

*Expansion Module EM-UNI-01*

*Frequency Inverter 230V / 400V*

**ACTIVE and  
ACTIVE Cube**



## General points on the documentation

The present supplement of the documentation is valid for the frequency inverter series ACT and ACU. The information necessary for the assembly and application of the EM-UNI-01 expansion module is documented in this guidance.

For better clarity, the user documentation is structured according to the customer-specific demands made of the frequency inverter.

### Quick Start Guide

The Quick Start Guide describes the fundamental steps for mechanical and electrical installation of the frequency inverter. The guided commissioning supports you in the selection of necessary parameters and the software configuration of the frequency inverter.

### Operating instructions

The operating instructions document the complete functionality of the frequency inverter. The parameters necessary for specific applications for adaptation to the application and the extensive additional functions are described in detail.

### Application manual

The application manual supplements the documentation for purposeful installation and commissioning of the frequency inverter. Information on various subjects connected with the use of the frequency inverter is described specific to the application.

### Installation instructions

As a complement of the brief instructions and the operating instructions, the installation instructions describe the installation and use of devices.

The documentation and additional information can be requested via your local representation of the company BONFIGLIOLI.

The following pictograms and signal words are used in the documentation:



#### **Danger!**

means a directly threatening danger. Death, serious injury and considerable damage to property will occur if the precautionary measure is not taken.



#### **Warning!**

marks a possible threat. Death, serious injury and considerable damage to property can be the consequence if attention is not paid to the text.



#### **Caution!**

refers to an indirect threat. Injury or damage to property can be the result.

#### **Attention!**

refers to a possible operational behavior or an undesired condition, which can occur in accordance with the reference text.

#### **Note**

marks information, which facilitates handling for you and supplements the corresponding part of the documentation.



**Warning!** In installation and commissioning, comply with the information in the documentation. You as a qualified person must read the documentation carefully before the start of the activity and obey the safety instructions. For the purposes of the instructions, "qualified person" designates a person acquainted with the erection, assembly, commissioning and operation of the frequency inverters and possessing the qualification corresponding to the activity.

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## 1 General safety and application information

This documentation has been created with greatest care and has been extensively and repeatedly checked. For reasons of clarity, we have not been able to take all detailed information on all the types of the products and also not every imaginable case of positioning, operation or maintenance into account. If you require further information or if particular problems not treated extensively enough in the operating instructions occur, you can obtain the necessary information via the local representation of the company of BONFIGLIOLI.

In addition, we would point out that the contents of these operating instructions are not part of an earlier or existing agreement, assurance or legal relationship, nor are they intended to amend them. All the manufacturer's obligations result from the purchase contract in question, which also contains the completely and solely valid warranty regulation. These contractual warranty provisions are neither extended nor limited by the implementation of these operating instructions.

The manufacturer reserves the right to correct or amend the contents and product information as well as omissions without specific announcement and assumes no kind of liability for damage, injuries or expenditure to be put down to the aforementioned reasons.

### 1.1 General information



**Warning!** BONFIGLIOLI VECTRON frequency inverters have high voltage levels during operating, depending on their protection class, drive moving parts and have hot surfaces.

In the event of inadmissible removal of the necessary covers, improper use, wrong installation or operation, there is the risk of serious damage to persons or property.

To avoid these damages, only qualified staff may carry out the transport, installation, setup or maintenance work required. Comply with the standards EN 50178, IEC 60364 (Cenelec HD 384 or DIN VDE 0100), IEC 60664-1 (Cenelec HD 625 or VDE 0110-1), BGV A2 (VBG 4) and national provisions. Qualified persons within the meaning of this principal safety information are people familiar with the erection, fitting, commissioning and operating of frequency inverters and the possible hazards and in possession of qualifications matching their activities.

## 1.2 Proper use



**Warning!** The frequency inverters are electrical drive components intended for installation in industrial facilities or machines. Commissioning and start of intended operation are not allowed until it has been established that the machine corresponds to the provisions of the EC machine directive 98/37/EEC and EN 60204. According to the CE sign, the frequency inverters additionally fulfill the requirements of the low-voltage directive 2006/95/EC and standards EN 50178/DIN VDE 0160 and EN 61800-2. Responsibility for compliance with the EMC directive 89/336/EEC is with the user. Frequency inverters are available in a limited way and as components exclusively intended for professional use within the meaning of the standard EN 61000-3-2.

With the issue of the UL certificate according to UL508c, the requirements of the CSA Standard C22.2-No. 14-95 have also been fulfilled.

The technical data and the information on connection and ambient conditions can be seen from the rating plate and the documentation and are to be complied with at all costs.

## 1.3 Transport and storage

Transport and storage are to be done appropriate in the original packing. Store the units only in dry rooms, which are protected against dust and moisture and are subjected to little temperature deviations. Observe the climatic conditions according to standard EN 50178 and to the values on the label of the original packing. The duration of storage without connection to the admissible reference voltage may not exceed one year.

## 1.4 Handling and installation



**Warning!** Damaged or destroyed components may not be put into operation because they may be a health hazard.

The frequency inverters are to be used according to the documentation, the directives and the standards. Handle carefully and avoid mechanical overloading. Do not bend the components or change the isolation distances. Do not touch electronic components or contacts. The devices contain construction elements with a risk of electrostatic, which can easily be damaged by improper handling. Any use of damaged or destroyed components shall be considered as a non-compliance with the applicable standards. Do not remove any warning signs from the device.

## 1.5 Electrical connection



**Warning!** Before any assembly or connection work, de-energize the frequency inverter.

Do not touch the sockets, because the capacitors may still be charged.

Make sure that the frequency inverter is de-energized.

Comply with the information given in the operating instructions and on the frequency inverter label.

In work on the frequency inverters, observe the applicable standards BGV A2 (VBG 4), VDE 0100 and other national directives. Comply with the information in the documentation on electrical installation and the relevant directives. Responsibility for compliance with and examination of the limit values of the EMC product standard EN 61800-3 for variable-speed electrical drive mechanisms is with the manufacturer of the industrial plant or machine.

The documentation contains information on installation correct for EMC. The cables connected to the frequency inverters may not be subjected to an isolation test with a high test voltage without previous circuit measures.

## 1.6 Information on use



**Warning!** The frequency inverter may be connected to power supply every 60 s. This must be considered when operating a mains contactor in jog operation mode. For commissioning or after an emergency stop, a non-recurrent, direct restart is permissible.

After a failure and restoration of the power supply, the motor may start unexpectedly if the AutoStart function is activated.

If staff is endangered, a restart of the motor must be prevented by means of external circuitry.

Before commissioning and the start of the operation, make sure to fix all covers and check the terminals. Check the additional monitoring and protective devices according to EN 60204 and applicable the safety directives (e.g. Working Machines Act, Accident Prevention Directives etc.).

No connection work may be performed, while the system is in operation..

## 1.7 Maintenance and service



**Warning!** Unauthorized opening and improper interventions can lead to physical injury or damage to property. Repairs on the frequency inverters may only be done by the manufacturer or persons authorized by the latter.



## 2 Introduction

This document describes the possibilities and the properties of the EM-UNI-01 expansion module for the frequency inverters of the ACT and ACU device series.

**Note:** This document exclusively describes the EM-UNI-01 expansion module. It does not provide basic information on the operation of the ACT and ACU series frequency inverters.

The EM-UNI-01 expansion module is an optional hardware component to extend the functionality of the frequency inverter. It enables the data exchange within the network between the components which have been directly connected, for example control and regulation elements.

The EM-UNI-01 expansion module is supported from device series ACU and as from software version 4.1.0 of device series ACT.

The EM-UNI-01 module extends the functionality of the frequency inverters of the ACT and ACU device series by the following additional functions:

- **CAN system bus**  
(CAN interface ISO-DIS 11898; CAN High Speed; max. 1 Mbaud)
- **Analog input**  
(additional bipolar analog input)
- **Analog output (electrical current output)**  
(additional analog output)
- **Speed sensor input**  
(speed sensor input or alternatively use of 2 inputs as digital inputs)
- **Digital inputs**  
(alternatively use as speed sensor input)
- **20 VDC supply voltage for speed sensor**
- **Digital port**  
(digital input/output)
- **PTC thermistor connection**
- **Potential free normally open contact for brake control (electronic relays)**

**Note:** The EM-UNI-01 expansion module has been enclosed with the frequency inverter as a separate component and must be fitted by the user. This is described in detail in the chapter "Mechanical Installation".

To assemble the expansion module it can be easily plugged into the frequency inverters of the ACT and ACU device series.



**Caution!** Do the assembly before the frequency inverter is put into operation, and only in a voltage-free state.

The pluggable sockets of the expansion module enable economical overall fitting with a safe function.

### 3 Installation of the EM-UNI-01 expansion module

#### 3.1 General

The mechanical and electrical installation of the EM-UNI-01 expansion module is to be carried out by qualified personnel according to the general and regional safety and installation directives. Safe operation of the frequency inverter requires that the documentation and the device specification be complied with in installation and start of operation. For specific areas of application further provisions and guidelines must be complied with where applicable.

The frequency inverters are designed according to the requirements and limit values of product standard EN 61800-3 with interference immunity factor (EMI) for operation in industrial applications. The electromagnetic interference is to be avoided by expert installation and observation of the specific product information.

For further information, refer to the chapter "Electrical Installation" of the frequency inverter operating instructions.



**Warning!** All connection sockets where dangerous voltage levels may be present (e.g. motor connection sockets, mains sockets, fuse connection sockets, etc.), must be protected against direct contact.

#### 3.2 Mechanical installation



**Danger!** If the following instructions are not complied with, there is direct danger with the possible consequences of death or severe injury by electrical current. Further, failure to comply can lead to destruction of the frequency inverter and/or of the expansion module.

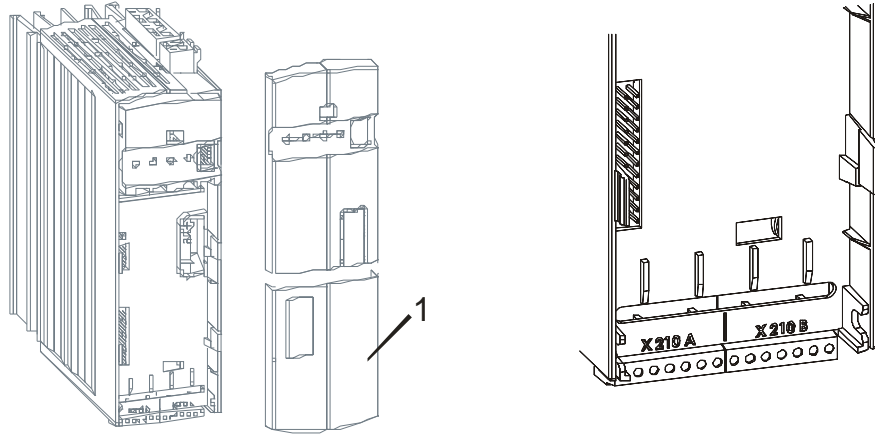
- Before assembly or disassembly of the EM-UNI-01 expansion module, the frequency inverter must be de-energized. Take appropriate measures to make sure it is not energized unintentionally.
- Make sure that the frequency inverter is de-energized.



**Danger!** The mains, direct voltage and motor sockets can be live with dangerous voltages after disconnection of the frequency inverter. Work may only be done on the device after a waiting period of some minutes until the DC link capacitors have been discharged.

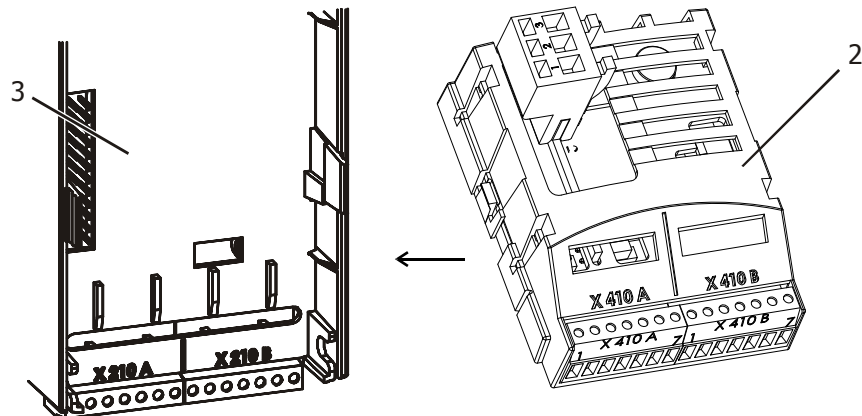
The EM-UNI-01 expansion module is supplied in a housing for assembly on the lower slot of the frequency inverter.

- Remove the lower cover (1) of the frequency inverter.  
The slot for the EM-UNI-01 expansion module becomes accessible.



**Caution!** The EM-UNI-01 expansion module (2) is pre-fitted in a housing. Do NOT touch the PCB visible on the back, as modules may be damaged.

- Plug the EM-UNI-01 expansion module (2) onto the slot (3).



- According to chapter "Electrical installation" connect the by customer intended cables to the sockets X410A and X410B.
- Disconnect the socket X412 from the module.
- Re-install the cover (1).
- Connect the by customer intended cables to the socket X412.
- Reconnect the socket X412 to the module.

### 3.3 Electrical installation



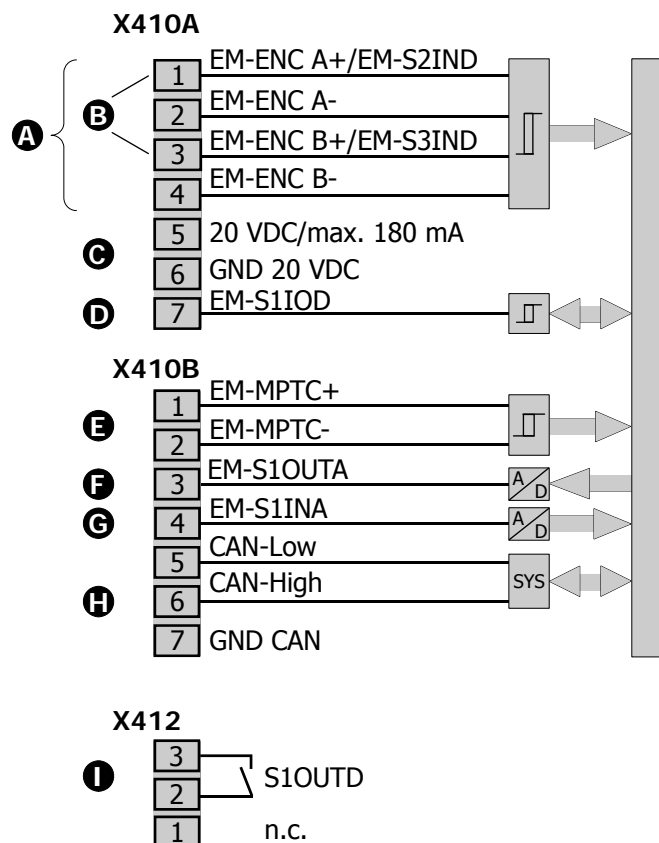
**Danger!** If the following instructions are not complied with, there is direct danger with the possible consequences of death or severe injury by electrical current. Further, failure to comply can lead to destruction of the frequency inverter and/or of the expansion module.

- Before assembly or disassembly of the EM-UNI-01 expansion module, the frequency inverter must be de-energized.
- Take appropriate measures to make sure it is not energized unintentionally.
- Make sure that the frequency inverter is de-energized.



**Danger!** The mains, direct voltage and motor sockets can have dangerous voltages even after disconnection of the frequency inverter. Work may only be done on the device after a waiting period of some minutes until the DC link capacitors have discharged.

#### 3.3.1 Circuit diagram



**A Speed sensor input EM-ENC**

Frequency signal,  $f_{max} = 300$  kHz, voltage-proof until 30 V, TTL (push-pull) according to specification RS-422A / RS-485,  $U_{max} = 5$  V, HTL (push-pull or unipolar),  $I_{max} = 12$  mA at 24 V

**B Digital inputs EM-S2IND and EM-S3IND**

Digital inputs EM-S2IND (socket 1) and EM-S3IND (socket 3).  $U_{max} = 30$  V ( $R_i \approx 2$  k $\Omega$ ); PLC compatible.

**C Voltage output for speed sensor**

Socket 5: 20 VDC /  $I_{max} = 180$  mA  
 Socket 6: GND 20 VDC.

**D Digital Port EM-S1IOD**

Digital input, response time approx. 16 ms,  $U_{max} = 30$  V, 10 mA at 20 VDC, PLC compatible;  $f_{max} = 150$  kHz  
 HIGH-level detection:  $\geq 12$  V, LOW-level detection:  $\leq 3$  V  
 Digital output: 18...24 V<sub>DC</sub> (depending on the electrical strength at the voltage output 20 VDC) ,  $I_{max} = 40$  mA, PLC compatible

**E Motor PTC Resistor Connection EM-MPTC**

Rated response resistance  $> 2.6$  k $\Omega$  (PTC) according to DIN 44081, PTC or bimetal temperature sensor (break contact)

**F Analog output EM-S1OUTA**

Analog signal,  $I_{max} = +20$  mA ( $R_{max} = 500$   $\Omega$ )

**G Analog input EM-S1INA**

Analog signal, resolution 10 Bit,  $U_{max} = \pm 10$  V ( $R_i = 100$  k $\Omega$ ),  $I_{max} = \pm 20$  mA ( $R_i = 250$   $\Omega$ )

**H Communication interface system bus**

CAN actuation of the system bus according to ISO-DIS 11898 (CAN High Speed)




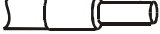



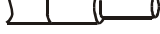
**I Electronic relay/normally open contact for brake control, S1OUTD.1 und S1OUTD.2**

$U_{min} = 12$  VAC (50 Hz ... 60 Hz);  $U_{max} = 275$  VAC (50 Hz ... 60 Hz),  
 $I_{min} = 50$  mA;  $I_{max} = 1,0$  A (up to 70 °C),  
 only for alternating voltage (AC), not suitable for direct current (DC)


### 3.3.2 Sockets

The control and software functionality can be freely configured for economical operation with a safe function.

**Expansion module EM-UNI-01**

		<b>Wieland DST85 / RM3,5</b>	
			0.14 ... 1.5 mm <sup>2</sup> AWG 30 ... 16
			0.14 ... 1.5 mm <sup>2</sup> AWG 30 ... 16
			0.25 ... 1.0 mm <sup>2</sup> AWG 22 ... 18
			0.25 ... 0.75 mm <sup>2</sup> AWG 22 ... 20
		0.2 ... 0.3 Nm 1.8 ... 2.7 lb-in	
		<b>Phoenix ZEC 1,5/3ST5,0</b>	
			0.2 ... 1.5 mm <sup>2</sup> AWG 24 ... 16
			0.2 ... 1.5 mm <sup>2</sup> AWG 24 ... 16
			0.25 ... 1.5 mm <sup>2</sup> AWG 22 ... 16
			0.25 ... 1.5 mm <sup>2</sup> AWG 22 ... 16

X412





**Caution!** The control inputs and outputs must be connected and disconnected free of electrical power.

When using sockets X410A.1 and X410A.3 as digital input, the sockets X410A.2 and X410A.4 must be unconnected.

Socket X410A	
Ter.	Description
1	Speed sensor input EM-ENC A+ or digital input EM-S2IND
2	Speed sensor input EM-ENC A-
3	Speed sensor input EM-ENC B+ or digital input EM-S3IND
4	Speed sensor input EM-ENC B-
5	Voltage output 20 VDC, $I_{max} = 180 \text{ mA}$ <sup>1)</sup> , for speed sensor supply
6	Earth/GND 20 VDC
7	Digital Port EM-S1IOD

Socket X410B	
Ter.	Description
1-2	Motor PTC connection EM-MPTC, rated response resistance > 2.6 k $\Omega$ (PTC) according DIN 44081
3	Analog output EM-S1OUTA, $I_{max} = +20 \text{ mA}$ ( $R_{max} = 500 \Omega$ )
4	Analog input EM-S1INA, resolution 10 bit, $U_{max} = \pm 10 \text{ V}$ ( $R_i = 100 \text{ k}\Omega$ ), $I_{max} = \pm 20 \text{ mA}$ ( $R_i = 250 \Omega$ )
5	System bus, CAN low
6	System bus, CAN high
7	Earth/GND

<sup>1)</sup> The power supply of 20 VDC at terminal X210A.1 may be loaded with a maximum current of  $I_{max} = 180 \text{ mA}$ . Relative to the application, the maximum current available will be reduced by the further control outputs in the basic device and the expansion module.

Socket X412	
Ter.	Description
3	S1OUTD.2 – Potential-free normally open contact
2	S1OUTD.1 – Potential-free normally open contact
1	Not connected

When the supply voltage of the frequency inverter is switched on, the EM-UNI-01 expansion module is ready for operation.

## 4 System bus interface

The CAN connection of the system bus is physically designed according to **ISO-DIS 11898** (CAN High Speed). The bus topology is the line structure.

In the default version, the frequency inverter support a CAN protocol controller, which may exist in **either** the CM-CAN communication module with CANopen interface **OR** in an expansion module for the system bus, such as the EM-UNI-01 expansion module.

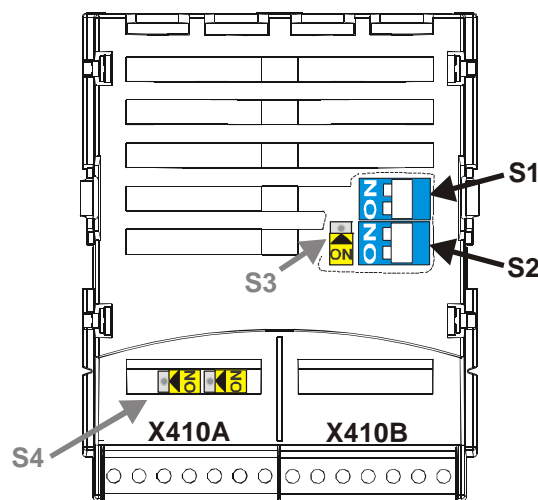
**Attention!** Installation of two optional components with CAN-Protocol controller results in a deactivation of the system bus interface in the EM-UNI-01 expansion module!

### 4.1 Bus termination

The necessary bus terminator at the physically first and last node can alternatively be activated via the two **DIP switches S1 and S2** on the EM-UNI-01 expansion module.

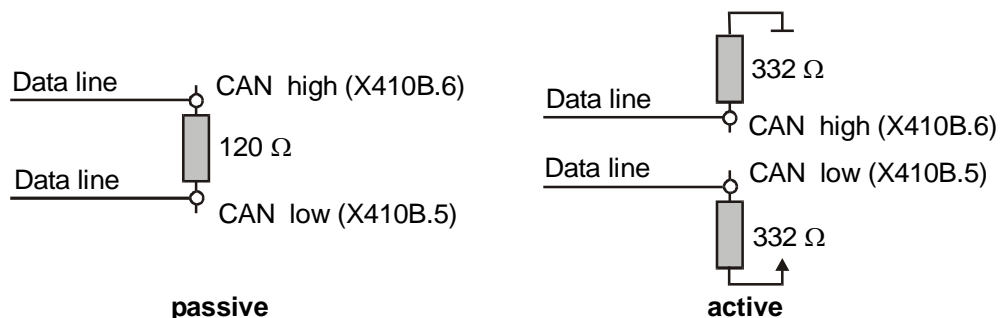
- Either switch **S1** to ON and **S2** to OFF for a **passive** termination.
- or switch **S1 and S2** to ON for an **active** termination. This results in an improved edge shape of the CAN signals, which results in an improvement of the signal shapes, in particular in extended systems.

**Note:** Switch **S3** is used to configure the analog input (see chapter "Analog input EM-S1INA").  
Switch **S4** is used to configure a termination resistor of 150  $\Omega$  for the speed sensor input EM-ENC (see chapter „Speed Sensor input EM-ENC“).



**Attention!** The factory setting for the bus termination is **OFF**.

An active termination may only be switched **once** on a bus system via **S1** and **S2**. The other bus termination has to be done in passive mode.



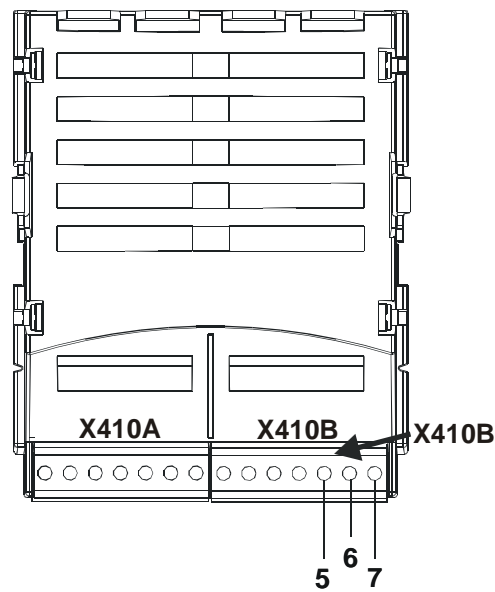
## 4.2 Cables

For the bus line, use a twisted cable with harness shield (**no foil shield**).

**Attention!** The control and communication lines are to be laid physically separate from the power lines. The harness screen of the data lines is to be connected to ground (PE) on both sides on a large area and with good conductivity.

## 4.3 Socket X410B

The system bus is connected via the terminals **5**, **6** and **7** of the plug **X410B** on the EM-UNI-01 expansion module.



Socket X410B		
Terminal	Input/Output	Description
(5) X410B.5	CAN-Low	CAN-Low (System bus)
(6) X410B.6	CAN-High	CAN-High (System bus)
(7) X410B.7	GND	CAN-GND (System bus)



#### 4.4 Baud rate setting/line length

The setting of the baud rate must be identical in all nodes on the system bus. The maximum possible baud rate is based on the necessary overall line length of the system bus. The baud rate is set via the parameter *Baud-Rate* **903** and thus defines the possible line length.

Operation mode	Function	max. line length
3 - 50 kBaud	Transmission rate 50 kBaud	1000 meters
4 - 100 kBaud	Transmission rate 100 kBaud	800 meters
5 - 125 kBaud	Transmission rate 125 kBaud	500 meters
6 - 250 kBaud	Transmission rate 250 kBaud	250 meters
7 - 500 kBaud	Transmission rate 500 kBaud	100 meters
8 - 1000 kBaud	Transmission rate 1000 kBaud	25 meters

A baud rate under 50 kBaud, as is defined according to CANopen, is not sensible for the system bus as the data throughput is too low.

The maximum line lengths stated are guidelines. If they are made complete use of, a calculation of the admissible length is to be done on the basis of the line parameters and the bus driver (PCA82C250T).

#### 4.5 Setting node address

A maximum of 63 slaves or frequency inverters with system bus can be operated on the system bus. Each frequency inverter is given a node ID, which may only exist once in the system, for its unambiguous identification. The setting of the system bus node ID is done via the parameter *Node-ID* **900**.

Parameter		Setting		
No.	Description	min.	max.	Factory setting
900	Node-ID	-1	63	-1

Thus, the system bus possesses a maximum number of 63 nodes (Network nodes), plus one frequency inverter as a master.

**Note:** With the factory setting of parameter *Node-ID* **900** = -1, the system bus is deactivated for this frequency inverter.  
If the *Node-ID* **900** = 0 is set, the frequency inverter is defined as a master. Only one frequency inverter on the system bus may be defined as a master.

## 4.6 Functional overview

The system bus connects different frequency inverters physically. Logical communication channels are established via this physical medium. These channels are defined via the identifiers. As CAN is not defined with a node-oriented, but a message-oriented addressing via the identifiers, these identifiers can be used to define the logical channels.

In the basic state (factory setting) the identifiers are set according to the Predefined Connection Set of CANopen. These settings are aimed at one master serving all the channels. In order to be able to build up process data movement via the PDO channels between an individual and a number of inverters (transverse movement), the setting of the identifiers in the nodes has to be adapted.

**Note:** The exchange of data is done message-oriented. A frequency inverter can transmit and receive a number of messages, identified via various identifiers.

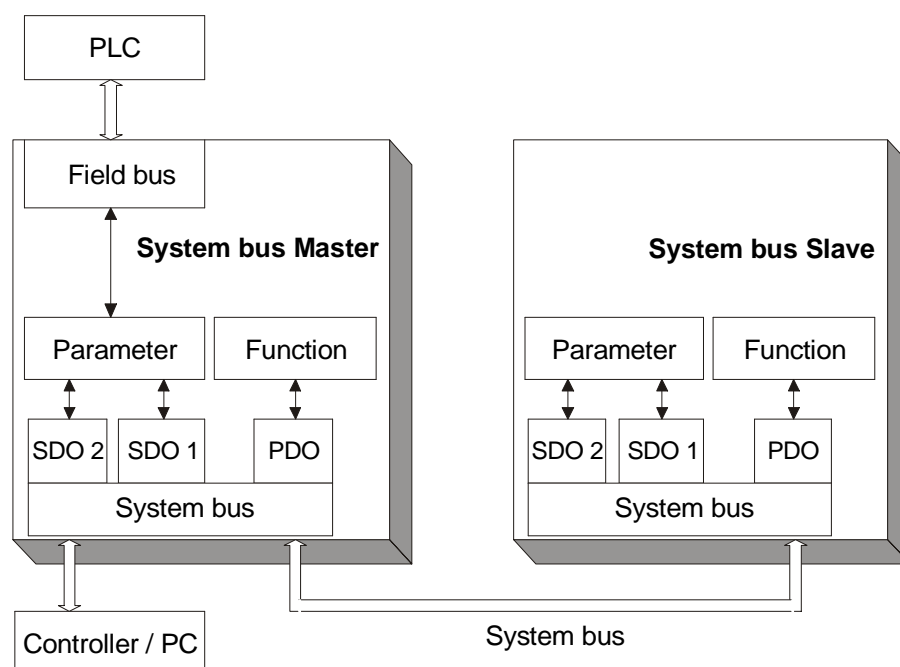
As a special feature, the properties of the CAN bus mean that the messages transmitted by one node can be received by a number of nodes simultaneously. The error monitoring methods of the CAN bus result in the message being rejected by all recipients and automatically transmitted again if there is a faulty reception in one receiver.

## 4.7 Network management

The network management controls the start of all the nodes on the system bus. Nodes can be started or stopped individually or together. For node recognition in a CAN or CAN open system, the slaves on the system bus generate a starting telegram (boot-up report).

In the event of a fault the slaves automatically transmit a fault report (emergency message).

For the functions of the network management, the methods and NMT telegrams (network management telegrams) defined according to CAN open (CiA DS 301) are used.



#### 4.7.1 SDO channels (parameter data)

Each frequency inverter possesses two SDO channels for the exchange of parameter data. In a slave device, these are two server SDO's, in a device defined as a master a client SDO and a server SDO. Attention must be paid to the fact that only one master for each SDO channel may exist in a system.

**Note:** Only one master can initiate exchange of data by its client SDO via the system bus.

The identifier assignment for the SDO channels (Rx/Tx) is done according to the Pre-defined Connection Set.

This assignment can be changed via parameters in order to solve identifier conflicts in a larger system in which other devices and frequency inverters are connected to the CAN bus.

**Attention!** In a system where a frequency inverter works as a master, the identifier allocations for the SDO channel may not be altered.  
In this way, an addressing of individual nodes via the field bus/system bus path of the master frequency inverter is possible.

Parameters are read/written via the SDO channels. With the limitation to the SDO Segment Protocol Expedited, which minimizes the handling needed for the parameter exchange, the transmittable data are limited to the uint / int / long types. This permits complete parameterization of the frequency inverters via the system bus, as all the settings and practically all the actual values mapped to these data types.

#### 4.7.2 PDO channels (process data)

Each frequency inverter possesses three PDO channels (Rx/Tx) for the exchange of process data.

The identifier assignment for the PDO channel (Rx/Tx) is done by default according to the Predefined Connection Set. This assignment corresponds to an alignment to a central master control.

In order to establish logical channels between the devices (transverse movement) on the system bus, the amendment of the PDO identifiers for Rx/Tx is necessary.

Each PDO channel can be operated with time or SYNC control. In this way, the operation behavior can be set for each PDO channel:

The setting of the operation mode is done via the following parameters:

*TxPDO1 Function 930, TxPDO2 Function 932 und TxPDO3 Function 934*

*RxPDO1 Function 936, RxPDO2 Function 937 und RxPDO3 Function 938*

Operation mode	Function
0 - deactivated	no exchange of data via the PDO channel (Rx and/or Tx)
1 - time-controlled	Tx-PDO's cyclically transmit according to the time specification Rx-PDO's are read in with $T_a = 1$ ms and forward the data received to the application
2 - SYNC controlled	Tx-PDO's transmit the data from the application that are then current after the arrival of the SYNC telegram. Rx-PDO's forward the last data received to the application after the arrival of the SYNC telegram.

For synchronous PDO's, the master (PC, PLC or frequency inverter) generates the SYNC telegram. The identifier assignment for the SYNC telegram is done by default according to the Predefined Connection Set. This assignment can be altered by parameterization.

## 4.8 Master functionality

An external control or a frequency inverter defined as a master (node ID = 0) can be used as a master. The fundamental tasks of the master are controlling the start of the network (boot-up sequence), generating the SYNC telegram and evaluating the emergency messages of the slaves.

Further, there can be access to the parameterization of all the frequency inverters on the system bus by means of a field bus connection via the client SDO of the master frequency inverter.

### 4.8.1 Control boot-up sequence, network management

The Minimum Capability Boot-Up method defined according to CANopen is used for the state control of the nodes (nodes).

This method knows the pre-operational, operational and stopped states.

After the initialization phase, all the nodes are in the pre-operational state. The system bus master transmits the NMT command **Start-Remote-Node**. With this command, individual nodes or all the nodes can be started together. A frequency inverter defined as a master starts **all** the nodes with **one** command. After receipt of the Start Remote Node command, the nodes change into the Operational state. From this time on, process data exchange via the PDO channels is activated.

A master in the form of a PLC/PC can start a node on the system bus individually and also stop them again.

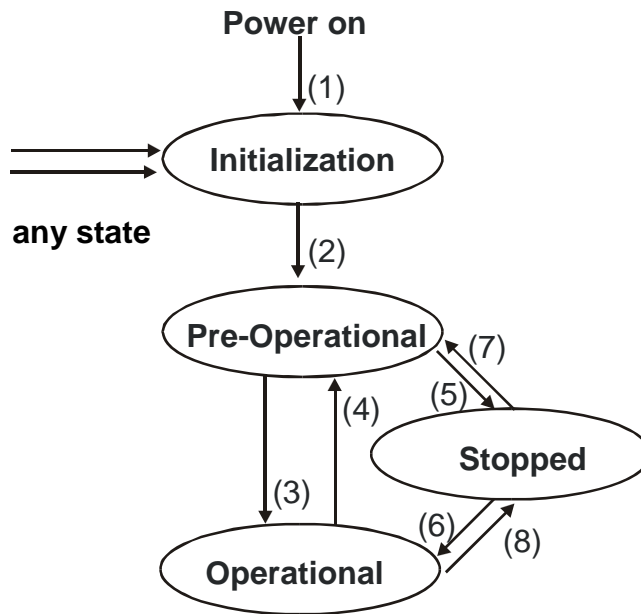
As the slaves on the system bus need different lengths of time to conclude their initialization phases (especially if external components exist alongside the frequency inverters), an adjustable delay for the change to Operational state is necessary. The setting is done in a frequency inverter defined as a system bus master via *Boot-Up Delay 904*.

Parameter		Setting		
No.	Description	Min.	Max.	Factory setting
904	Boot-Up Delay	3500 ms	50000 ms	3500 ms

#### Properties of the states:

State	Properties
Pre-Operational	Parameterization via SDO channel possible Exchange of process data via PDO channel not possible
Operational	Parameterization via SDO channel possible Exchange of process data via PDO channel possible
Stopped	Parameterization via SDO channel not possible Exchange of process data via PDO channel not possible

**Note:** Start-Remote-Node is cyclically transmitted with the set delay time by a frequency inverter defined as a system bus master, in order to put slaves added with a delay or temporarily separated from the network back into the Operational state.



After Power On and initialization, the slaves are in the Pre-Operational state. The transition (2) is automatic. The system bus master (frequency inverter or PLC/PC) triggers the transition (3) to Operational state. The transitions are controlled via NMT telegrams.

The identifier used for the NMT telegrams is "0" and may only be used by the system bus master for NMT telegrams. The telegram contains two data bytes.

Byte 0	Byte 1
CS (Command Specifier)	Node-ID

Identifier = 0

Is node ID  $\neq$  0, the NMT command addresses the node selected via the node ID. If node ID = 0, **all** the nodes are addressed.

Transition	Command	Command Specifier
(3) , (6)	Start Remote Node	1
(4) , (7)	Enter Pre-Operational	128
(5) , (8)	Stop Remote Node	2
-	Reset Node	129
-	Reset Communication	130

**Note:** The frequency inverter defined as a system bus master only transmits the command "Start Remote Node" with node ID = 0 (for all nodes). Transmission of the command is done after completion of the initialization phase and the time delay *Boot-Up Delay* **904** following it.

## 4.8.2 SYNC telegram, generation

If synchronous PDO's have been created on the system bus, the master must send the SYNC telegram cyclically. If a frequency inverter has been defined as a system bus master, the latter must generate the SYNC telegram. The interval for the SYNC telegram of a frequency inverter defined as the system bus master is adjustable. The SYNC telegram is a telegram without data.

**The default identifier = 128 according to the Predefined Connection Set.**

If a PC or PLC is used as a master, the identifier of the SYNC telegrams can be adapted by parameterization on the frequency inverter.

The identifier of the SYNC telegram must be set identically in all nodes on the system bus.

The setting of the identifier of the SYNC telegram is done via the parameter *SYNC-Identifier* **918**.

Parameter		Setting		
No.	Description	Min.	Max.	Fact. sett.
918	SYNC-Identifier	0	2047	0

The setting "0" results in identifier assignment according to the Predefined Connection Set.

**Attention!** The identifier range 129...191 may not be used as the emergency telegrams can be found there.

The temporal cycle for the SYNC is set on a frequency inverter defined as a system bus master via the parameter *SYNC-Time* **919**.

**Note:** A setting of 0 ms for the parameter *SYNC-Time* 919 means "no SYNC telegram".

### 4.8.3 Emergency message, reaction

If a slave on the system bus enters a fault state, it transmits the emergency telegram. The emergency telegram marks the node ID for the identification of the failed node via its identifier and the existing fault message via its data contents (8 bytes).

After a fault has been acknowledged on the slave, the latter again transmits an emergency telegram with the data content zero.

The emergency telegram has the identifier 128 + node ID ( = 129 ... 191)

The system bus master evaluates the emergency telegrams of the slaves. Its reaction to an emergency telegram can be set with *Emergency Reaction 989*.

Operation mode	Function
0 - Error	The system bus master receives the emergency telegram and switches-off
1 - No Error	The Emergency Telegram is displayed as a warning

#### Operation mode - parameter 989 = 0 – Error

Behavior of the system bus master in *Emergency Reaction 989 = 0 / Error*:

As soon as the system bus master receives an emergency telegram, it also switches to failure mode and reports the failed node on the basis of its ID via the kind of error. Only the node is reported, not the cause of the error.

The fault message on the system bus master via *Current error 260* is **21nn** with **nn = node ID** (hexadecimal) of the slave in which a fault switch-off exists. In addition, the system bus master reports the warning Sysbus (0x2000) via the parameter *Warnings 270* Bit 13.

If a fault switch-off occurs on a number of slaves, the first slave to transmit its emergency telegram is displayed on the system bus master.

#### Operation mode - parameter 989 = 1 – No Error

Behavior of system bus master in the case of *Emergency Reaction 989 = 1 / No Error*:

As soon as the system bus master receives an emergency telegram, it reports the warning Sysbus (0x2000) via the parameter *Warnings 270* Bit 13.

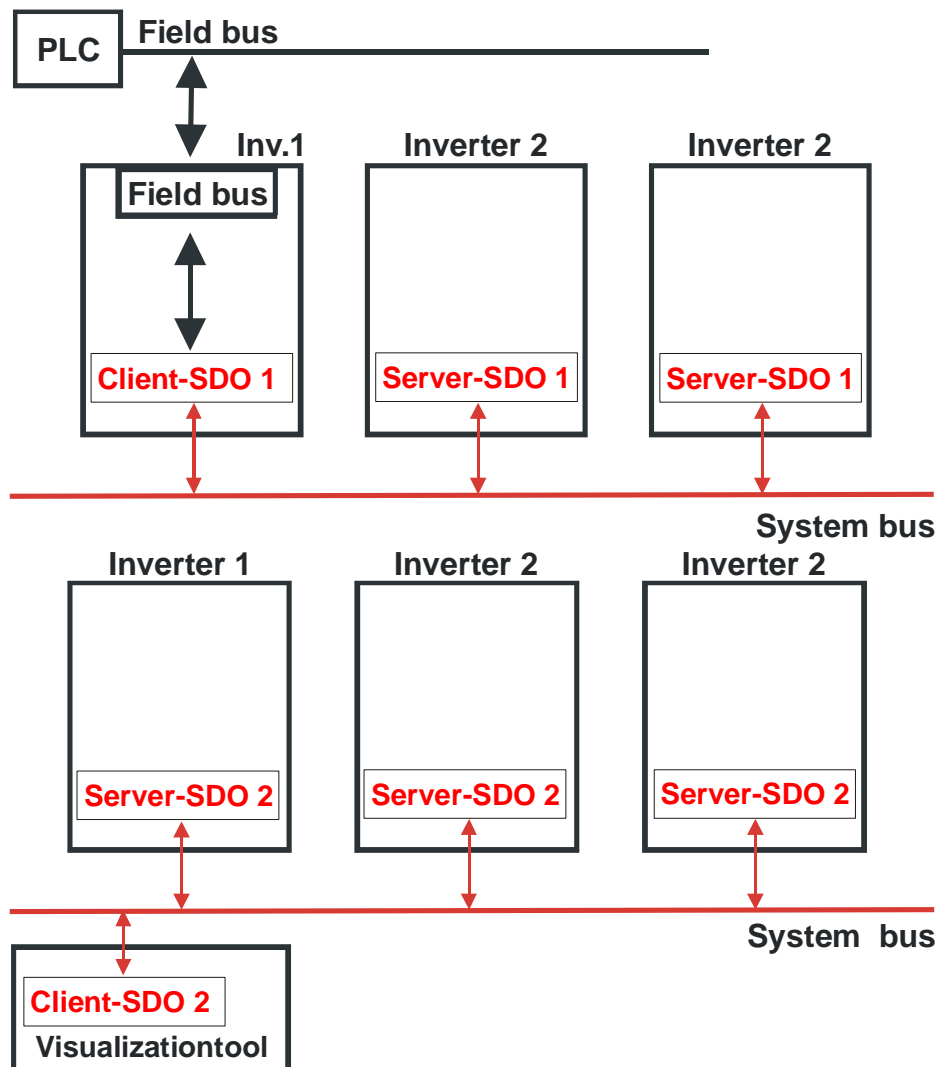
**Note:** In both cases, the Boolean variable SysbusEmergency with source number 730 is set to TRUE in the system bus master. It can be used in the system bus master and (in transmission via a TxPDO) in the slaves for a defined shutdown. SysbusEmergency is also set if the system bus master enters fault state. Resetting of SysbusEmergency is done with the fault acknowledgment.

#### 4.8.4 Client SDO (system bus master)

Each node on the system bus can be addressed via the SDO channels. In this way, each node can be addressed and parameterized by one master via its client SDO1. All the parameters of the data types uint/int/long are accessible. String parameters cannot be processed. If a frequency inverter has been defined as a system bus master, each node on the system bus in this frequency inverter can be addressed by via the field bus connection (RS232, RS485, Profibus-DP) and its client SDO1.

**Attention!** The second SDO channel SDO2 of the frequency inverters is planned for the parameterization of the frequency inverters via a visualization tool on the system bus.

The service used is SDO Segment Protocol Expedited according to CANopen. A frequency inverter defined as a system bus master automatically generates the correct telegrams. If the SDO channel is operated via a PLC/PC on the system bus, the telegrams must be generated according to the specification.





## 4.9 Slave functionality

### 4.9.1 Implement boot-up sequence, network management

#### 4.9.1.1 Boot-up message

After the initialization, each slave on the system bus transmits its boot-up message (heartbeat message).

**Note:** The boot-up telegram has the identifier 1792 + node ID and a data byte with contents = 0x00.

This telegram is used when a PLC/PC with CANopen functionality is used as a master. A frequency inverter defined as a system bus master does **not** evaluate the boot-up message.

#### 4.9.1.2 Status control

The identifier used for the NMT telegrams is "0" and may only be used by the system bus master for NMT telegrams. The telegram contains two data bytes.

Byte 0	Byte 1
CS (Command Specifier)	Node-ID

Identifier = 0

If node ID  $\neq$  0, the NMT command acts on the node selected via the node ID. If node ID = 0, **all** the nodes are addressed.

Transition	Command	Command Specifier
(3),(6)	Start Remote Node	1
(4),(7)	Enter Pre-Operational	128
(5),(8)	Stop Remote Node	2
-	Reset Node	129
-	Reset Communication	130

**Attention!** The reset node and reset communication command specified according to DS 301 lead to a change to Pre-Operational via Initialization in the frequency inverters. A new boot-up message is generated.

After a slave has received the command "Start Remote Node", it activates the PDO channels and is ready for the exchange of process data.

## 4.9.2 Process SYNC telegram

If synchronous PDO's have been created in a frequency inverter, their processing is synchronized with the SYNC telegram. The SYNC telegram is generated by the system bus master and is a telegram without data.

**The identifier is 128 according to the Predefined Connection Set.**

If a PC or PLC is used as a master, the identifier of the SYNC telegrams can be adapted by parameterization on the frequency inverter. The identifier of the SYNC telegram must be set identically in all nodes on the system bus.

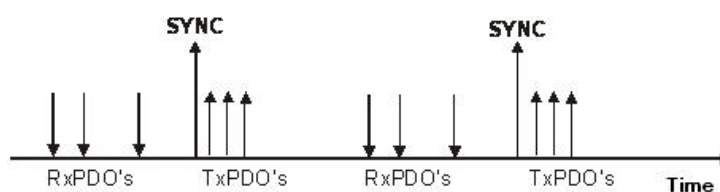
**Attention!** The identifier range 129 ... 191 may not be used as the emergency telegrams can be found there.

The setting of the identifier of the SYNC telegram is done via the parameter *SYNC-Identifier* **918**.

Parameter		Setting		
No.	Description	Min.	Max.	Factory setting
918	SYNC-Identifier	0	2047	0

The setting "0" results in identifier assignment according to the Predefined Connection Set.

The data of the Rx-PDO's are forwarded to the application after the arrival of the SYNC telegram. At the same time, the transmission of the Tx-PDO's with the currently available data from the application is triggered.



This method enables pre-occupancy of set points in the system bus nodes and a synchronous / parallel take-over of the data.

### 4.9.3 Emergency message, fault switch-off

As soon as a fault switch-off occurs in a slave frequency inverter, the emergency telegram is transmitted. The emergency telegram marks the node ID for the identification of the failed node via its identifier and the existing fault message via its data contents (8 bytes).

The emergency telegram has the identifier 128 + node ID.

After a fault acknowledgment, another emergency telegram is transmitted, with the data content (Byte 0 ...7) being set to zero this time. This identifies the node's repeated readiness for operation. Any further faults are transmitted in a new emergency telegram.

The acknowledgment sequence is based on the definitions according to CANopen.

Data contents of the emergency telegram:

Emergency telegram		
Byte	Value	Meaning
0	0x00	low-byte Error-Code
1	0x10	high-byte Error-Code
2	0x80	Error-Register
3	0x00	-
4	0x00	-
5	0x00	-
6	0xnn	internal Error-Code, low-byte
7	0xmm	internal Error-Code, high-byte

Bytes 0, 1 and 2 are firmly defined and compatible with CANopen.  
Bytes 6/7 contain the product specific VECTRON error code.

Error-Code = 0x1000 = general error  
Error-Register = 0x80 = manufacturer-specific error

The explanation and description of the product-specific VECTRON error code can be found in the annex "Error messages".

#### 4.9.4 Server SDO1/SDO2

The communication channel for the exchange of parameter data is the SDO channel. Communication works according to the client/server model. The server is the node holding the data (here the frequency inverter), the client is the node requesting or wanting to alter the data (PLC, PC or frequency inverter as system bus master).

For the frequency inverter, two server SDO channels have been implemented. The first SDO channel **SDO1** is used for the parameterization of the PLC/PC as a master or frequency inverter with field bus connection as a system bus master. The second SDO channel **SDO2** is reserved for a visualization tool for parameterization. An exchange of data can only be implemented by the master via a client SDO.

The SDO channels are stipulated for the server SDO's via identifiers according to the Predefined Connection Set to CANopen. As CANopen only provides for and defines one SDO channel in the Predefined Connection Set, the second SDO channel can be deactivated.

In addition, the number of system bus nodes and the adjustable node ID are limited to 63.

##### **Identifier assignment according to the Predefined Connection Set:**

Identifier Rx-SDO = 1536 + Node-ID (Node-ID = 1 ... 127, Identifier = 1537...1663)  
Identifier Tx-SDO = 1408 + Node-ID (Node-ID = 1 ... 127, Identifier = 1409...1535)

##### **Identifier assignment for SDO1/SDO2 compatible with the Predefined Connection Set:**

Identifier Rx-SDO1 = 1536 + Node-ID (Node-ID = 1 ... 63, Identifier = 1537...1599)  
Identifier Tx-SDO1 = 1408 + Node-ID (Node-ID = 1 ... 63, Identifier = 1409...1471)

Identifier Rx-SDO2 = 1600 + Node-ID (Node-ID = 0 ... 63, Identifier = 1600...1663)  
Identifier Tx-SDO2 = 1472 + Node-ID (Node-ID = 0 ... 63, Identifier = 1472...1535)

This corresponds to the factory settings of the frequency inverters for the SDO's. The node ID = 0 for SDO2 is the system bus master.

**Attention!** The SDO2 must be deactivated in a CANopen system in order not to generate any compatibility problems.

If a frequency inverter has been defined as the system bus master, the above settings for the SDO1 must be maintained in all the frequency inverters. In this way, access to the parameterization of the frequency inverters via a field bus connection on the master frequency inverter is possible.

The client SDO1 in the master frequency inverter addresses the server SDO1 of the slaves via the above identifiers.

**Attention!** The identifiers for a visualization tool on the second SDO channel SDO2 cannot be changed.

If a PC or a PLC is used as a master, the identifiers of the **Rx/Tx-SDO1** can be adapted by parameterization on the frequency inverter.

**Attention!** In free assignment of identifiers, there may not be any double occupancy!

The identifier range 129...191 may not be used as the emergency telegrams can be found there.

The setting of the identifiers of the RxSDO1 is done via the parameter *RxSDO1-Identifier* **921**.

Parameter		Setting		
No.	Description	Min.	Max.	Fact. sett.
921	RxSDO1-Identifier	0	2047	0

The setting of the identifiers of the TxSDO1 is done via parameter number **922**.

Parameter		Setting		
No.	Description	Min.	Max.	Fact. sett.
922	TxSDO1-Identifier	0	2047	0

The setting "0" results in identifier assignment according to the Predefined Connection Set.

The second SDO channel can be deactivated via the *SDO2 Set Active* **923**.

Operation mode	Function
0 - SDO2 deactivated	Communication channel deactivated
1 - SDO2 activated	Communication channel activated for the visualization tool

**The identifier assignment for the second SDO channel is always to following specification:**

Identifier Rx-SDO2 = 1600 + Node-ID

Identifier Tx-SDO2 = 1472 + Node-ID

**Note:** In this way, constant identifiers for communication are available for the visualization tool.

## 4.10 Communication channels, SDO1/SDO2

### 4.10.1 SDO telegrams (SDO1/SDO2)

The service used for the exchange of parameter data is **SDO Segment Protocol Expedited**. The data (of type uint, int, long) are exchanged in a telegram.

Access to the parameters in the frequency inverters with a statement of parameter number and data set is displayed via the addressing defined for object access pursuant to the specifications of CANopen via Index/Sub-Index.

Index = parameter number / Sub index = data set.

The length of data to be transmitted is 2 bytes for uint/int and 4 bytes for long. As standardization and simplification, always 4 bytes are transmitted.

The data are on bytes 4...7 of the SDO telegram.

- uint/int variables are transmitted in bytes 4 and 5 with bytes 6 und 7 = 0.
- long variables are transmitted in bytes 4...7.

#### Writing parameters:

Client → Server      SDO Download (expedited)

0	1	2	3	4	5	6	7
Ctrl. byte	Parameter number		Data set	Data			
<b>0x22</b>	LSB	MSB	0xnn	LSB			MSB
uint/int				LSB	MSB	0x00	0x00
long				LSB	...	...	MSB

Server → Client      Download Response → Writing process free of errors

0	1	2	3	4	5	6	7
Ctrl. byte	Parameter number		Data set	Data			
<b>0x60</b>	LSB	MSB	0xnn	0			

Server → Client      Abort SDO Transfer → Writing process faulty

0	1	2	3	4	5	6	7
Ctrl. byte	Parameter number		Data set	Data			
<b>0x80</b>	LSB	MSB	0xnn	Code	0	0	0

The error code is stated in byte 4 in a faulty writing process. (see Table, failure codes).

**Attention!** Control byte 0x22 for the identification "SDO Download expedited" does not consider the bits "s" (data size indicated) and "n" (number of bytes not containing data). If set, they are ignored. The user is responsible for the number of bytes matching the type of data.

**Reading parameters:**

Client → Server SDO Upload (expedited)

<b>0</b>	<b>1</b>	<b>2</b>	<b>3</b>	<b>4</b>	<b>5</b>	<b>6</b>	<b>7</b>
Ctrl. byte	Parameter number		Data set	Data			
<b>0x40</b>	LSB	MSB	0xnn	0			

Server → Client Upload Response → Reading process free of errors

<b>0</b>	<b>1</b>	<b>2</b>	<b>3</b>	<b>4</b>	<b>5</b>	<b>6</b>	<b>7</b>
Ctrl. byte	Parameter number		Data set	Data			
<b>0x42</b>	LSB	MSB	0xnn	LSB			MSB
uint/int				LSB	MSB	0x00	0x00
long				LSB	...	...	MSB

Server → Client Abort SDO Transfer → Reading process faulty

<b>0</b>	<b>1</b>	<b>2</b>	<b>3</b>	<b>4</b>	<b>5</b>	<b>6</b>	<b>7</b>
Ctrl. byte	Parameter number		Data set	Data			
<b>0x80</b>	LSB	MSB	0xnn	Code	0	0	0

The error code is stated in byte 4 in a faulty reading process.  
(see Table, failure codes).

failure codes	
Code	Description
1	inadmissible parameter figure
2	inadmissible data set
3	parameter not readable
4	parameter not writable
5	reading error EEPROM
6	writing error EEPROM
7	checksum error EEPROM
8	parameter cannot be written during running drive
9	values of the data sets differ
10	parameter of wrong type
11	unknown parameter
12	BCC error in VECTRON bus protocol
15	unknown error
20	system bus node not available only in access via field bus connection
21	string parameter not admissible only in access via VECTRON bus protocol

Errors marked in the table are generated by the field bus side, not in the Abort SDO Transfer of the system bus.

## 4.10.2 Communication via field bus connection (SDO1)

If a frequency inverter has been defined as the system bus master and equipped with a field bus interface, access to the parameterization of all the nodes on the system bus is possible via this field bus interface and the first SDO channel (SDO1). An extension has been created in the protocol frame of the field buses for this purpose.

**Attention!** The prerequisite for this mechanism is that the identifier setting for the first SDO channel (SDO1) corresponds to the Predefined Connection Set. The parameter addressed must also be existent in the system bus master.

### 4.10.2.1 Profibus-DP

If an object with communication channel (PKW) is used in Profibus-DP, access to all other nodes on the system bus is possible. The structure of the communication channel permits an additional addressing of a system bus node. This is done by the use of an unused byte in the communication channel.

#### Communication channel PKW

0	1	2	3	4	5	6	7
PKE		Index	-	Data			
AK/SPM	Parameter number	Data set	Node-ID system bus				

Byte 3 is used to transmit the node ID of the required node on the system bus. If byte 3 = 0, the master inverter of the system bus is addressed. The display is binary (0...63).

### 4.10.2.2 RS232/RS485 with VECTRON bus protocol

In the VECTRON bus protocol, there is a byte in the telegram header that is always transmitted with 0 as a standard feature.

#### ENQUIRY

0	1	2	3	4	5	6
Address	0	p	n	n	n	ENQ
	Node-ID system bus	Data set	Parameter number			

#### SELECT

0	1	2	3	4			
Address	STX	0	p	n	n	n	...
		Node-ID System bus	Data set	Parameter number			

Byte 1 in the enquiry and byte 2 in the select telegram are not defined and are used to transmit the node ID of the required node on the system bus. If this byte = 0, the master inverter of the system bus is addressed. The display is ASCII corresponding to the conventions for the display of the address in the VECTRON bus protocol.

**Note:** If there is an NAK fault message, the error is to be read out from the system bus master with node ID = 0 via parameter 11!



Display of node ID system bus in the VECTRON bus protocol:

System bus Node-ID					
System bus address	(ASCII-) character	HEX value	System bus address	(ASCII-) character	HEX value
1	A	41	31	—	5F
2	B	42	32	`	60
3	C	43	33	a	61
4	D	44	34	b	62
5	E	45	35	c	63
6	F	46	36	d	64
7	G	47	37	e	65
8	H	48	38	f	66
9	I	49	39	g	67
10	J	4A	40	h	68
11	K	4B	41	i	69
12	L	4C	42	j	6A
13	M	4D	43	k	6B
14	N	4E	44	l	6C
15	O	4F	45	m	6D
16	P	50	46	n	6E
17	Q	51	47	o	6F
18	R	52	48	p	70
19	S	53	49	q	71
20	T	54	50	r	72
21	U	55	51	s	73
22	V	56	52	t	74
23	W	57	53	u	75
24	X	58	54	v	76
25	Y	59	55	w	77
26	Z	5A	56	x	78
27	[	5B	57	y	79
28	\	5C	58	z	7A
29	]	5D	59	{	7B
30	^	5E	60		7C
			61	}	7D
			62	~	7E
			63	□	7F

## 4.11 Process data channels, PDO

### 4.11.1 Identifier assignment process data channel

The process channel for the exchange of process data under CANopen is the PDO channel. Up to three PDO channels with differing properties can be used in one device.

The PDO channels are defined via identifiers according to the Predefined Connection Set to CANopen:

Identifier 1. Rx-PDO = 512 + Node-ID  
 Identifier 1. Tx-PDO = 384 + Node-ID

Identifier 2. Rx-PDO = 768 + Node-ID  
 Identifier 2. Tx-PDO = 640 + Node-ID

Identifier 3. Rx-PDO = 1024 + Node-ID  
 Identifier 3. Tx-PDO = 896 + Node-ID

This corresponds to the factory settings of the frequency inverters for the Rx/Tx-PDO's. This occupancy is aligned to an external master (PLC/PC) serving all the channels.

If the PDO channels are used for a connection of the frequency inverters amongst one another, the identifiers are to be set accordingly by parameterization.

**Attention!** In free assignment of identifiers, there may not be any double occupancy!

The identifier range 129...191 may not be used as the emergency telegrams can be found there.

Setting of the identifiers of the Rx/TxPDO's:

Parameter		Setting		
No.	Description	Min.	Max.	Fact. sett.
924	RxPDO1 Identifier	0	2047	0
925	TxPDO1 Identifier	0	2047	0
926	RxPDO2 Identifier	0	2047	0
927	TxPDO2 Identifier	0	2047	0
928	RxPDO3 Identifier	0	2047	0
929	TxPDO3 Identifier	0	2047	0

The setting "0" results in identifier assignment according to the Predefined Connection Set.

#### 4.11.2 Operation modes process data channel

The transmit/receive behavior can be time controlled or controlled via a SYNC telegram. The behavior can be parameterized for each PDO channel.

**Tx-PDO's** can work time controlled or SYNC controlled. A time controlled TxPDO transmits its data at the interval of time set. A SYNC controlled TxPDO transmits its data after the arrival of a SYNC telegram.

**RxPDO's** in the time controlled setting forward the received data to the application immediately. If an RxPDO has been defined as SYNC controlled, its forwards its received data to the application after the arrival of a SYNC telegram.

##### Settings TxPDO1/2/3

Parameter		Setting		
No.	Description	Min.	Max.	Fact. sett.
931	TxPDO1 Time	1 ms	50000 ms	8 ms
933	TxPDO2 Time	1 ms	50000 ms	8 ms
935	TxPDO3 Time	1 ms	50000 ms	8 ms

The setting of the operation mode is done via the following parameters:

*TxPDO1 Function 930, TxPDO2 Function 932 und TxPDO3 Function 934*

Operation mode	Function
0 - Not Active	No data are sent
1 - Controlled by time	In the cycle of the adjusted time interval the data are sent
2 - Controlled by SYNC	To arrival of a SYNC telegram the data are sent

##### Settings RxPDO1/2/3

The setting of the operation mode is done via the following parameters:

*RxPDO1 Function 936, RxPDO2 Function 937 und RxPDO3 Function 938*

Operation mode	Function
0 - Controlled by time	The received data are passed on immediately
1 - Controlled by SYNC	After arrival of a SYNC telegram the received data are passed on

**Note:** In the "controlled by time" operation mode, there is a polling of the received data with the trigger cycle of  $T_a = 1$  ms.

### 4.11.3 Timeout monitoring process data channel

Each frequency inverter monitors its received data for whether they are updated within a defined time window.

The monitoring is done onto the SYNC telegram and the RxPDO channels.

#### Monitoring SYNC / RxPDO's

Parameter		Setting		
No.	Description	Min.	Max.	Fact. sett.
939	SYNC Timeout	0 ms	60000 ms	0 ms
941	RxPDO1 Timeout	0 ms	60000 ms	0 ms
942	RxPDO2 Timeout	0 ms	60000 ms	0 ms
945	RxPDO3 Timeout	0 ms	60000 ms	0 ms

Setting 0 means no timeout monitoring.

**Attention!** There is only monitoring for the SYNC telegram if at least one RxPDO or one TxPDO channel is defined as SYNC controlled.

If a timeout period is exceeded, the frequency inverter switches to failure mode and reports one of the faults:

- F2200**    **System bus Timeout SYNC**
- F2201**    **System bus Timeout RxPDO1**
- F2202**    **System bus Timeout RxPDO2**
- F2203**    **System bus Timeout RxPDO3**

#### 4.11.4 Communication relationships of the process data channel

Regardless of the process data to be transmitted, the communication relationships of the process data channels must be defined. The connection of PDO channels is done via the assignment of the identifiers. The identifiers of Rx-/Tx-PDO must match in each case.

There are two principal possibilities:

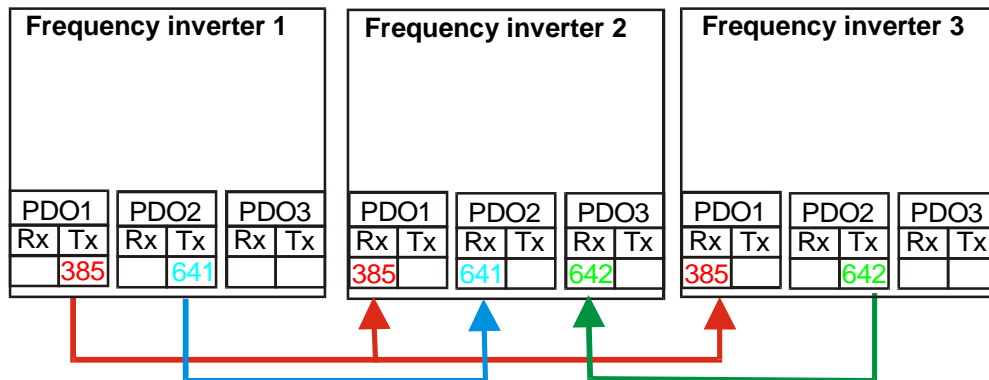
- one Rx-PDO to one Tx-PDO (one to one)
- connect several Rx-PDO's to one TxPDO (one to many)

This process is documented in a tabular form via a **communication relationship list**.

Example:

Frequency inverter 1		Frequency inverter 2		Frequency inverter 3	
PDO	Identifier	PDO	Identifier	PDO	Identifier
<b>TxPDO1</b>	<b>385</b>	TxPDO1		TxPDO1	
RxPDO1		<b>RxPDO1</b>	<b>385</b>	<b>RxPDO1</b>	<b>385</b>
<b>TxPDO2</b>	<b>641</b>	TxPDO2		<b>TxPDO2</b>	<b>642</b>
RxPDO2		<b>RxPDO2</b>	<b>641</b>	RxPDO2	
TxPDO3		TxPDO3		TxPDO3	
RxPDO3		<b>RxPDO3</b>	<b>642</b>	RxPDO3	

**Attention!** All the TxPDO's used must have different identifiers!  
The Identifier must be unique in the system bus network.



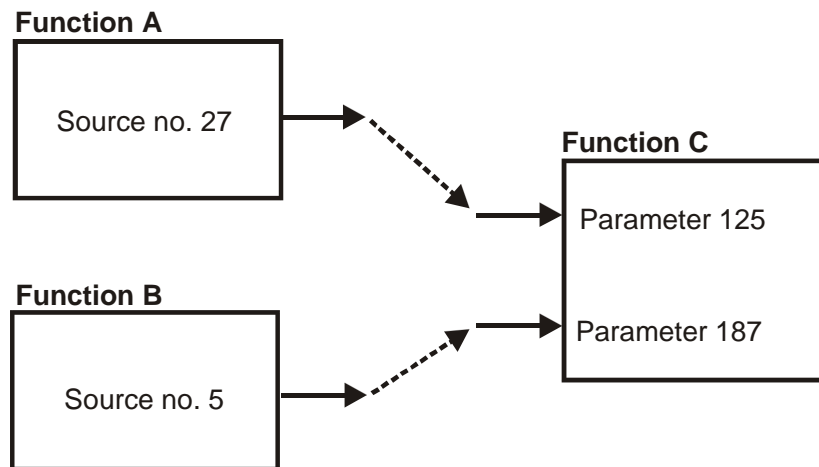
#### 4.11.5 Virtual links

A PDO telegram according to CANopen contains 0 ...8 data bytes. A mapping for any kind of objects can be done in these data bytes.

For the system bus, the PDO telegrams are firmly defined with 8 data bytes. The mapping is not done via mapping parameters as with CANopen, but via the method of sources and links.

Each function provides its output data via a source. These sources are defined via source numbers. The input data of functions are defined via parameters. The link of a data input to a data output is done via the assignment of parameters to source numbers.

##### Example 1:

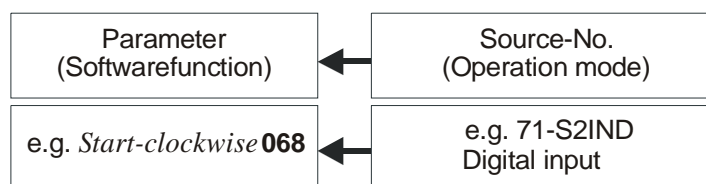


In example 1, the two inputs of function C are connected to the outputs of functions A and B. The parameterization for this connection is thus:

##### Function C

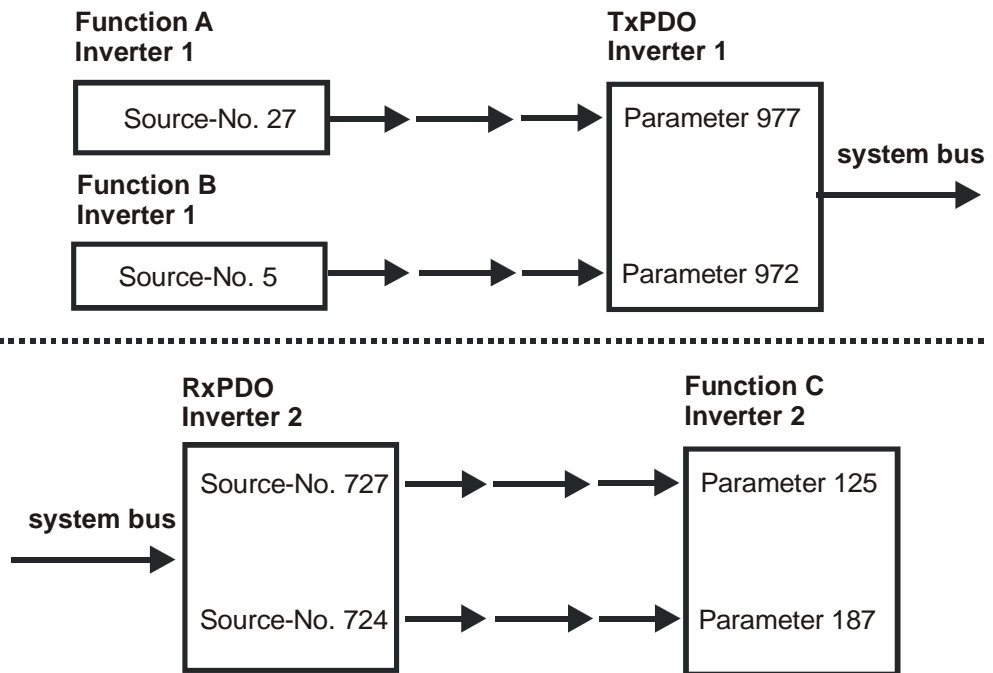
Parameter 125 = Source-No. 27  
Parameter 187 = Source-No. 5

##### Example of a virtual link in VPlus:



The assignment of the operation modes to the software functions available can be adapted to the application in question.

For the system bus, the input data of the TxPDO's are also displayed as input parameters and the output data of the RxPDO's as sources.

**Example 2:**


Example 2 displays the same situation as Example 1. But now, the functions A and B are in frequency inverter 1 and function C in frequency inverter 2. The connection is done via a TxPDO in frequency inverter 1 and a RxPDO in frequency inverter 2. Thus, the parameterization for this connection is:

**Frequency inverter 1**

Parameter 977 = Source-No. 27  
 Parameter 972 = Source-No. 5

**Frequency inverter 2**

Parameter 125 = Source-No. 727  
 Parameter 187 = Source-No. 724

As the links used with the system bus exceed the device limits, they are termed "virtual links".

The virtual links with the possible sources are related to the Rx/TxPDO channels. For this purpose, the eight bytes of the Rx-/TxPDO's are defined structured as inputs and sources. This exists for each of the three PDO channels.

**Each transmit PDO and receive PDO can be occupied as follows:**

**4 Boolean variables**

**or**

**4 uint/int variables**

**or**

**2 long variables**

**or**

**a mixture paying attention to the eight bytes available**

**Assignment data type / number of bytes:**

Assignment	
Data type	Length
Boolean	2 Bytes
uint/int	2 Bytes
long	4 Bytes



#### 4.11.5.1 Input parameters of the TxPDO's for data to be transmitted

The listed parameters can be used to stipulate the data that are to be transported there for each position in the TxPDO telegrams. The setting is done in such a way that a source number is entered for the required data in the parameters.

TxPDO1 Byte	P. No. Boolean input	TxPDO1 Byte	P. No. uint/int input	TxPDO1 Byte	P. No. long input
0	<b>946</b>	0	<b>950</b>	0	<b>954</b> Long1
1	Boolean1	1	Word1	1	
2	<b>947</b>	2	<b>951</b>	2	
3	Boolean2	3	Word2	3	<b>955</b> Long2
4	<b>948</b>	4	<b>952</b>	4	
5	Boolean3	5	Word3	5	
6	<b>949</b>	6	<b>953</b>	6	
7	Boolean4	7	Word4	7	

TxPDO2 Byte	P. No. Boolean input	TxPDO2 Byte	P. No. uint/int input	TxPDO2 Byte	P. No. long input
0	<b>956</b>	0	<b>960</b>	0	<b>964</b> Long1
1	Boolean1	1	Word1	1	
2	<b>957</b>	2	<b>961</b>	2	
3	Boolean2	3	Word2	3	<b>965</b> Long2
4	<b>958</b>	4	<b>962</b>	4	
5	Boolean3	5	Word3	5	
6	<b>959</b>	6	<b>963</b>	6	
7	Boolean4	7	Word4	7	

TxPDO3 Byte	P. No. Boolean input	TxPDO3 Byte	P. No. uint/int input	TxPDO3 Byte	P. No. long input
0	<b>966</b>	0	<b>972</b>	0	<b>976</b> Long1
1	Boolean1	1	Word1	1	
2	<b>967</b>	2	<b>973</b>	2	
3	Boolean2	3	Word2	3	<b>977</b> Long2
4	<b>968</b>	4	<b>974</b>	4	
5	Boolean3	5	Word3	5	
6	<b>969</b>	6	<b>975</b>	6	
7	Boolean4	7	Word4	7	

**Note:** Depending on the selected data information the uint/int inputs are mapped to percentage values.

With this method, there are up to three possibilities for a meaning of the contents of the individual bytes. Each byte may only be used for one possibility.

To ensure this, the processing of the input links is derived from the setting. If an input link has been set to the fixed value of zero, it is **not** processed.

**The settings for the fixed value zero are:**

Source = 7 (FALSE) for Boolean variables  
 Source = 9 (0) for uint, int, long variables

This is the factory setting.

#### Examples Boolean source

Boolean source	
Source	Data
6	TRUE
7	FALSE
70	Contact input 1
71	Contact input 2
72	Contact input 3
161	Running message
163	Nominal figure reached
164	Set frequency reached (P. 510)

#### Examples uint/int source

unit/int source	
Source	Data
9	0
63	Reference percentage 1
64	Reference percentage 2
52	Percentage MFI1
133	Output percentage ramp
137	Output reference percentage channel
138	Output actual percentage channel
740	Control word
741	State word

#### Examples long source

long source	
Source	Data
9	0
0	Output frequency ramp
1	Fixed frequency 1
5	Reference line value
62	Output frequency reference value channel
50	Reference frequency MFI1

#### 4.11.5.2 Source numbers of the RxPDO's for received data

Equivalent to the input links of the TxPDO's, the received data of the RxPDO's are mapped to sources or source numbers. The sources existing in this way can be used in the frequency inverter via the local input links for the data targets.

RxPDO1 Byte	Source No. Boolean value	RxPDO1 Byte	Source No. uint/int value	RxPDO1 Byte	Source No. long- Value
0	700	0	704	0	708 Long1
1	Boolean1	1	Word1	1	
2	701	2	705	2	
3	Boolean2	3	Word2	3	709 Long2
4	702	4	706	4	
5	Boolean3	5	Word3	5	
6	703	6	707	6	
7	Boolean4	7	Word4	7	

RxPDO2 Byte	Source No. Boolean value	RxPDO2 Byte	Source No. uint/int value	RxPDO2 Byte	Source No. long value
0	710	0	714	0	718 Long1
1	Boolean1	1	Word1	1	
2	711	2	715	2	
3	Boolean2	3	Word2	3	719 Long2
4	712	4	716	4	
5	Boolean3	5	Word3	5	
6	713	6	717	6	
7	Boolean4	7	Word4	7	

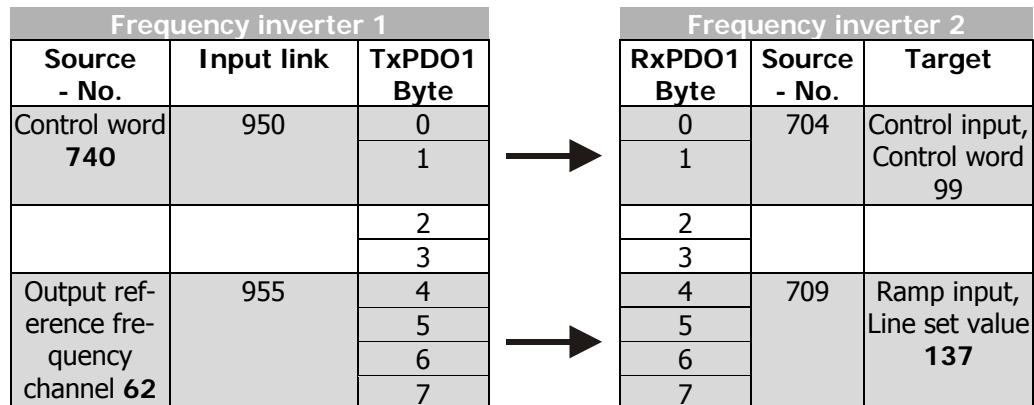
RxPDO3 Byte	Source No. Boolean value	RxPDO3 Byte	Source No. uint/int value	RxPDO3 Byte	Source No. long value
0	720	0	724	0	728 Long1
1	Boolean1	1	Word1	1	
2	721	2	725	2	
3	Boolean2	3	Word2	3	729 Long2
4	722	4	726	4	
5	Boolean3	5	Word3	5	
6	723	6	727	6	
7	Boolean4	7	Word4	7	

With this method, there are up to three possibilities for a meaning of the contents of the individual bytes. Each byte may only be used for one possibility.

**Note:** Depending on the selected data information the uint/int inputs are mapped to percentage values.

### 4.11.5.3 Examples of virtual links

#### Example 1:



Parameter 950 = Source-No. 740  
 Parameter 955 = Source-No. 62

Parameter 99 = Source-No. 704  
 Parameter 137 = Source-No. 709

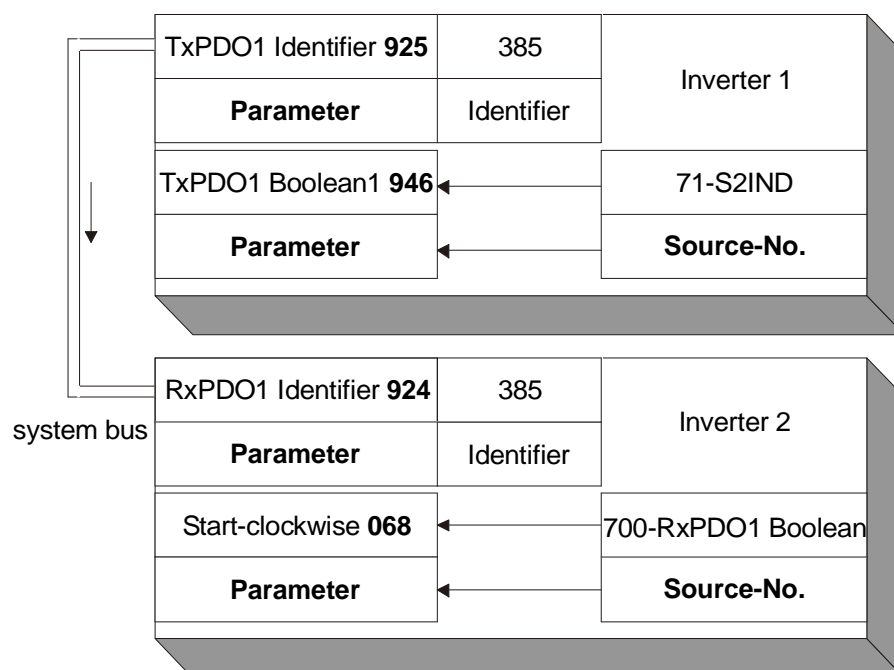
The control word of frequency inverter 1 is linked with the control word of frequency inverter 2. In this way, both frequency inverters can be operated synchronously via the remote control. The output of the reference value channel of frequency inverter 1 is laid onto the output of the ramp of frequency inverter 2. In this way, both frequency inverters have a joint source of reference values and are given reference values in the internal notation.

As an extension, a number of frequency inverters can also exist on the receiving side (Rx), which are supplied simultaneously with data parallel.

The input links not used in the TxPDO1 of frequency inverter 1 are set to ZERO and is thus not be served.

#### Example 2:

Example of a virtual link with transmission via the system bus:



## 4.12 Control parameters

For the monitoring of the system bus and the display of the internal states, two control parameters are provided. There is a report of the system bus state and a report of the CAN state via two actual value parameters.

The parameter *Node-State* **978** provides information about the Pre-Operational, Operational, Stopped state. A PDO transfer is only possible in the Operational state. The state is controlled by the system bus master (PLC / PC / frequency inverter) via NMT telegrams.

The parameter *CAN-State* **979** provides information about the state of the physical layer. If there are transmission errors, the state changes from OKAY to WARNING until the cancellation of the communication with BUS-OFF. After BUS-OFF, the CAN controller is automatically re-initialized and the system bus started again.

**Note:** If the BUS-OFF state occurs, the frequency inverter enters fault state with "F2210 BUS-OFF".

After Bus-OFF, the system bus in the frequency inverter is completely reinitialized. There is a new boot-up message from the node and an emergency telegram with the Bus-OFF message is transmitted. The change of state of the node to Operational is done by the Start-Remote-Node telegram cyclically sent by the system bus master.

Actual values of the system bus		
No.	Description	Display
978	Node-State	1 - Pre-Operational 2 - Operational 3 - Stopped
979	CAN-State	1 - OKAY 2 - WARNING 3 - BUS-OFF

### 4.13 Handling of the parameters of the system bus

As soon as the system bus expansion module EM-SYS exists in a frequency inverter, the actual value parameters for system state and bus state are activated and can be monitored in the actual value menu **VAL** of the control unit KP500 or with the VPlus PC program in the menu **Actual values\System bus**.

**Note:** The actual value parameters are on control level 3 and are thus available for the user at any time.

All the setting parameters for the configuration of the system bus are not directly accessible for the user. For defined customer applications, pre-defined XPI files can be generated by BONFIGLIOLI VECTRON for the VPlus PC program, with which the necessary parameters are visible for the user. The application-relevant variables are then available in these XPI files.

**Note:** XPI files can be read in addition to the loaded parameter information of the frequency inverter into the VPlus PC program.  
In the menu of the software under the point Edit you find the command "Read in XPI file".

The method of working via an XPI file has its reasoning in the fact that deep interventions in the system are possible via the system bus and can lead to serious problems in the application with an untrained user. Via the XPI files, a user is given a selection list pre-defined by BONFIGLIOLI VECTRON.

**Attention!** The configuration of the necessary parameters for the system bus is accessible by a XPI file with the help of the VPlus PC program.  
The control unit KP500 does not support this functionality.  
If the expansion module system bus EM-SYS is installed additionally to a communication module for the field bus connection (CM-232, CM-485 or CM-PDP) in the frequency inverter, the parameterization can be made with the interface adapter KP232.

Experienced users have complete access to all the existing sources and possible input links with the XPI file of the active functions. The selection depends on the selected configuration and control procedure.

The display of the parameters when using the XPI file is according to the following structure:

<b>System bus</b>	
<b>Basic Settings</b>	900Node-ID 903Baud-Rate
<b>Master Functions</b>	904Boot-Up Delay 919SYNC-Time
<b>SYNC-Identifier</b>	918SYNC-Identifier
<b>SDO1-Identifier</b>	921RxSDO1-Identifier 922TxSDO1-Identifier
<b>SDO2 Set Active</b>	923SDO2 Set Active
<b>PDO-Identifier</b>	924RxPDO1-Identifier 925TxPDO1-Identifier 926RxPDO2-Identifier 927TxPDO2-Identifier 928RxPDO3-Identifier 929TxPDO3-Identifier
<b>TxPDO-Function</b>	930TxPDO1 Function 931TxPDO1 Time 932TxPDO2 Function 933TxPDO2 Time 934TxPDO3 Function 935TxPDO3 Time
<b>RxPDO-Function</b>	936RxPDO1 Function 937RxPDO2 Function 938RxPDO3 Function
<b>Timeout</b>	939SYNC Timeout 941RxPDO1 Timeout 942RxPDO2 Timeout 945RxPDO3 Timeout
<b>TxPDO1 Objects</b>	946TxPDO1 Boolean1 947TxPDO1 Boolean2 948TxPDO1 Boolean3 949TxPDO1 Boolean4 950TxPDO1 Word1 951TxPDO1 Word2 952TxPDO1 Word3 953TxPDO1 Word4 954TxPDO1 Long1 955TxPDO1 Long2
<b>TxPDO2 Objects</b>	956TxPDO2 Boolean1 957TxPDO2 Boolean2 958TxPDO2 Boolean3 959TxPDO2 Boolean4 960TxPDO2 Word1 961TxPDO2 Word2 962TxPDO2 Word3 963TxPDO2 Word4 964TxPDO2 Long1 965TxPDO2 Long2
<b>TxPDO3 Objects</b>	966TxPDO3 Boolean1 967TxPDO3 Boolean2 968TxPDO3 Boolean3 969TxPDO3 Boolean4 972TxPDO3 Word1 973TxPDO3 Word2 974TxPDO3 Word3 975TxPDO3 Word4 976TxPDO3 Long1 977TxPDO3 Long2
<b>Actual values</b>	
<b>System bus</b>	978Node-State 979CAN-State

## 4.14 Utilities

For the planning of the system bus according to the drive tasks in question, there are utilities in the form of tables.

**The planning of the system bus is done in three steps:**

1. Definition of the communication relationships
2. Production of the virtual links
3. Capacity planning of the system bus

The priority assignment of the identifiers is relevant for the definition of the communication relationships. Data that are to be transmitted with a higher priority must be given low identifiers. This results in the message with the higher priority being transmitted first with a simultaneous access of two nodes to the bus.

**Note:** The recommended identifier range for the communication relationships via the PDO channels is 385 ...1407.

The identifiers below 385 are used for the NMT telegrams (boot-up sequence, SYNC telegram) and emergency message.

The identifiers above 1407 are used for the SDO channel for parameterization.



#### 4.14.1 Definition of the communication relationships

The communication relationships are planned and documented with the help of the table. The table is available as a Microsoft Word document "kbl.doc" on the BONFIGLIOLI VECTRON product CD or upon request.

Inverter: _____	Inverter: _____	Inverter: _____	Inverter: _____	Inverter: _____
Node-ID: _____	Node-ID: _____	Node-ID: _____	Node-ID: _____	Node-ID: _____
PDO	PDO	PDO	PDO	PDO
Identifier	Identifier	Identifier	Identifier	Identifier
TxPDO1	TxPDO1	TxPDO1	TxPDO1	TxPDO1
RxPDO1	RxPDO1	RxPDO1	RxPDO1	RxPDO1
TxPDO2	TxPDO2	TxPDO2	TxPDO2	TxPDO2
RxPDO2	RxPDO2	RxPDO2	RxPDO2	RxPDO2
TxPDO3	TxPDO3	TxPDO3	TxPDO3	TxPDO3
RxPDO3	RxPDO3	RxPDO3	RxPDO3	RxPDO3

#### 4.14.2 Creating virtual links

The virtual links are planned and documented with the help of the table. The table is available as a Microsoft Word document "vvk.doc" on the BONFIGLIOLI VECTRON product CD or upon request.

Inverter: _____	Inverter: _____	Identifier: _____ (Tx/RxPDO)	<table border="1"> <tr> <th>Source-No.</th> <th colspan="3">Input Link/Parameter-No.</th> </tr> <tr> <td></td> <th>Boolean</th> <th>uint/int</th> <th>long</th> </tr> <tr> <td></td> <td></td> <td></td> <td></td> </tr> <tr> <td></td> <td></td> <td></td> <td></td> </tr> <tr> <td></td> <td></td> <td></td> <td></td> </tr> </table>			Source-No.	Input Link/Parameter-No.				Boolean	uint/int	long												
Source-No.	Input Link/Parameter-No.																								
	Boolean	uint/int	long																						
Node-ID: _____	Node-ID: _____																								
RxPDO-No.: _____	RxPDO-No.: _____																								



### 4.14.3 Capacity planning of the system bus

Each PDO telegram contains 8 Bytes of usable data. According to the worst case, this results in a maximum telegram length of 140 bits. The maximum telegram run time of the PDO's is thus stipulated via the set baud rate.

Capacity planning	
Baud rate / kBaud	Telegram run time / $\mu$ s
1000	140
500	280
250	560
125	1120
100	1400
50	2800

As a function of the set baud rate and the transmission interval of the TxPDO's selected, the following bus loads results:

Capacity of the system bus										
Baud rate / kBaud	Bus load as a function of the transmission for one TxPDO in %									
	1ms	2ms	3ms	4ms	5ms	6ms	7ms	8ms	9ms	10ms
<b>1.000</b>	14	7	4.7	3.5	2.8	2.3	2	1.8	1.6	1.4
<b>500</b>	28	14	9.3	7	5.6	4.7	4	3.5	3.1	2.8
<b>250</b>	56	28	18.7	14	11.2	9.3	8	7	6.2	5.6
<b>125</b>	112	56	37.3	28	22.4	18.7	16	14	12.4	11.2
<b>100</b>	140	70	46.7	35	28	23.3	20	17.5	15.6	14
<b>50</b>	280	140	93.3	70	56	46.7	40	35	31.1	28

**Attention!** A bus load >100% means that a telegram cannot be dispatched completely between two transmission times.

**Such a setting is not permitted!**

This calculation must be done for each TxPDO. The sum of all the TxPDO's decides on the entire bus load. The bus load must be designed in such a way that any telegram repetitions for transmission errors are possible without exceeding the bus capacity.

**Note:** To facilitate capacity planning, a Microsoft Excel file with the name "Load\_Systembus.xls" is available.

The capacity planning are planned and documented with the help of the table. The work sheet is available as a Microsoft Excel document "Load\_Systembus.xls" on the BONFIGLIOLI VECTRON product CD or by request.

<b>System bus load</b>			
<b>Baud rate [kBaud]:</b> 50, 100, 125, 250, 500, 1000			<b>1000</b>
Frequency inverter	TxPDO Number	Ta [ms]	Workload [%]
1	1	0	0
	2	0	0
	3	0	0
2	1	0	0
	2	0	0
	3	0	0
3	1	0	0
	2	0	0
	3	0	0
4	1	0	0
	2	0	0
	3	0	0
5	1	0	0
	2	0	0
	3	0	0
6	1	0	0
	2	0	0
	3	0	0
7	1	0	0
	2	0	0
	3	0	0
8	1	1	14
	2	1	14
	3	1	14
9	1	1	14
	2	1	14
	3	0	0
10	1	0	0
	2	0	0
	3	0	0
<b>Total workload [%]</b>			<b>70</b>

In the table, the set baud rate is entered from the parameter *Baud-Rate 903* in kBaud. For each frequency inverter, the set time for the transmission interval (e. g. *TxPDO1 Time 931*) in ms is entered for the TxPDO being used at the time. In the column **Load** the bus load caused by the individual TxPDO appears, under **Total Load** the entire bus load.

For the bus load (Total load) the following limits have been defined:

≤ 80 %    → OKAY  
 80 ... 90 % → CRITICAL  
 > 90 %    → NOT POSSIBLE

## 5 Control inputs and outputs

### 5.1 Analog input EM-S1INA

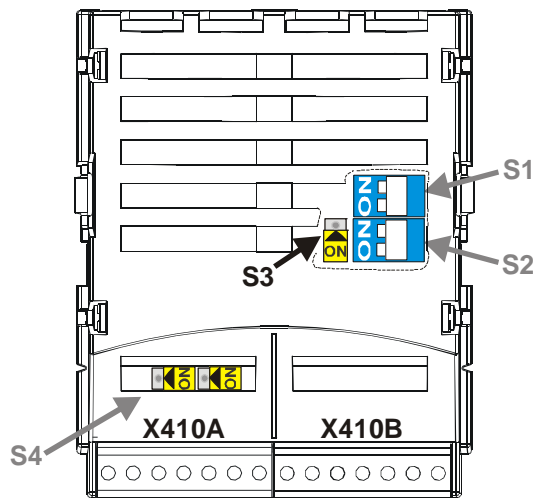
#### 5.1.1 General

The analog input of the EM-UNI-01 expansion module can optionally be configured as a voltage or a current input. Parameterization of the input signal is done by the definition of a linear characteristic and assignment as a

- reference value source  
(can be selected via the parameter *Reference frequency source* **475**),
- reference percentage source  
(can be selected via the parameter *Reference percentage source* **476**),
- actual percentage source  
(can be selected via the parameter *Actual percentage source* **478**, in configuration **x11**) or
- limit value sources  
(can be selected via the parameter *Limit Source* **734...737**).

#### 5.1.2 Configuration voltage/current input

The analog input of the EM-UNI-01 expansion module has been configured in the factory setting for a voltage signal of  $\pm 10$  V. Switch **S3** enables a switch-over of the operation mode for an analog current signal of  $\pm 20$  mA.



Operation mode – switch S3	Function
OFF - Voltage input	OFF (to lower position) – analog input EM-S1INA is configured for a voltage signal.
ON - Current input	ON (to the top position) – analog input EM-S1INA is configured for a current signal.

**Note:** With the two switches **S1** and **S2**, the bus connection of the system bus interface is configured (see chapter "System bus interface"). The switches **S4** activate the termination resistor of  $150 \Omega$  for the speed sensor input according to specification RS422-A/RS-485. (see chapter "Speed Sensor Input EM-ENC")

### 5.1.3 Characteristic

The mapping of the analog input signals onto a frequency or percentage reference value is possible for various demands. The parameterization is to be done via two points of the linear characteristic of the reference channel.

The characteristic point 1, with the coordinates X1 and Y1, and the characteristic point 2, with the coordinates X2 and Y2, are to be set in the four data sets.

The characteristic points X1 and X2 are stated as percentages, as the analog input can be switched as a current or voltage input via switch S3.

Parameter		Setting		
No.	Description	Min.	Max.	Fact. sett.
564	Characteristic point X1	-100.00 %	100.00 %	-98.00 %
565	Characteristic point Y1	-100.00 %	100.00 %	-100.00 %
566	Characteristic point X2	-100.00 %	100.00 %	98.00 %
567	Characteristic point Y2	-100.00 %	100.00 %	100.00 %

The coordinates of the characteristic points are related as a percentage to the analog signal, with 10 V or 20 mA, and the parameter *Maximum Frequency* **419** or parameter *Maximum reference percentage* **519**. The change of direction of rotation can be done via the digital inputs and/or by selecting the characteristic points.

The definition of the analog input characteristic can be calculated via the two-point form of the straight line equation. The speed Y of the drive mechanism is controlled according to the analog control signal X.

$$Y = \frac{Y2 - Y1}{X2 - X1} \cdot (X - X1) + Y1$$

**Attention!** Monitoring of the analog input signal via the parameter *Error/Warning Behavior* **563** demands a check of the characteristic parameters. A reasonable use is only possible if the *Characteristic point X1* **564** is in the positive range.

### 5.1.4 Operation modes

The operation modes of the analog input characteristic enable application-related scaling as a supplement to the characteristic points stated. One of the four linear types of characteristic is selected for adaptation of the signal for the analog input signal via the parameter *Operation mode* **562**.

If the characteristic points are not suited for the type of characteristic selected, the characteristic points are corrected internally.

Operation mode	Function
1 - bipolar	The analog input signal is mapped onto the reference figure according to the characteristic points (X1/Y1) and (X2/Y2).
11 - unipolar	With a negative parameter value of the characteristic points X1 or X2, they are mapped to the reference value zero.
21 - unipolar 2...10 V / 4...20 mA	If the characteristic points X1 or X2 have been set with a negative parameter figure or smaller than 0%, the input characteristic is mapped to the reference value 20%.
101 - Bipolar, absolute value	Negative parameter values of the characteristic points Y1 or Y2 are mapped as a positive reference value in the characteristic.

Further information on the operation modes stated in the table can be found in the following chapter "Examples".

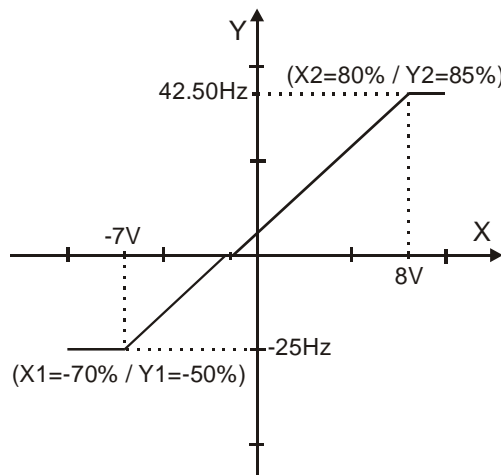
### 5.1.4.1 Examples

The analog input signal is mapped onto a reference value as a function of the characteristic. The following examples show the operation modes for an analog voltage signal. The parameter *Minimum Frequency* **418** is set to the value 0.00 Hz. The characteristic point 100% for the Y axis corresponds to the parameter *Maximum Frequency* **419** of 50.00 Hz in the examples.

**Attention!** The various operation modes change the input characteristic as a function of the parameterized characteristic points. In the following examples, the areas of coordinate system from which a characteristic point is displaced are marked.

#### Operation mode "1 – bipolar"

In operation mode "1 – bipolar", the characteristic of the analog input can be freely set by stating two characteristic points.



#### Characteristic point 1:

$$X1 = -70.00\% \cdot 10 \text{ V} = -7.00 \text{ V}$$

$$Y1 = -50.00\% \cdot 50.00 \text{ Hz} = -25.00 \text{ Hz}$$

#### Characteristic point 2:

$$X2 = 80.00\% \cdot 10 \text{ V} = 8.00 \text{ V}$$

$$Y2 = 85.00\% \cdot 50.00 \text{ Hz} = 42.50 \text{ Hz}$$

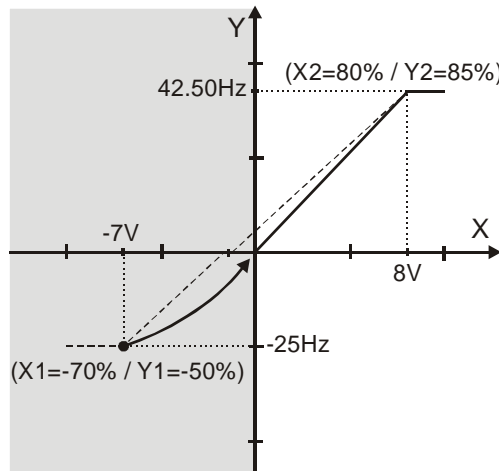
#### Tolerance band:

$$\Delta X = 2.00\% \cdot 10 \text{ V} = 0.20 \text{ V}$$

The change of direction of rotation is done in the example at an analog input signal of -1.44 V, with a tolerance band of  $\pm 0.20 \text{ V}$ .

### Operation mode "11 – unipolar"

In operation mode "11 – unipolar", the characteristic points are displaced to the origin of the characteristics with a negative value for the X axis.



**Characteristic point 1:**

$$X1 = -70.00\% \cdot 10 \text{ V} = -7.00 \text{ V}$$

$$Y1 = -50.00\% \cdot 50.00 \text{ Hz} = -25.00 \text{ Hz}$$

**Characteristic point 2:**

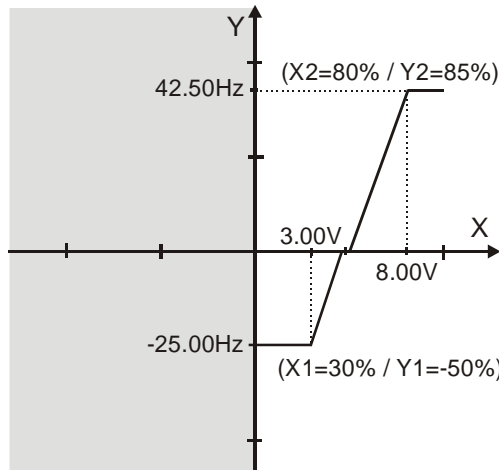
$$X2 = 80.00\% \cdot 10 \text{ V} = 8.00 \text{ V}$$

$$Y2 = 85.00\% \cdot 50.00 \text{ Hz} = 42.50 \text{ Hz}$$

**Tolerance band:**

$$\Delta X = 2.00\% \cdot 10 \text{ V} = 0.20 \text{ V}$$

The characteristic point 1 has been displaced to the origin. The parameter *Tolerance band 560* is not used in this example, as no change of sign of the reference frequency value takes place.



**Characteristic point 1:**

$$X1 = 30.00\% \cdot 10 \text{ V} = 3.00 \text{ V}$$

$$Y1 = -50.00\% \cdot 50.00 \text{ Hz} = -25.00 \text{ Hz}$$

**Characteristic point 2:**

$$X2 = 80.00\% \cdot 10 \text{ V} = 8.00 \text{ V}$$

$$Y2 = 85.00\% \cdot 50.00 \text{ Hz} = 42.50 \text{ Hz}$$

**Tolerance band:**

$$\Delta X = 2.00\% \cdot 10 \text{ V} = 0.20 \text{ V}$$

The change of direction of rotation is done in the example at an analog input signal of 4.85 V, with a tolerance band of  $\pm 0.20 \text{ V}$ .

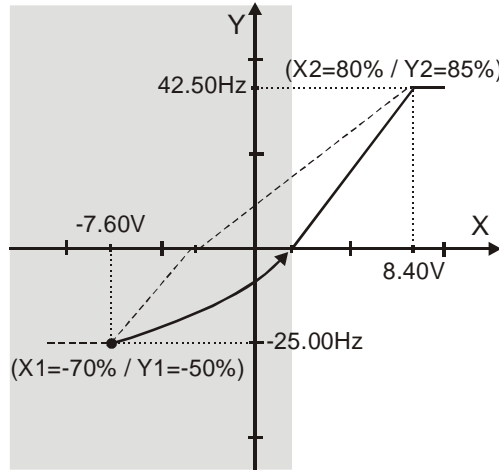


**Operation mode "21 – unipolar 2...10 V / 4...20 mA"**

This operation mode limits the input characteristic to the range between 20% and 100% of the analog signal. If the value for a characteristic point of the X axis is outside 0%, it is mapped to the characteristic point (2 V / 0 Hz).

The characteristic point on the X axis is calculated according to the following formula:

$$\text{characteristic point X} = \text{parameter value X} \cdot (100.00\% - 20.00\%) + 20.00\%$$


**Characteristic point 1:**

$$X1 = [-70.00\% \cdot (100.00\% - 20.00\%) + 20.00\%] \cdot 10 \text{ V} = -7.60 \text{ V}$$

$$Y1 = -50.00\% \cdot 50.00 \text{ Hz} = -25.00 \text{ Hz}$$

**Characteristic point 2:**

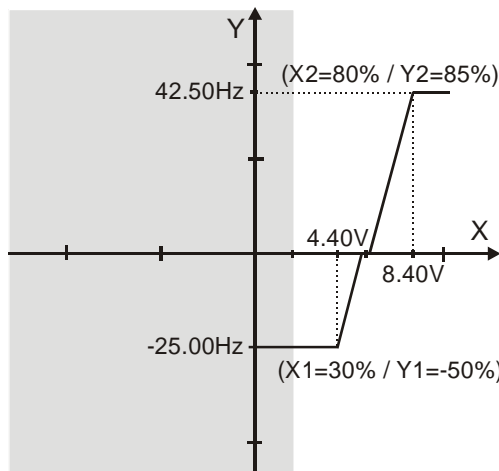
$$X2 = [80.00\% \cdot (100.00\% - 20.00\%) + 20.00\%] \cdot 10 \text{ V} = 8.40 \text{ V}$$

$$Y2 = 85.00\% \cdot 50.00 \text{ Hz} = 42.50 \text{ Hz}$$

**Tolerance band:**

$$\Delta X = [2.00\% \cdot (100.00\% - 20.00\%) \cdot 10 \text{ V}] = 0.16 \text{ V}$$

The characteristic point 1 has been displaced to the point (2.00V / 0.00 Hz). The parameter *Tolerance band 560* is not used in this example, as no change of sign of the reference frequency value takes place.


**Characteristic point 1:**

$$X1 = [30.00\% \cdot (100.00\% - 20.00\%) + 20.00\%] \cdot 10 \text{ V} = 4.40 \text{ V}$$

$$Y1 = -50.00\% \cdot 50.00 \text{ Hz} = -25.00 \text{ Hz}$$

**Characteristic point 2:**

$$X2 = [80.00\% \cdot (100.00\% - 20.00\%) + 20.00\%] \cdot 10 \text{ V} = 8.40 \text{ V}$$

$$Y2 = 85.00\% \cdot 50.00 \text{ Hz} = 42.50 \text{ Hz}$$

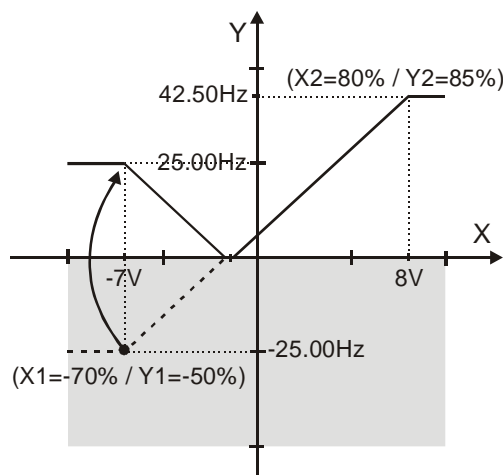
**Tolerance band:**

$$\Delta X = [2.00\% \cdot (100.00\% - 20.00\%) \cdot 10 \text{ V}] = 0.16 \text{ V}$$

The change of direction of rotation is done in the example at an analog input signal of 5.88 V, with a tolerance band of  $\pm 0.16 \text{ V}$ .

### Operation mode "101 – bipolar, absolute value"

The operation mode "101 – bipolar, absolute value" maps the bipolar analog signal onto an unipolar input characteristic. The formation of the absolute value takes the characteristic into account comparable to the "bipolar" operation mode, but the characteristic points are reflected on the X axis with a negative value for the Y axis.



#### Characteristic point 1:

$$X1 = -70.00\% \cdot 10 \text{ V} = -7.00 \text{ V}$$

$$Y1 = -50.00\% \cdot 50.00 \text{ Hz} = -25.00 \text{ Hz}$$

#### Characteristic point 2:

$$X2 = 80.00\% \cdot 10 \text{ V} = 8.00 \text{ V}$$

$$Y2 = 85.00\% \cdot 50.00 \text{ Hz} = 42.50 \text{ Hz}$$

#### Tolerance band:

$$\Delta X = 2.00\% \cdot 10 \text{ V} = 0.20 \text{ V}$$

In this example, the reference value is again increased from an analog input signal of -1.44 V with a tolerance band of  $\pm 0.20 \text{ V}$ . The theoretical change of sign of the reference value is used and leads to the tolerance band stated.

There is no change of the direction of rotation.

## 5.1.5 Scaling

The analog input signal is mapped to the freely configurable characteristic. The maximum admissible setting range of the drive mechanism is to be set according to the configuration selected via the frequency limits or the percentage value limits. In the parameterization of a bipolar characteristic, the minimum and maximum limit for both directions of rotation are taken over. The percentage values of the characteristic points are relative to the maximum limits selected.

Parameter		Setting		
No.	Description	Min.	Max.	Fact. sett.
418	Minimum Frequency	0.00 Hz	999.99 Hz	3.50 Hz
419	Maximum Frequency	0.00 Hz	999.99 Hz	50.00 Hz

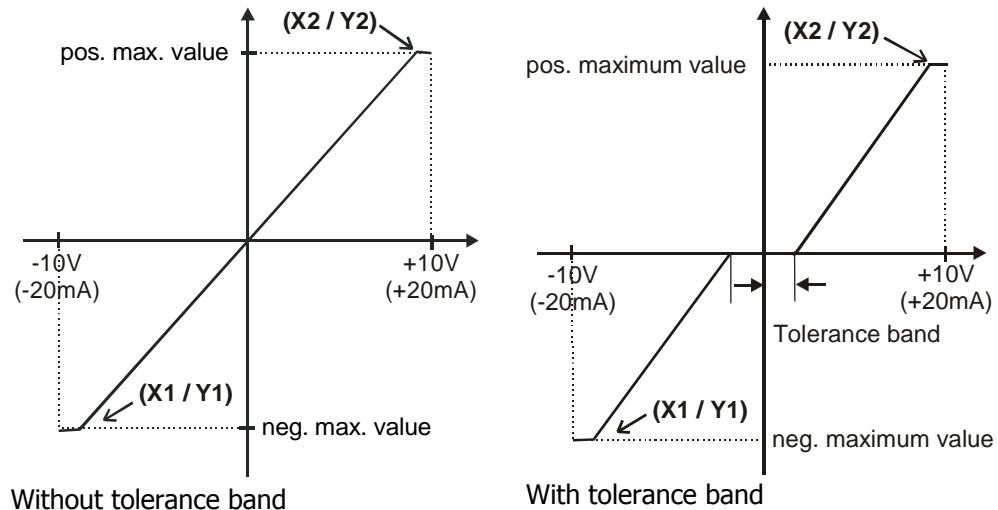
The controls use the maximum value of the output frequency, which is calculated from the *maximum frequency* **419** and the compensated slip of the drive mechanism. The frequency limits define the speed range of the drive mechanism and the reference percentage values supplement the scaling of the input characteristic according to the configured functions.

Parameter		Setting		
No.	Description	Min.	Max.	Fact. sett.
518	Minimum reference percentage	0.00 %	300.00 %	0.00 %
519	Maximum reference percentage	0.00 %	300.00 %	100.00 %

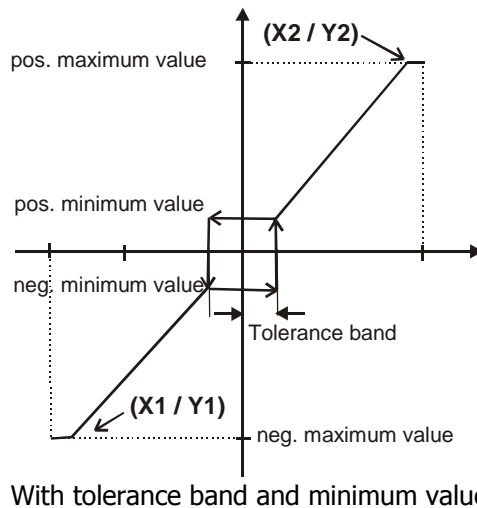
### 5.1.6 Tolerance band and hysteresis

The analog input characteristic with change of sign of the reference value can be adapted by the parameter *Tolerance band 560* of the application. The tolerance band to be defined extends the zero crossing of the speed relative to the analog control signal. The percentage parameter value is relative to the maximum current or voltage signal.

Parameter		Setting		
No.	Description	Min.	Max.	Fact. sett.
560	Tolerance band	0.00 %	25.00 %	2.00 %



The *Minimum Frequency 418* or the *Minimum reference percentage 518* set in the factory extends the parameterized tolerance band to the hysteresis.



For example, the output variable resulting from the positive input signals is kept at the positive minimum value until the input signal is below the value for the tolerance band in a negative direction. After that proceed on the set characteristic.

### 5.1.7 Error and warning behavior

The monitoring of the analog input signal necessary according to the application is to be configured via the parameter *Error/Warning behavior 563*.

Operation mode	Function
0 - Off	The input signal is not monitored.
1 - Warning < 1 V / 2 mA	If the input signal is less than 1 V or 2 mA, there is a warning message.
2 - Shutdown < 1 V / 2 mA	If the input signal is less than 1 V or 2 mA, there is a warning message, the drive mechanism is decelerated according to stopping behavior 1.
3 - Fault switch-off < 1 V / 2 mA	If the input signal is less than 1 V or 2 mA, there is a warning and fault message and the drive mechanism stops freely.

The monitoring of the analog input signal is active, independent of the release of the frequency inverter according to the operation mode selected.

In operation mode **2**, the drive mechanism is decelerated independent of the stopping behavior set (Parameter *Operation mode 630*) according to stopping behavior 1 (shutdown and switch-off). If the set holding time has expired, there is a fault message. A repeat start of the drive mechanism is possible by switching the start signal on and off if the fault has been cleared.

Operation mode **3** defines the free stoppage of the drive mechanism, independent of the stopping behavior selected, which is stipulated with the parameter *Stop function 630*.

**Attention!** Monitoring of the analog input signal via the parameter *Error/Warning Behavior 563* demands a check of the characteristic parameters.

### 5.1.8 Adjustment

As a result of component tolerances, it can be necessary to adjust the analog input. Parameter *Adjustment 568* is used for this purpose.

Operation mode	Function
0 - no adjustment	Normal operation
1 - Adjustment 0 V / 0 mA	Adjustment of the measurement with an analog signal of 0 V or 0 mA.
2 - Adjustment 10 V / 20 mA	Adjustment of the measurement with an analog signal of 10 V or 20 mA.

#### Example of the adjustment of the analog input with a voltage signal:

**Note:** The measurements for the adjustment are to be done with a suitable measuring instrument and the correct polarity. If not, faulty measurements can result. In case of the use of an external voltage supply keep care on the correct calibration of the voltage values and accordingly current values for the adjustments as these values are stored as 0 V/0 mA and 10V/20 mA.

- Apply 0 V to the analog input; e.g. with a bridge from the terminal of the analog input X410B.4 to terminal X210B.7 (earth/GND) of the frequency inverter.
- Select operation mode "1 - Adjustment 0 V / 0 mA".
- Apply 10 V to the analog input; e.g. with a link from the terminal of the analog input to terminal X210B.5 (reference output 10 V) of the frequency inverter.
- Select operation mode "2 - Adjustment 10 V / 20 mA".

The adjustment of the analog input is finalized.

### 5.1.9 Filter time constant

The time constant of the filter for the reference analog value can be set via the parameter *Filter time constant* **561**.

The time constant states the time for which the input signal is averaged by means of a low pass, e.g. in order to eliminate fault effects.

The setting range is a range of values between 0 ms and 5000 ms in 15 steps.

Operation mode	Function
0 - Time constant 0 ms	Filter deactivated – analog reference value is forwarded unfiltered
2 - Time constant 2 ms	Filter activated – averaging of the input signal via the set value of the filter time constants
4 - Time constant 4 ms	
8 - Time constant 8 ms	
16 - Time constant 16 ms	
32 - Time constant 32 ms	
64 - Time constant 64 ms	
128 - Time constant 128 ms	
256 - Time constant 256 ms	
512 - Time constant 512 ms	
1000 - Time constant 1000 ms	
2000 - Time constant 2000 ms	
3000 - Time constant 3000 ms	
4000 - Time constant 4000 ms	
5000 - Time constant 5000 ms	

## 5.2 Analog output EM- S1OUTA

### 5.2.1 General

The analog output of the EM-UNI-01 expansion module is a current output with a range of 0...20 mA. Parameterization of the output signals is done by the selection of the operation mode and a linear characteristic, stating the offset and the amplification.

### 5.2.2 Operation modes

The operation mode of the analog output is selected via the parameter *Operation mode* **590**.

Additional to the operation modes listed, operation modes 1 through 54 which are stated in the operating instructions of the frequency inverter in chapter "Analog output MFO1A" also apply.

Operation mode	Function
0 - 0 mA	Analog output switched off; 0 mA fixed current for adjustment
41 - EM-S1INA, absolute value	Absolute signal value at analog input EM-S1INA; 0 mA...20 mA
100 - 20 mA	20 mA fixed current for adjustment
201 to 254	Operation modes 1...54; Act. absolute value 4 mA...20 mA (wire fracture monitoring)

### 5.2.3 Adjustment

As a result of component tolerances, it may be necessary to adjust the analog output. Parameter *Adjustment* **599** is used for this purpose.

Parameter		Setting		
No.	Description	Min.	Max.	Fact. sett.
599	Adjustment	-10.00 mA	30.00 mA	0.00 mA

#### Example of the adjustment of the analog output:

**Note:** The measurements for the adjustment are to be done with a suitable measuring instrument and the correct polarity.  
The order shown in the example is always to be complied with during the adjustment.  
If not, faulty measurements and settings can result.

- Select operation mode "0 – 0 mA" on the parameter *Operation mode* **590**.
- Enter the current measured on the output in the parameter *Adjustment* **599**.
- Select operation mode "100 -20 mA" on the parameter *Operation mode* **590**.
- Enter the current measured on the output in the parameter *Adjustment* **599**.
- Select operation mode "0 – 0 mA" on the parameter *Operation mode* **590**. In case the current measured at the output deviates from 0 mA significantly, repeat the adjustment.

**Note:** The greatest precision to be achieved is approx. +/-40 µA.

- Select the required operation mode of the analog output on parameter *Operation mode* **590**.

## 5.2.4 Zero adjustment and amplification

After the adjustment, the current of the output signal at 0% and 100% of the reference signals can be set with the parameters *Offset 585* (zero adjustment) and *Amplification 586*.

The zero adjustment with the parameter *Offset 585* is done as a percentage of the final value of the analog output (20 mA).

Via the parameter *Amplification 586* the amplification can be set as a percentage of the final value of the analog output (20 mA).

In the factory setting, the zero point has been set at 0% Offset, i.e. minimum value of the reference signal equal to 0 mA output signal. The factory setting amplification equal to 100% means that the output signal is 20 mA when the reference value is reached.

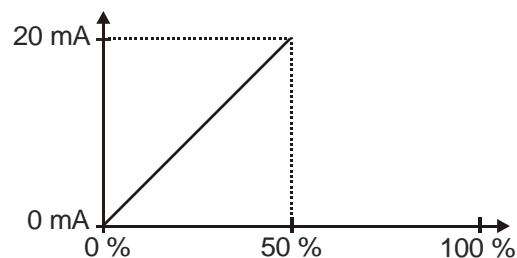
Parameter		Setting		
No.	Description	Min.	Max.	Fact. sett.
585	Offset	-100.00 %	100.00 %	0.00 %
586	Amplification	5.0 %	1000.0 %	100.0 %

### 5.2.4.1 Examples

The actual value parameter is mapped to the analog output signal as a function of the selected parameters *Offset 585* and *Amplification 586*. The following examples show the application-specific adaptation for an analog current signal.

#### Example 1:

Parameter		Setting
No.	Description	Example
585	Offset	0.00 %
586	Amplification	200.0 %

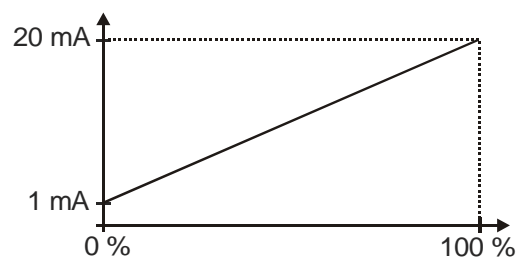


The setting of the parameter *Offset 585* to 0.00% and the parameter *Amplification 586* to 200.0% means that the output signal:

- is 0 mA at 0% of the reference signal
- is 20 mA at 50% of the reference signal

#### Example 2:

Parameter		Setting
No.	Description	Example
585	Offset	5.00 %
586	Amplification	100.0 %



The setting of the parameter *Offset 585* to 5.00% and the parameter *Amplification 586* to 100.0% means that the output signal:

- is 1mA (5% of 20 mA) at 0% of the reference signal
- is 20 mA at 100% of the reference signal



### 5.3 Speed sensor input EM-ENC

The 4 speed sensor inputs of the EM-UNI-01 expansion module can be set via the parameter *Operation mode Speed sensor 2* **493** and selection of the corresponding operation mode for the evaluation of a two-channel speed sensor (incremental speed sensor).

With the help of parameter *Operation mode Speed sensor 2* **493**, the following operation modes are available:

Operation mode 493	Function
0 - Off	Speed measurement not active
4 - Quadruple evaluation	Two-channel speed sensor with recognition of rotation direction via track signals A and B; four signal edges are evaluated per division mark.
104 - Quadruple evaluation inverted	As operation mode 4; the actual speed value is inverted. (Alternative to exchanging the track signals).

Unlike the standard sockets available according to specification RS-422A/RS-485, the interface is suitable for a 5 V push-pull signal.

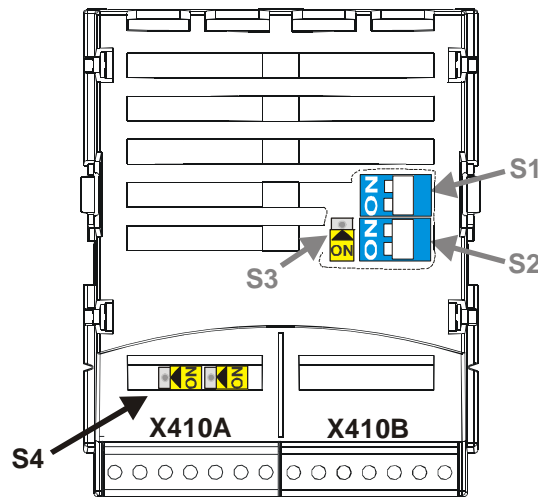
For parameter *Analog Operation* **553**, the additional operation mode 4 – “Abs. Speed Sensor 2” can be selected, which can output the absolute value of the speed sensor signal 2 in the range from 0.00 Hz to *maximum frequency* **419** via the multifunctional output MFO1.

### 5.3.1 Termination resistor

The termination resistor of 150 Ω for the speed sensor of the EM-UNI-01 speed sensor is deactivated by default.



**Caution!** The termination resistor may only be activated for a 5 V push-pull signal according to specification RS-422A / RS-485. For activating the termination resistor, **both** slide switches **S4** must be switched to position "ON". Switching of the two slide switches to different positions may destroy components. If a unipolar speed sensor is used, e.g. with a 24V signal, no termination resistor is required.



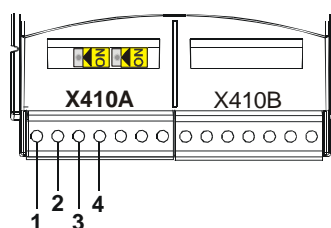
Operation mode of switches S4	Function
OFF - no termination resistor	OFF (to the right)
ON - Termination resistor	ON (to the left)

**Note:** With the two switches **S1** and **S2**, the bus connection of the system bus interface is configured (see chapter "System bus interface").

Switch **S3** enables switching the analog input to voltage signal or current signal (see chapter "Analog input EM-S1INA").

#### Assignment of the inputs:

Control terminal X410A	
Terminal	Input
(1): X410A.1	Speed sensor input EM-ENC: track A+
(2): X410A.2	Speed sensor input EM-ENC: track A-
(3): X410A.3	Speed sensor input EM-ENC: track B+
(4): X410A.4	Speed sensor input EM-ENC: track B-



### 5.3.2 Division marks

The number of increments of the connected speed sensor can be parameterized via the parameter *Division marks speed sensor 2* **494**. The number of division marks of the speed sensor is to be selected according to the speed range of the application. The maximum number of division marks  $S_{max}$  is defined by the limit frequency of  $f_{max} = 300$  kHz of the speed sensor inputs EM-ENC (track A) and EM-ENC (track B).

$$S_{max} = 300000 \text{ Hz} \cdot \frac{60 \text{ s/min}}{n_{max}} \quad n_{max} = \text{Max. speed of the motor in RPM}$$

To ensure a good true running of the drive mechanism, a sensor signal must be evaluated at least every 2 ms (signal frequency  $f = 500$  Hz). The minimum number of division marks  $S_{min}$  of the incremental speed sensor for a required minimum speed  $n_{min}$  can be calculated from this requirement. The evaluation of four signal edges per mark is firmly defined in the function of speed sensor 2.

$$S_{min} = 500 \text{ Hz} \cdot \frac{60 \text{ s/min}}{A \cdot n_{min}} \quad \begin{array}{l} n_{min} = \text{Min. speed of the motor in RPM} \\ A = 4 \text{ (quadruple evaluation)} \end{array}$$

Parameter		Setting		
No.	Description	Min.	Max.	Fact. Sett.
494	Division marks speed sensor 2	1	8192	1024

### 5.3.3 Operation mode Level

Via the parameter *Operation mode Level* **495**, the following operation modes can be selected:

Operation mode Level 495	Function
0 - push-pull	Push-pull signals (5 V) are evaluated (according to specification RS-422A/RS-485).
2 - unipolar	Unipolar signals (10 V...24 V) at A+ and B+ are evaluated.

### 5.3.4 Actual speed source

If both speed sensor 1 (basic device) and also speed sensor 2 of the EM-UNI-01 expansion module are switched active, the actual value signal used as a source for the speed controller must be parameterized.

In the basic setting, speed sensor 1 is used as the actual value source.

Switching over is done via parameter *Actual Speed Source* **766**.

Operation mode	Function
1 - Speed sensor 1	The actual speed source is speed sensor 1 of the basic device (factory setting).
2 - Speed sensor 2	The actual speed source is speed sensor 2 of the EM-UNI-01 expansion module.

## 5.4 Actual value comparison

The expansion module extends also the number of operation modes available for parameters *Operation mode comparator 1* **540** and *Operation mode comparator 2* **543**. These operation modes permit a comparison of the speed frequency of speed sensor 2 with a maximum speed frequency and a comparison of the analog input EM-S1INA with a maximum analog input value.

Operation mode	Function
8 - Speed frequency actual value 2	Speed frequency speed sensor 2 <b>220</b> > maximum speed frequency (calculated from <i>Maximum speed frequency</i> <b>419</b> and <i>No. of pole pairs</i> <b>373</b> )
16 - Analog input EM-S1INA, absolute value	<i>Analog input EM-S1INA</i> <b>253</b> > Analog input 100%
108 und 116	Operation modes with sign (+/-)

## 5.5 Frequency and percentage reference channel

The varied functions for the specification of the reference values are connected in the various configurations by the frequency or percentage reference channel. The *Reference frequency source* **475**, and the *Reference percentage source* **476** determine the additive connection of the available reference sources as a function of the installed hardware.

Operation mode	Function
2 - Analog value EM-S1INA, absolute value	Reference source is the analog input EM-S1INA
4 - MFI1A + EM-S1INA, absolute value	Reference sources are the multifunctional input MFI1A and the analog input EM-S1INA
12 - EM-S1INA + FF ( or FP), absolute value	Reference sources are the analog input EM-S1INA and fixed frequency FF (or fixed percentage FP)
14 - MFI1A + EM-S1INA + FF, absolute value	Reference sources are the multifunctional input MFI1A, analog input EM-S1INA and fixed frequency FF
22 - EM-S1INA + MF, absolute value	Reference sources are the analog input EM-S1INA and the motor potentiometer function MP
24 - MFI1A + EM-S1INA + MP, absolute value	Reference sources are the multifunctional input MFI1A, analog input EM-S1INA and the motor potentiometer function MP
34 - Speed sensor 2 (F2) , absolute value	The frequency signals in <i>Operation mode Speed sensor 2</i> <b>493</b> are evaluated as a reference value.
35 - MFI1A + Speed sensor 2 (F2), absolute value	Reference sources are the multifunctional input MFI1A and the frequency signals in <i>Operation mode Speed sensor 2</i> <b>493</b>
102 to 135	Operation modes with signs (+/-)

Additional to the operation modes listed, those stated in the operating instructions of the frequency inverter in chapter "Frequency reference channel" and in chapter "Percentage reference channel" do also apply.

## 5.6 Actual value display

The actual value of speed sensor 2 can be read via the parameters *Frequency speed sensor 2* **219** and *Speed, speed sensor 2* **220**.

The analog input signal on analog input EM-S1INA can be a voltage or a current signal depending on the setting of switch **S3**. Accordingly, the actual value parameter *Analog input EM-S1INA* **253** is displayed as a percentage value.

The analog output signal on analog output EM-S1OUTA can be displayed via the parameter *Analog output EM-S1OUTA* **267**.

## 5.7 Digital Port EM-S1IOD

The digital port EM-S1IOD of the EM-UNI-01 expansion module can be defined as a digital input or output.

The assignment of the control signals at the digital input to the available software functions can be adapted to the application in question.

Parameterization of this digital output permits a linking to a variety of functions. The selection of functions depends on the parameterized configuration.

The selection of the operation modes for the digital port EM-S1IOD is effected via parameter *Operation Mode* **558**.

Operation mode	Function
0 - input	Port EM-S1IOD can be used as a digital input.
1 - output	Port EM-S1IOD can be used as a digital output.

### 5.7.1 Operation Mode – Digital Input

As a function of the selected *Configuration* **30**, the factory-set assignment and the selection of the operation mode differ. In addition to the digital control input available, further internal logistic signals are also available as sources.

The individual software functions are assigned to the various signal sources via parameterization-capable inputs. This enables a flexible and varied use of the digital control signals.

Operation mode	Function
320 - EM-S1IND	signal at digital port (X410A.7)
520 - EM-S1IND inverted	inverted signal at digital port (X410A.7)

Additional to the operation modes listed, those stated in the operating instructions of the frequency inverter in the chapter "Digital inputs" do also apply.

### 5.7.1.1 Fixed reference values and fixed value switch-over

As a function of the *Reference Frequency Source* **475** selected, fixed frequencies can be used as reference values. The EM-UNI-01 expansion module extends the functionality described in the operating instructions of the frequency inverter (parameter *Fixed frequency change-over 1* **66** and *Fixed frequency change-over 2* **67**) by the parameter *Fixed frequency change-over 3* **131** and the matching parameters *Fixed frequency 5* **485**, *Fixed frequency 6* **486**, *Fixed frequency 7* **487**, *Fixed frequency 8* **488**.

	<i>Fixed frequency change-over 1</i> <b>66</b>	<i>Fixed frequency change-over 2</i> <b>67</b>	<i>Fixed Frequency change-over 3</i> <b>131</b>
<i>Fixed frequency 1</i> <b>480</b>	0	0	0
<i>Fixed frequency 2</i> <b>481</b>	1	0	0
<i>Fixed frequency 3</i> <b>482</b>	1	1	0
<i>Fixed frequency 4</i> <b>483</b>	0	1	0
<i>Fixed frequency 5</i> <b>485</b>	0	1	1
<i>Fixed frequency 6</i> <b>486</b>	1	1	1
<i>Fixed frequency 7</i> <b>487</b>	1	0	1
<i>Fixed frequency 8</i> <b>488</b>	0	0	1

### 5.7.2 Operation Mode - Digital Output

Via parameter *Operation Mode Output* **559**, the operation modes listed in the frequency inverter operating instructions in chapter "Digital Outputs" can be selected.

## 5.8 Digital inputs EMS2IND and EMS3IND

The EM-UNI-01 expansion module has two digital inputs. The assignment of the control signals to the available software functions can be adapted to the application in question. As a function of the selected *Configuration 30*, the factory-set assignment and the selection of the operation mode differ. In addition to the digital control inputs available, further internal logistic signals are also available as sources.

The individual software functions are assigned to the various signal sources via parameterization-capable inputs. This enables a flexible and varied use of the digital control signals.

Operation mode	Function
321 - EM-S2IND	Signal on digital input 2 (X410A.1)
322 - EM-S3IND	Signal on digital input 3 (X410A.3)
521 - EM-S2IND inverted	Inverted signal on digital input 2 (X410A.1)
522 - EM-S3IND inverted	Inverted signal on digital input 3 (X410A.3)

Alongside the operation modes listed, those stated in the operating instructions of the frequency inverter in the chapter "Digital inputs" also apply.



### Caution!

When using sockets X410A.1 and X410A.3 as digital inputs, the sockets X410A.2 and X410A.4 must be unconnected.

### 5.8.1 Fixed reference values and fixed value switch-over

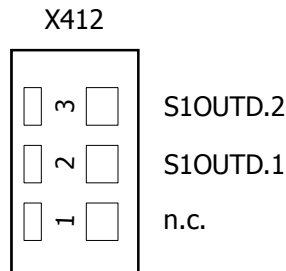
As a function of the *Reference Frequency Source 475* selected, fixed frequencies can be used as reference values. The EM-UNI-01 expansion module extends the functionality described in the operating instructions of the frequency inverter (parameter *Fixed frequency change-over 1 66* and *Fixed frequency change-over 2 67*) by the parameter *Fixed frequency change-over 3 131* and the matching parameters *Fixed frequency 5 485*, *Fixed frequency 6 486*, *Fixed frequency 7 487*, *Fixed frequency 8 488*.

Activation Fixed frequencies			
	<i>Fixed frequency change-over 1 66</i>	<i>Fixed frequency change-over 2 67</i>	<i>Fixed Frequency change-over 3 131</i>
<i>Fixed frequency 1 480</i>	0	0	0
<i>Fixed frequency 2 481</i>	1	0	0
<i>Fixed frequency 3 482</i>	1	1	0
<i>Fixed frequency 4 483</i>	0	1	0
<i>Fixed frequency 5 485</i>	0	1	1
<i>Fixed frequency 6 486</i>	1	1	1
<i>Fixed frequency 7 487</i>	1	0	1
<i>Fixed frequency 8 488</i>	0	0	1

## 5.9 Digital output EM-S1OUTD

### 5.9.1 General

The digital output of the EM-UNI-01 expansion module is a potential-free normally open contact. The parameterization of this digital output allows a lot of combination of functions. The choosable functions depend on the parameterized configuration. The output is applicable for triggering a motor brake.



### 5.9.2 Operation modes

The choice of the digital output operation mode (sockets X412.2 and X412.3) is made by the parameter operation mode *EM-S1OUTD 533*.

The choosable operation modes are listed in frequency inverter operation manual in chapter „Digital outputs“.

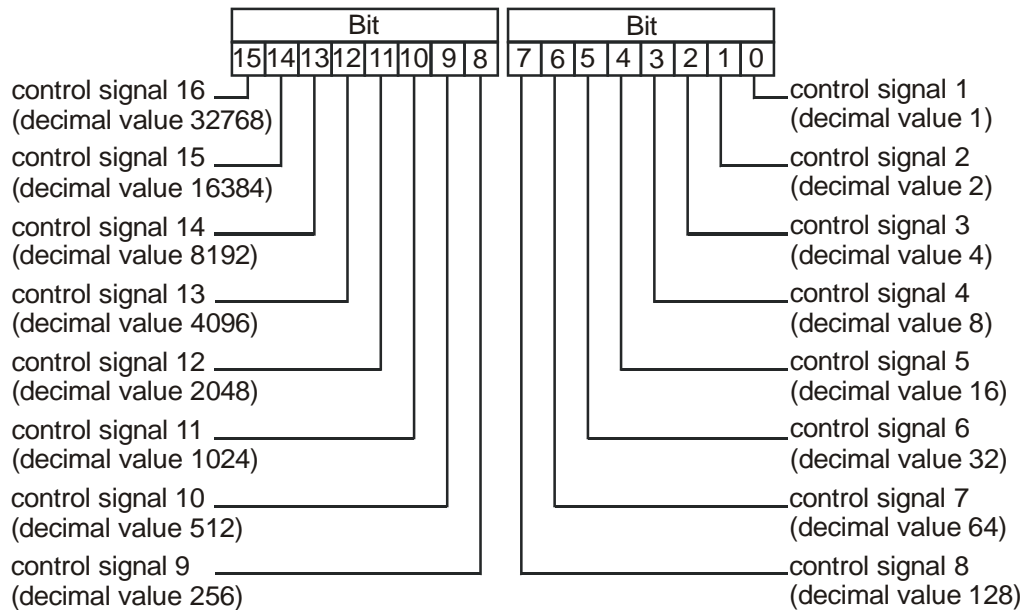


## 5.10 Status of the digital signals

The status of the digital signals can be read in decimal coding via the parameters *Digital inputs 250* and *Digital outputs 254*. The display of the digital input signals enables checking the various control signals and their connections with the software functions in question, in particular in commissioning.

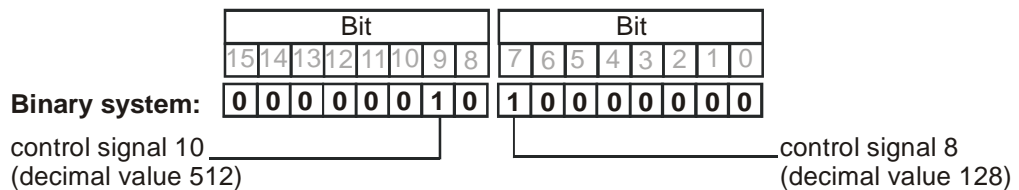
After conversion of the decimal figure into the binary system, bits 7, 8 and 9 display the states of the inputs EM-S1-IND (Digital port), EM-S2IND and EM-S3IND.

### Coding of the status of the digital signals



#### Example:

The actual value parameter *Digital inputs 250* displays the decimal value **640**. After conversion into the binary system, the following combination results:



The following status of the digital input signals of the EM-UNI-01 expansion module has been displayed.

- Digital input EM-S1IND = 1 – control signal 8 (Bit 7), digital port
- Digital input EM-S2IND = 0 – control signal 9 (Bit 8)
- Digital input EM-S3IND = 1 – control signal 10 (Bit 9)

Bit 3 (decimal value 8) displays the state of the output signal at digital port EM-S1IOD (configured as digital output).

- Digital output EM-S1IOD = 1 – control signal 4 (Bit 3)

## 5.11 Motor temperature

Temperature monitoring forms part of the configurable fault and alarm behavior. The connected load can be monitored by connecting a measuring resistor (motor PTC) with temperature characteristics according to DIN 44081 or by means of a bimetal temperature sensor (break contact).

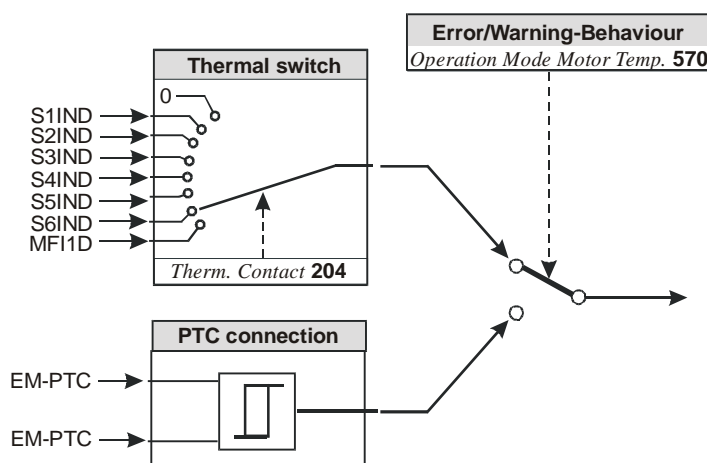
The operation mode of the motor PTC port can be selected via parameter *Operation Mode Motor temp. 570*. The operation modes described in chapter "Motor Temperature" of the frequency inverter operating instructions are complemented by the following operation modes with the EM-UNI-01 expansion module:

Operation mode	Function
11 - EM-MPTC: warning only	The critical operating point is displayed by the control unit and parameter <i>Warnings 269</i> .
12 - EM-MPTC: Error-switch-off	Error-switch-off is displayed by message F0400. Error-switch-off can be acknowledged via the control unit or the digital input.
13 - EM-MPTC: Error-switch-off, 1 min. delay	Error-switch-off according to operation mode 2, delayed by one minute.
14 - EM-MPTC: Error-switch-off, 5 min. delay	Error-switch-off according to operation mode 2, delayed by five minutes.
15 - EM-MPTC: Error-switch-off, 10 min. delay	Error-switch-off according to operation mode 2, delayed by ten minutes.

The function to be adjusted by parameter *Operation Mode Motor Temp. 570* results in signaling the overtemperature by the red LED of the frequency inverter, irrespective of the selected operation modes of the control inputs and outputs.

The operation modes with error-switch-off result in the fault message "FAULT" with fault number "F0400" being displayed on the control unit KP500.

The fault message can be acknowledged via parameter *Program 34* or the logic signal linked with parameter *Error Acknowledgement 103*.



The function selected according to the above table with parameter *Operation mode Motor Temp. 570* can be linked to the digital control outputs and the warning mask. (For detailed information refer to the operating instructions of the frequency inverter).



**Note:** The evaluation of the motor PTC port is independent of the signal at the digital controller input S1IND (controller release).

The motor temperature for a temperature adjustment, as described in chapter "Temperature Adjustment", can be effected via analog input EM-S1INA. The selection is effected via parameter *Operation Mode* **465**.

Operation mode	Function
2 - Temp. meas. at EM-S1INA	Temperature synchronization (0 ... 200 °C => 0...10 V / 0...20 mA), Actual temperature value at analog input of EM-UNI-01 expansion module.

## 6 Parameter list












The parameter list is structured according to the menu branches of the control unit. For better clarity, the parameters are marked with pictograms:


-  The parameter is available in the four data sets
- The parameter value is set by the SETUP routine
-  This parameter cannot be written in the operation of the frequency inverter

### 6.1 Actual value menu (VAL)

Actual values of the machine				
No.	Description	Unit	Display range	Chapter
219	Frequency speed sensor 2	Hz	0.0 ... 999.99	5.6
220	Speed, speed sensor 2	rpm	0 ... 60000	5.6
Actual values of the frequency inverter				
250	Digital inputs	-	0 ... 32767	5.10
253	Analog input EM-S1INA	%	-100 ... +100	5.6
254	Digital outputs	-	0 ... 32767	5.10
267	Analog output EM-S1OUTA	mA	0.0 ... 20.0	5.6
Actual values of the system bus				
978	Node-State	-	1 ... 3	4.12
979	CAN-State	-	1 ... 3	4.12

### 6.2 Parameter menu (PARA)

Digital input				
No.	Description	Unit	Setting range	Chapter
131	Fixed Frequency change-over 3	-	Selection	5.7.1.1
Fixed frequencies				
	485 Fixed frequency 5	Hz	-999.99 ... 999.99	5.7.1.1
	486 Fixed frequency 6	Hz	-999.99 ... 999.99	5.7.1.1
	487 Fixed frequency 7	Hz	-999.99 ... 999.99	5.7.1.1
	488 Fixed frequency 8	Hz	-999.99 ... 999.99	5.7.1.1
Speed sensor 2				
	493 Operation mode speed sensor 2	-	Selection	5.3
	494 Division marks speed sensor 2	-	1 ... 8192	5.3.2
	495 Level	-	Selection	5.3.3
Digital output EM-S1OUTD				
533	Op. Mode EM-S1OUTD	-	Selection	5.9.2
Digital port				
558	Operation mode	-	Selection	5.7
559	Output Operation	-	Selection	5.7.2
Analog input				
	560 Tolerance band	%	0.00 ... 25.00	5.1.6
	561 Filter time constant	-	Selection	5.1.9
	562 Operation mode	-	Selection	5.1.4
	563 Error/warning behavior	-	Selection	5.1.7
	564 Characteristic point X1	%	-100.00 ... 100.00	5.1.3
	565 Characteristic point Y1	%	-100.00 ... 100.00	5.1.3
	566 Characteristic point X2	%	-100.00 ... 100.00	5.1.3
	567 Characteristic point Y2	%	-100.00 ... 100.00	5.1.3
	568 Adjustment	-	Selection	5.1.3

Analog output EM- S1OUTA				
No.	Description	Unit	Setting range	Chapter
585	Offset	%	-100.00 ... 100.00	5.2.4
586	Amplification	%	5.0 ... 1000.0	5.2.4
590	Operation mode	-	Selection	5.2.2
599	Adjustment	mA	-10.00 ... +30.00	5.2.3
Speed controller				
 766	Actual speed source	-	Selection	5.3.4
System bus				
900	Node-ID	-	-1 ... 63	4.5
903	Baud-Rate	-	Selection	4.4
904	Boot-Up Delay	ms	3500 ... 50000	4.8.4
918	SYNC-Identifier	-	0 ... 2047	4.8.2
919	SYNC-Time	ms	0 ... 50000	4.9.2
921	RxSDO1-Identifier	-	0 ... 2047	4.9.4
922	TxSDO1-Identifier	-	0 ... 2047	4.9.4
923	SDO2 Set Active	-	Selection	4.9.4
924	RxPDO1-Identifier	-	0 ... 2047	4.11.1
925	TxPDO1-Identifier	-	0 ... 2047	4.11.1
926	RxPDO2-Identifier	-	0 ... 2047	4.11.1
927	TxPDO2-Identifier	-	0 ... 2047	4.11.1
928	RxPDO3-Identifier	-	0 ... 2047	4.11.1
929	TxPDO3-Identifier	-	0 ... 2047	4.11.1
930	TxPDO1 Function	-	Selection	4.11.2
931	TxPDO1 Time	ms	0 ... 50000	4.11.2
932	TxPDO2 Function	-	Selection	4.11.2
933	TxPDO2 Time	ms	0 ... 50000	4.11.2
934	TxPDO3 Function	-	Selection	4.11.2
935	TxPDO3 Time	ms	0 ... 50000	4.11.2
936	RxPDO1 Function	-	Selection	4.11.2
937	RxPDO2 Function	-	Selection	4.11.2
938	RxPDO3 Function	-	Selection	4.11.2
939	SYNC Timeout	ms	0 ... 60000	4.11.3
941	RxPDO1 Timeout	ms	0 ... 60000	4.11.3
942	RxPDO2 Timeout	ms	0 ... 60000	4.11.3
945	RxPDO3 Timeout	ms	0 ... 60000	4.11.3
946	TxPDO1 Boolean1	-	Selection	4.11.5.1
947	TxPDO1 Boolean2	-	Selection	4.11.5.1
948	TxPDO1 Boolean3	-	Selection	4.11.5.1
949	TxPDO1 Boolean4	-	Selection	4.11.5.1
950	TxPDO1 Word1	-	Selection	4.11.5.1
951	TxPDO1 Word2	-	Selection	4.11.5.1
952	TxPDO1 Word3	-	Selection	4.11.5.1
953	TxPDO1 Word4	-	Selection	4.11.5.1
954	TxPDO1 Long1	-	Selection	4.11.5.1
955	TxPDO1 Long2	-	Selection	4.11.5.1
956	TxPDO2 Boolean1	-	Selection	4.11.5.1
957	TxPDO2 Boolean2	-	Selection	4.11.5.1
958	TxPDO2 Boolean3	-	Selection	4.11.5.1
959	TxPDO2 Boolean4	-	Selection	4.11.5.1
960	TxPDO2 Word1	-	Selection	4.11.5.1
961	TxPDO2 Word2	-	Selection	4.11.5.1

System bus				
No.	Description	Unit	Setting range	Chapter
962	TxPDO2 Word3	-	Selection	4.11.5.1
963	TxPDO2 Word4	-	Selection	4.11.5.1
964	TxPDO2 Long1	-	Selection	4.11.5.1
965	TxPDO2 Long2	-	Selection	4.11.5.1
966	TxPDO3 Boolean1	-	Selection	4.11.5.1
967	TxPDO3 Boolean2	-	Selection	4.11.5.1
968	TxPDO3 Boolean3	-	Selection	4.11.5.1
969	TxPDO3 Boolean4	-	Selection	4.11.5.1
972	TxPDO3 Word1	-	Selection	4.11.5.1
973	TxPDO3 Word2	-	Selection	4.11.5.1
974	TxPDO3 Word3	-	Selection	4.11.5.1
975	TxPDO3 Word4	-	Selection	4.11.5.1
976	TxPDO3 Long1	-	Selection	4.11.5.1
977	TxPDO3 Long2	-	Selection	4.11.5.1
989	Emergency Reaction	-	Selection	4.8.3

## 7 Annex

### 7.1 Error messages

The various control functions and methods and the hardware of the frequency inverter contain functions which continuously monitor the application. As a supplement to the messages documented in these operating instructions, the following failure keys are activated by the EM-UNI-01 expansion module.

Control connections		
F14	02	Reference value signal on analog input EM-S1INA faulty, check signal
	30	Speed sensor signal is faulty, check connections
	31	One track of the speed sensor signal is missing, check connections
	32	Direction of rotation of speed sensor wrong, check connections
	33	Speed sensor signal 2 with wrong division mark, check speed sensor.
	34	Division mark of speed sensor signal 2 too low, check speed sensor.
	35	Division mark of speed sensor signal 2 too high, check speed sensor.

System bus		
F21	nn	Fault report to system bus master in fault in system bus slave nn = Node ID of slave (hex)

System bus		
F22	00	Communication fault, system bus, timeout SYNC telegram
	01	Communication fault, system bus, timeout RxPDO1
	02	Communication fault, system bus, timeout RxPDO2
	03	Communication fault, system bus, timeout RxPDO3
	10	Communication fault, system bus, bus OFF

Additional to the listed fault messages, there are further fault messages for internal purposes and not listed here. If you receive fault messages, which are not listed here, please contact us by phone.



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### AUSTRALIA

BONFIGLIOLI TRANSMISSION (Aust) Pty Ltd.  
101, Plumpton Road, Glendenning NSW 2761, Australia  
Locked Bag 1000 Plumpton NSW 2761  
Tel. (+ 61) 2 8811 8000 - Fax (+ 61) 2 9675 6605  
www.bonfiglioli.com.au - sales@bonfiglioli.com.au

### AUSTRIA **BEST**

MOLL MOTOR GmbH  
Industriestrasse 8 - 2000 Stockerau  
Tel. (+43) 2266 63421+DW - Fax (+43) 6342 180  
www.mollmotor.at - office@mollmotor.at

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Rua Omlio Monteiro Soares, 260 - Vila Fanny - 81030-000  
Tel. (+41) 334 2091 - Fax (+41) 332 8669  
www.atibrasil.com.br - vendas@atibrasil.com.br

### CANADA

BONFIGLIOLI CANADA INC.  
2-7941 Janie Street - Concord, ONTARIO L4K 4L6  
Tel. (+1) 905 7384466 - Fax (+1) 905 7389833  
www.bonfigliolicanada.com - sales@bonfigliolicanada.com

### CHINA

BONFIGLIOLI DRIVES (SHANGHAI) CO. LTD.  
No. 8 Building, 98 Tian Ying Road  
Qingpu District, Shanghai, PRC 201712  
Tel. +86 21 69225500 - Fax +86 21 69225511  
www.bonfiglioli.cn - bds@bonfiglioli.com.cn

### FRANCE

BONFIGLIOLI TRANSMISSIONS S.A.  
14 Rue Eugène Pottier BP 19  
Zone Industrielle de Moimont II - 95670 Marly La Ville  
Tel. (+33) 1 34474510 - Fax (+33) 1 34688800  
www.bonfiglioli.fr - btf@bonfiglioli.fr

### GERMANY

BONFIGLIOLI DEUTSCHLAND GmbH  
Sperberweg 12 - 41468 Neuss  
Tel. (+49) 02131 2988-0 - Fax (+49) 02131 2988-100  
www.bonfiglioli.de - info@bonfiglioli.de

### GREAT BRITAIN

BONFIGLIOLI UK Ltd  
Industrial Equipment - Unit 3 Colemeadow Road  
North Moons Moat - Redditch, Worcestershire B98 9PB  
Tel. (+44) 1527 65022 - Fax (+44) 1527 61995  
www.bonfiglioli-uk.com - uksales@bonfiglioli-uk.com

Mobile Equipment  
5 Grosvenor Grange - Woolston - Warrington, Cheshire WA1 4SF  
Tel. (+44) 1925 852667 - Fax (+44) 1925 852668  
www.bonfiglioli-uk.com - salesmobile@bonfiglioli-uk.com

### GREECE **BEST**

B.E.S.T. HELLAS S.A.  
O.T. 48A T.O. 230 - C.P. 570 22 Industrial Area - Thessaloniki  
Tel. (+30) 2310 796456 - Fax (+30) 2310 795903  
www.bonfiglioli.gr - info@bonfiglioli.gr

### HOLLAND **BEST**

ELSTO AANDRIJFTECHNIEK  
Loostenweg, 7 - 2215 TL Voorhout  
Tel. (+31) 252 219 123 - Fax (+31) 252 231 660  
www.elsto.nl - imfo@elsto.nl

### HUNGARY **BEST**

AGISYS AGITATORS & TRANSMISSIONS Ltd  
2045 Törökbalint, Tó u.2. Hungary  
Tel. +36 23 50 11 50 - Fax +36 23 50 11 59  
www.agisys.hu - info@agisys.hu

### INDIA

BONFIGLIOLI TRANSMISSIONS PVT Ltd.  
PLOT AC7-AC11 Sidco Industrial Estate  
Thirumudivakkam - Chennai 600 044  
Tel. +91(0)44 24781035 / 24781036 / 24781037  
Fax +91(0)44 24780091 / 24781904  
www.bonfiglioli.co.in - bonfig@vsnl.com

### ITALY

BONFIGLIOLI ITALIA S.p.A.  
Via Sandro Pertini lotto 7b - 20080 Carpiano (Milano)  
Tel. (+39) 02 985081 - Fax (+39) 02 985085817  
www.bonfiglioli.it - customerservice.italia@bonfiglioli.it

### NEW ZEALAND **BEST**

SAECO BEARINGS TRANSMISSION  
36 Hastie Avenue, Mangere  
Po Box 22256, Otahuhu - Auckland  
Tel. +64 9 634 7540 - Fax +64 9 634 7552  
mark@saeco.co.nz

### POLAND **BEST**

POLPACK Sp. z o.o. - Ul. Chrobrego 135/137 - 87100 Torun  
Tel. (+48) 56 6559235 - 6559236 - Fax (+48) 56 6559238  
www.polpack.com.pl - polpack@polpack.com.pl

### PORTUGAL **BEST**

BT BONFITEC Equipamentos Industriais, Lda.  
Largo do Colegio de Ermesinde, 70 - Formiga 4445-382 Ermesinde  
Tel. (+351) 229759634/5/6 - Fax (+351) 229752211  
www.bonfitec.pt - bonfitec@bonfitec.pt

### RUSSIA **BEST**

FAM  
57, Maly prospekt, V.O. - 199048, St. Petersburg  
Tel. +7 812 3319333 - Fax +7 812 3271454  
www.fam-drive.ru - info@fam-drive.ru

### SPAIN

TECNOTRANS BONFIGLIOLI S.A.  
Pol. Ind. Zona Franca sector C, calle F, nº6 08040 Barcelona  
Tel. (+34) 93 4478400 - Fax (+34) 93 3360402  
www.tecnotrans.com - tecnotrans@tecnotrans.com

### SOUTH AFRICA

BONFIGLIOLI POWER TRANSMISSION Pty Ltd.  
55 Galaxy Avenue, Linbro Business Park - Sandton  
Tel. (+27) 11 608 2030 OR - Fax (+27) 11 608 2631  
www.bonfiglioli.co.za - bonfigsales@bonfiglioli.co.za

### SWEDEN

BONFIGLIOLI SKANDINAVIEN AB  
Koppargatan 8 - 234 35 Lomma, Sweden  
Tel. (+46) 40418230 - Fax (+46) 40414508  
www.bonfiglioli.se - info@bonfiglioli.se

### THAILAND **BEST**

K.P.T MACHINERY (1993) CO.LTD.  
259/83 Soi Phiboovues, Sukhumvit 71 Rd. Phrakonong-nur,  
Wattana, Bangkok 10110  
Tel. 0066.2.3913030/7111998  
Fax 0066.2.7112852/3811308/3814905  
www.kpt-group.com - sales@kpt-group.com

### USA

BONFIGLIOLI USA INC  
3541 Hargrave Drive Hebron, Kentucky 41048  
Tel.: (+1) 859 334 3333 - Fax: (+1) 859 334 8888  
www.bonfiglioliusa.com  
industrialsales@bonfiglioliusa.com  
mobilesales@bonfiglioliusa.com

### VENEZUELA **BEST**

MAICA SOLUCIONES TECNICAS C.A.  
Calle 3B - Edif. Comindu - Planta Baja - Local B  
La Urbina - Caracas 1070  
Tel. (+58) 212 2413570 / 2425268 / 2418263  
Fax (+58) 212 2424552 - Tlx 24780 Maica V  
maica1@cantv.net

### HEADQUARTERS

BONFIGLIOLI RIDUTTORI S.p.A.  
Via Giovanni XXIII, 7/A  
40012 Lippo di Calderara di Reno  
Bologna (ITALY)  
Tel. (+39) 051 6473111  
Fax (+39) 051 6473126  
www.bonfiglioli.com  
bonfiglioli@bonfiglioli.com

### SPARE PARTS BONFIGLIOLI

B.R.T.  
Via Castagnini, 2-4  
Z.I. Bargellino - 40012  
Calderara di Reno - Bologna (ITALY)  
Tel. (+39) 051 727844  
Fax (+39) 051 727066  
www.brtbonfiglioliricambi.it  
brt@bonfiglioli.com





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