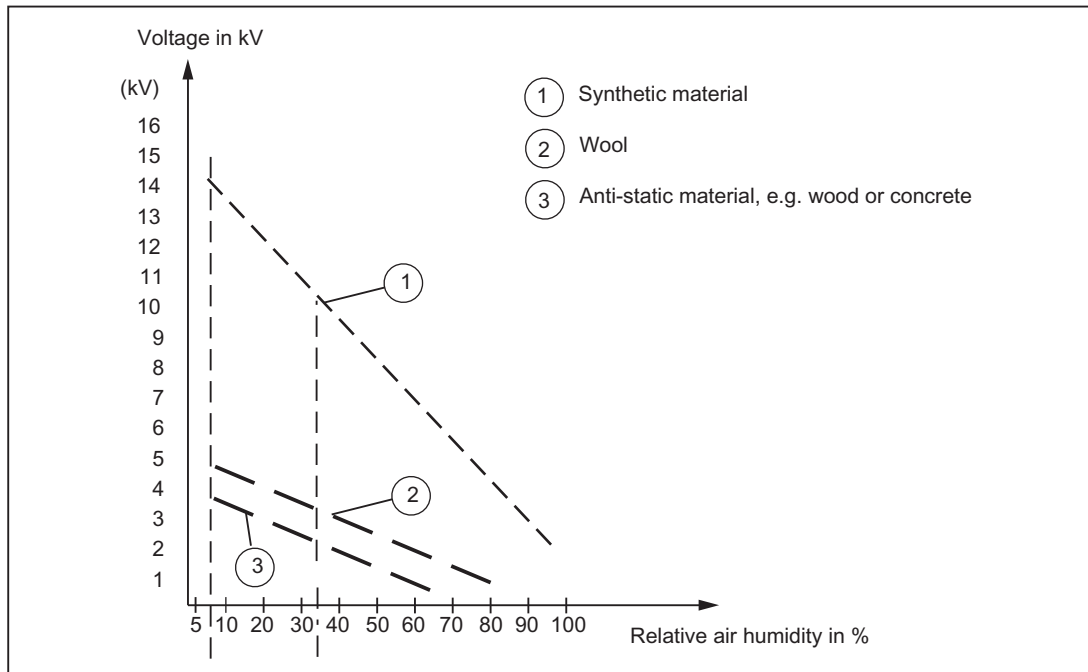


Figure C-1 Electrostatic voltage that can accumulate on operating personnel

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.

Index

A

- Active setting
 - Programming devices/PCs, 136
- Ambient conditions
 - Climatic, 40
- Automatic configuration, 184
- Automatic controller setting
 - Position controller, 257
 - Speed controller, 256
- Automatic position controller setting, 257
- Automatic speed controller setting, 256
- Axis
 - Creating with axis wizard, 220
 - Testing with the axis control panel, 228
- Axis control panel, 227
- Axis grouping, 27
 - DRIVE-CLiQ components, 28
 - SIMOTION D, 28
 - SINAMICS infeed, 28
 - SINAMICS power unit, 28

B

- batteryexisting, 111
- batterynecessary, 111
- Boot loader, 316
 - Reading, 316
 - Writing, 316
- Bus connector, 79
 - MPI, 84
 - Setting the terminating resistor, 81

C

- CE marking, 347
- Commissioning
 - Download project to CF card , 179
 - Individual steps, 153
 - Load into file system, 179
 - Requirements, 149
- Communication Board Ethernet (CBE30), 52
- CompactFlash card
 - Changing, 314
 - Characteristics, 95
 - Content, 104
 - Formatting, 316

- Inserting, 97
- Writing to, 315
- Components
 - open, 43
- Conditions of use, 38
- Configuration
 - Global measuring inputs D4x5, 342
 - Local measuring inputs D4x5, 342
 - Measuring inputs on the D4x5, 342
- Control Unit mounting
 - D445-1 next to Line Module, 47
 - On the side of the Line Module, 46
 - On the wall of the control cabinet, 47
 - With spacers, 48
- Controller optimization, 259
 - Automatic position controller setting, 257
 - Automatic speed controller setting, 256
 - Function generator, 259
 - Measuring functions, 259
 - Trace, 259
- cULus Approval, 347
- CX32
 - LEDs during booting, 327
- CX32 configuration
 - Online configuration, 199
 - Overview, 190
 - Requirement, 191
 - topology, 194
- Cycle clock scaling
 - external/internal PROFIBUS, 133

D

- D4x5
 - Installing, 43
 - Removal and installation, 286
 - Replacing, 281
 - Upgrading, 281
- Data
 - Deleting, 266
- Data storage
 - Diagnostic data, 333
- Declaration of conformity, 348
- Designs, 44
- Diagnostic buffer entries, 108
- Diagnostic data
 - Backing up, 330, 338
 - Backing up during operation, 331
 - Backing up during startup, 332

- Backing up via web server, 338
- Data storage, 333
- Diagnostics
 - 7-segment display of the D4x5, 324
 - LED displays, 319
 - SIMOTION Task Profiler, 339
 - Via HTML, 334
 - Web server, 339
- Digital input/digital output
 - Connecting cables, 74
 - Wiring, 75
- Distributed I/O systems, 30
- DMC20/DME20
 - Creating, 253
 - Properties, 252
- DP cycle, 131
 - PROFINET, 145
- Drive optimization, 259
- Drive wizard
 - Calling, 156
- DRIVE-CLiQ
 - Advantages, 31
 - Components, 32
 - Connectable components, 70
 - Rules for wiring, 69

E

- Electromagnetic compatibility, 347
- EMC directives, 66, 347
- EMERGENCY STOP concept, 66
- Equipotential bonding, 63
- ESD guideline, 349
- Ethernet
 - Characteristics, 138
 - Configuring addresses, 141
 - Interfaces, 140

F

- Fan/battery module, 112
 - D425/D435, 113
 - D445/D445-1, 114
 - Fan control, 112
 - Fan faults, 113
 - Max. permissible supply air temperature, 112
- Firmware
 - Updating automatically, 312
 - Updating manually, 313
 - Upgrading, 304
- Firmware downgrade, 313

- Firmware update
 - Performing, 304
 - Web server, 305
- Front cover
 - Opening, 64
- FW update
 - Performing, 304

G

- Global measuring inputs D4x5, 342
- Guideline
 - ESD, 349

H

- Hardware
 - Configuring, 188

I

- I/O systems
 - PROFIBUS, 29
 - PROFINET, 31
 - Released, 32
- Installing
 - CBE30, 52
 - CX32, 53
 - D4x5, 43
 - TB30, 51
- Integrated drive
 - Downloading a configuration, 188
 - SINAMICS S120, 156
- Interface
 - X122/X132, 75

L

- LED display
 - CBE30 PROFINET, 325
 - CX32, 328, 329
 - D4x5 backup of non-volatile data, 323
 - PROFIBUS DP, 320
 - PROFINET interface, 320
 - SINAMICS Integrated with D4x5, 320
 - Upgrading the D4x5, 323
- License
 - Backing up, 310
 - Protection against deletion, 269
 - Undervoltage indicator, 320

- Load
 - Into file system, 179
 - Project, 176
 - To the target system, 313
- Local measuring inputs D4x5, 342
- Local measuring inputs on the D4x5
 - Parameter, 344
- M**
- Maintenance
 - Overview, 281
- Measuring input
 - D4x5 overview, 247
 - Global for D4x5, 247
- Measuring inputs on the D4x5
 - Local/global measuring inputs, 342
- Mechanical rated conditions, 39
- Memory model, 101
- Memory reset, 266
 - via SIMOTION SCOUT, 267
 - with mode switch, 268
- Module
 - Transport and storage conditions, 37
- MPI bus
 - Bus connector, 84
 - Connection rules, 85
 - interface, 137
 - Parameter, 138
- MPI interface, 130
- N**
- Non-volatile data
 - Backing up, 330, 338
 - Backing up via web server, 338
 - Restoring, 336
 - Saving to CF card, 103
- Non-volatile SIMOTION data
 - Backing up, 107
 - Diagnostics, 108
 - Power-up, 108
 - Restoring, 107
- O**
- Offline configuration
 - Overview, 155
 - Procedure, 155
 - Requirement, 155
- Onboard I/Os of the D4x5
 - Configuration overview, 244
 - Overview, 243
- Online configuration
 - Procedure, 182
 - Requirement, 182
- Output cam
 - Configuration for D4x5, 249
- Overview
 - Diagnostic data, 329
 - Upgrading and downgrading, 304
- Overview of connections, 60
- P**
- PG/PC connection
 - enabling the active setting, 136
 - via Ethernet, 126
 - via PROFIBUS, 124
- Power failure, 108
- Power supply
 - Connecting, 68
 - Rules for the line voltage, 67
 - Safety rules, 66
 - Switching on, 98
 - VDE guideline, 66
- Power-up
 - Control Unit, 98
- PROFIBUS address, 131
- PROFIBUS cable
 - Baud rate, 80
 - Cable length, 80
 - Connecting, 81
 - Properties, 79
 - removing, 82
 - Rules for cabling, 80
- PROFIBUS DP
 - Definitions, 128
 - Transmission rate, 135
- PROFIBUS DP
 - Creating a new subnet, 135
 - DP cycle, 131
 - Interfaces, 129
- PROFINET
 - Cable types, 87
 - Cabling, 85
 - Diagnostics via LED displays, 319
 - DP cycle, 145
 - IO controller, 146
 - IO device, 146
 - Properties, 146

- Project
 - archiving on CF card, 181
 - creating, 121
 - Load, 313
 - Project update
 - Web server, 305
 - Protection against external electrical phenomena, 67
 - Protective conductor connection, 61
- R**
- References, 4
 - Replace module
 - DRIVE-CLiQ type, 288
 - Restoring
 - Non-volatile data, 336
 - Restoring the default settings
 - SIMOTION D4x5, 270
 - SINAMICS Integrated, 270
 - Retain data
 - Backing up, 291, 330
 - Retain data and user data
 - Backing up, 310
- S**
- Safety information, 52
 - Service selector switch
 - Switch position 1, 337
 - Servicing
 - Overview, 281
 - Shield connection
 - Using, 76
 - SIMOTION D4x5
 - Hardware components, 27
 - Possible applications, 25
 - Software components, 28
 - System overview, 25
 - User memory concept, 101
 - Variants, 26
 - SIMOTION SCOUT
 - Documentation, 34
 - engineering, 219
 - Installing, 121
 - SIMOTION Task Profiler, 339
 - SIMOTION D4x5
 - Installing, 43
 - SINAMICS Integrated
 - Restoring the factory settings, 270
 - Speed controller
 - Adjusting the P-gain, 263
 - Optimizing, 260
 - Starting the measuring function, 261
 - Standard IE cable types, 87
 - Starter, 34
 - Subnet
 - Connection components, 78
 - Connection rules, 82
 - Segment, 79
 - Terminating resistor, 79
 - Switching on
 - Requirement, 95
 - System
 - Powering down, 271
 - System components, 29
 - System cycle clock, 132
 - Bus cycle clock, 131
 - DP cycle, 145
 - IPO cycle clock, 131, 145
 - Position control cycle clock, 131
 - Ratios of system cycle clocks, 132
 - System function
 - _savePersistentMemoryData, 107
 - System variable
 - batteryexisting, 111
 - batterynecessary, 111
- T**
- Task Profiler, 339
 - Terminating resistor, 79
 - Testing the drive, 216
 - TM41
 - Programming, 255
 - TM41 terminal module, 254
 - Configuring, 254
 - Totally Integrated Automation, 25
 - Transmission rate
 - Adapting, 135
- U**
- UL certification, 347
 - Unit data
 - Backing up, 291
 - User data
 - Deleting, 269
 - Loading, 265
 - User memory concept, 101
 - Backup time, 103
 - Fan/battery module, 103
 - Non-volatile data, 102

Volatile data, 104

V

Variables

 Backing up, 291

Vibrations

 Reduction, 39

Volatile data, 104

W

Web server

 Diagnostics, 339

 FW update, 305

