

Control Units

CU240E
CU240S

sinamics
G120

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SINAMICS G120 Control Units CU240E CU240S

Parameter Manual

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This Parameter Manual is valid for the following Control Units and Firmware versions:

Control Unit	As from Firmware version:
CU240E	V3.2
CU240S	V3.2
CU240S DP	V3.2
CU240S DP-F	V3.2
CU240S PN	V3.2
CU240S PN-F	V3.2

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Safety Guidelines

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



Danger

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



Warning

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



Caution

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

Caution

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

Notice

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

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

Qualified Personnel

The device/system may only be set up and used in conjunction with this documentation. Commissioning and operation of a device/system may only be performed by **qualified personnel**. Within the context of the safety notes in this documentation qualified persons are defined as persons who are authorized to commission, ground and label devices, systems and circuits in accordance with established safety practices and standards.

Prescribed Usage

Note the following:



Warning

This device may only be used for the applications described in the catalog or the technical description and only in connection with devices or components from other manufacturers which have been approved or recommended by Siemens.

Correct, reliable operation of the product requires proper transport, storage, positioning and assembly as well as careful operation and maintenance.

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

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Parameters

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1.1 Introduction to Parameters

The layout of the parameter description is as follows.

	BICO (if exist)		
r1515	CO: Additional torque setpoint / Add. trq. setp		
	Access level: 2	P-Group: Closed-loop control	Data type: Floating Point
	Unit: [Nm]		Data set: -

Fig. 1-1 Read-only parameter

	Index	BICO (if exist)		
p0701[0...2]		Function of digital input 0 / Function of DI0		
CU240E		Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S		Quick comm. NO	Active: NO	Data set: CDS
PM240		Can be changed: T		
		Min	Max	Factory setting
		0	99	1
CU/PM variants				

Fig. 1-2 Write parameter

Parameter number

Indicates the relevant parameter number. The numbers used are 4-digit numbers in the range 0000 to 9999. Only for PROFINET there are a few parameters in the range of 61.000. Numbers prefixed with an "r" indicate that the parameter is a "read-only" parameter, which displays a particular value but cannot be changed directly by specifying a different value via this parameter number.

All other parameters are prefixed with a "P". The values of these parameters can be changed directly in the range indicated by the "Min" and "Max" settings in the header. If these values have a physical unit, it is shown in brackets.

[index] indicates that the parameter is an indexed parameter and specifies the range of indices available.

.0...15 indicates that the parameter has several bits, which can be evaluated or connected individually.

CU/PM variants

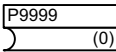
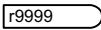
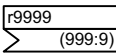
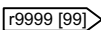
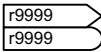
Indicates for which Control Units and/or Power Modules the parameter is valid. If no CUs or PMs are listed the parameter is valid for all variants.

Parameter text (Long name/Short name)

Indicates the name of the relevant parameter.

Certain parameter names include the following abbreviated prefixes: BI, BO, CI, CO and CO/BO followed by a colon.

These abbreviations have the following meanings:

BI	=		Binector input, i.e. parameter selects the source of a binary signal
BO	=		Binector output, i.e. parameter connects as a binary signal
CI	=		Connector input, i.e. parameter selects the source of an analog signal
CO	=		Connector output, i.e. parameter connects as an analog signal
CO/BO	=		Connector/Binector output, i.e. parameter connects as an analog signal and/or as a binary signal

CoBo.pdf

To make use of BICO you will need access to the full parameter list. At this level many new parameter settings are possible, including BICO functionality. BICO functionality is a different, more flexible way of setting and combining input and output functions. It can be used in most cases in conjunction with the simple, access level 2 settings.

The BICO system allows complex functions to be programmed. Boolean and mathematical relationships can be set up between inputs (digital, analog, serial etc.) and outputs (inverter current, frequency, analog output, relays, etc.).

At BI and CI parameters the parameter number is specified under Factory setting with which this parameter is connected. In this case the Min and Max values have dashes.

Access level (refers only to access via Operator Panel (OP))

Indicates the level of user access. There are four access levels: Standard, Extended, Expert and Service. The number of parameters that appear in each functional group depends on the access level set in P0003 (user access level).

P-Group (refers only to access via Operator Panel (OP))

Specifies the functional group to which the parameter belongs.

Note:

Parameter P0004 (parameter filter) acts as a filter and focuses access to parameters according to the functional group selected.

Data type

The data types available are shown in the table below.

Table 1-1 Available data types

Notation	Meaning
Unsigned8 (U8)	8-bit unsigned
Unsigned16 (U16)	16-bit unsigned
Unsigned32 (U32)	32-bit unsigned
Integer16 (I16)	16-bit integer
Integer32 (I32)	32-bit integer
Floating Point (Float)	Floating point

The information of the data types for binector and connector inputs can be composed of two specifications (discreted by a slash):

- First specification
data type of the parameter
- Second specification
data type of the signal source preferably to be connected (binector or connector output)

Quick Comm

Indicates whether or not (Yes or No) a parameter can only be changed during quick commissioning, i.e. when P0010 (parameter groups for commissioning) is set to 1 (quick commissioning).

Active

- YES changes to the parameter values take effective immediately after they have been entered.
- No the "P" button on the Operator Panel must be pressed before the changes take effect.

Data set

Parameters which are dependent on a data set are identified as follows:

- CDS (Command Data Set)
- DDS (Drive Data Set)

They are always indexed with [0...2].

For **CDS** is valid:

[0] = Command Data Set 0

[1] = Command Data Set 1

[2] = Command Data Set 2

For **DDS** is valid:

[0] = Drive Data Set 0

[1] = Drive Data Set 1

[2] = Drive Data Set 2

Can be changed

Inverter state in which the parameter is changeable. Three states are possible:

- Commissioning C
- Run U
- Ready to runt T

This indicates when the parameter can be changed. One, two or all three states may be specified. If all three states are specified, this means that it is possible to change this parameter setting in all three inverter states.

Unit

Indicates the unit of measure applicable to the parameter values.

Min

Indicates the minimum value to which the parameter can be set.

Max

Indicates the maximum value to which the parameter can be set.

Factory setting

Indicates the default value, i.e. the value which applies if the user does not specify a particular value for the parameter.

Description

Explanation of the function of a parameter.

Values

Lists the possible values of a parameter.

Recommendation

Information about recommended settings.

Index

The name and meaning of each individual index is specified for indexed parameters, except indexed parameters which belong to a data set (see Data set).

Bit field

For parameters with bit fields, the following information is provided about each bit:

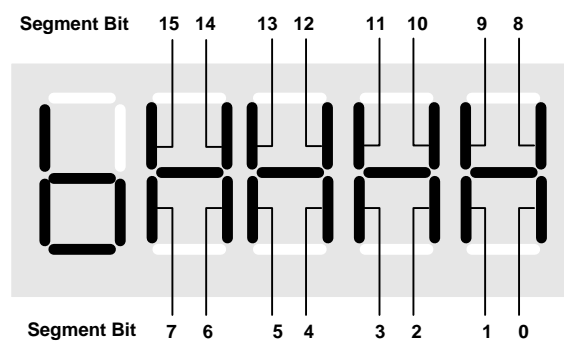
- Bit number and signal name
- Meaning with signal states 0 and 1
- Function diagram (optional). The signal is shown on this function diagram.

Dependency

Conditions which need to be fulfilled in connection with this parameter. Also includes special effects which can occur between this parameter and others.

Seven-segment display

The seven-segment display of the OP is structured as follows:



Visio-7-Segment Display.pdf

Fig. 1-3 Seven-segment display

1.2 List of Parameters

Product: G120, Version: 3202700, Language: eng

r0000	Drive display / Drive display		
	Access level: 1	P-Group: -	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays the user selected output. This value is defined in P0005.		
Note:	Pressing the "Fn" button on OP for 2 seconds allows the user to view the values of DC link voltage, output frequency, output voltage, output current, and chosen r0000 setting (defined in P0005).		

r0002	Drive state / Drive state		
CU240E	Access level: 2	P-Group: Commands	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays actual drive state.		
Value:	0: Commissioning mode (P0010 != 0) 1: Drive ready 2: Drive fault active 3: Drive starting (DC-link precharging) 4: Drive running 5: Stopping (ramping down) 6: Drive inhibited		
Dependency:	State 3 visible only while precharging DC link.		

r0002	Drive state / Drive state		
CU240S	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S DP	Unit: -	Calculated: -	Data set: -
CU240S PN			
Description:	Displays actual drive state.		
Value:	0: Commissioning mode (P0010 != 0) 1: Drive ready 2: Drive fault active 3: Drive starting (DC-link precharging) 4: Drive running 5: Stopping (ramping down) 6: Drive inhibited		
Dependency:	State 3 visible only while precharging DC link. It is only visible when an externally powered control unit is fitted.		

r0002	Drive state / Drive state		
CU240S DP-F	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -
Description:	Displays actual drive state.		
Value:	0: Commissioning mode (P0010 != 0) 1: Drive ready 2: Drive fault active 3: Drive starting (DC-link precharging) 4: Drive running 5: Stopping (ramping down) 6: Drive inhibited 7: Safety active 8: Safety reset/commissioning 9: Safety fault active		
Dependency:	State 3 visible only while precharging DC link. It is only visible when an externally powered control unit is fitted.		

p0003 User access level / User access level			
Access level: 1	P-Group: -	Data type: Unsigned16	
Quick comm. NO	Active: NO	Data set: -	
Can be changed: U, T	Calculated: -		
Min 0	Max 4	Factory setting 1	
Description:	Defines user access level to parameter sets. The default setting (standard) is sufficient for most simple applications.		
Value:	0: User defined parameter list - see P0013 for details on use 1: Standard: Allows access into most frequently used parameters. 2: Extended: Allows extended access e.g. to inverter I/O functions 3: Expert: For expert use only. 4: Service: Only for use by authorized service, password protected		
Note:	Only valid for control units with OP.		
p0004 Parameter filter / Parameter filter			
CU240E	Access level: 1	P-Group: -	Data type: Unsigned16
CU240S	Quick comm. NO	Active: NO	Data set: -
CU240S DP	Can be changed: U, T	Calculated: -	
CU240S PN	Min 0	Max 22	Factory setting 0
Description:	Filters parameters according to functionality to enable a more focussed approach to commissioning.		
Value:	0: All parameters 2: Inverter 3: Motor 4: Speed sensor 5: Technol. application / units 7: Commands, binary I/O 8: AI and AO 10: Setpoint channel / RFG 12: Drive features 13: Motor control 19: Motor identification 20: Communication 21: Warnings / faults / monitoring 22: Technology controller		

p0004	Parameter filter / Parameter filter		
CU240S DP-F	Access level: 1	P-Group: -	Data type: Unsigned16
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	0	22	0
Description:	Filters parameters according to functionality to enable a more focussed approach to commissioning.		
Value:	0: All parameters 2: Inverter 3: Motor 4: Speed sensor 5: Technol. application / units 7: Commands, binary I/O 8: AI and AO 10: Setpoint channel / RFG 11: Safety functions 12: Drive features 13: Motor control 19: Motor identification 20: Communication 21: Warnings / faults / monitoring 22: Technology controller		

p0005[0...2]	Display selection / Display selection		
	Access level: 2	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: C, U, T	Calculated: -	
	Min	Max	Factory setting
	2	4000	21
Description:	Selects display for parameter r0000 on OP (drive display).		
Example:	P0005 = 21: Actual filtered frequency (r0021) P0005 = 25: Actual output voltage (r0025) P0005 = 26: Actual filtered DC link voltage (r0026) P0005 = 27: Actual output current (r0027)		
Notice:	These settings refer to read only parameter numbers ("rxxxx").		

p0006	Display mode / Display mode		
	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: C, U, T	Calculated: -	
	Min	Max	Factory setting
	0	4	2
Description:	Defines mode of display on OP for r0000 (drive display).		
Value:	0: Ready state: setpoint/output frequency. Run: output frequency 1: Ready state: setpoint. Run: output frequency. 2: Ready state: P0005/r0020 value. Run: P0005 value 3: Ready state: r0002/r0020 value. Run: r0002 value 4: In all states just display P0005		
Note:	When inverter is not running, the display alternates between the values for "Not Running" and "Running". Per default, the setpoint and actual frequency values are displayed alternately.		

p0007	Backlight delay time / Backl. delay time		
	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: C, U, T	Calculated: -	
	Min 0	Max 2000	Factory setting 0
Description:	Defines time period after which the backlight of the OP display turns off if no operator keys have been pressed.		
Note:	P0007 = 0: Backlight always on (default state). P0007 = 1 - 2000: Number of seconds after which the backlight will turn off.		
p0010	Commissioning parameter / Commissioning par.		
CU240E	Access level: 1	P-Group: -	Data type: Unsigned16
CU240S	Quick comm. NO	Active: NO	Data set: -
CU240S DP	Can be changed: T	Calculated: -	
CU240S PN	Min 0	Max 95	Factory setting 0
Description:	Filters parameters so that only those related to a particular functional group are selected.		
Value:	0: Ready 1: Quick commissioning 2: Inverter 29: Download 30: Factory setting 95: Safety commissioning (only on safety CU)		
Dependency:	Reset to 0 for inverter to run. P0003 (user access level) also determines access to parameters.		
Note:	<ul style="list-style-type: none"> • P0010 = 1 The inverter can be commissioned very quickly and easily by setting P0010 = 1. After that only the important parameters (e.g.: P0304, P0305, etc.) are visible. The value of these parameters must be entered one after the other. The end of quick commissioning and the start of internal calculation will be done by setting P3900 = 1 - 3. Afterwards parameter P0010 and P3900 will be reset to zero automatically. • P0010 = 2 For service purposes only. • P0010 = 29 To transfer a parameter file via PC tool (e.g.: STARTER) parameter P0010 will be set to 29 by the PC tool. When download has been finished PC tool resets parameter P0010 to zero. • P0010 = 30 When resetting the parameters of inverter P0010 must be set to 30. Resetting of the parameters will be started by setting parameter P0970 = 1. The inverter will automatically reset all its parameters to their default settings. This can prove beneficial if you experience problems during parameter setup and wish to start again. Duration of factory setting will take about 60 s. 		

p0010	Commissioning parameter / Commissioning par.		
CU240S DP-F	Access level: 1	P-Group: -	Data type: Unsigned16
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	0	95	0
Description:	Filters parameters so that only those related to a particular functional group are selected.		
Value:	0: Ready 1: Quick commissioning 2: Inverter 29: Download 30: Factory setting 95: Safety commissioning (only on safety CU)		
Dependency:	Reset to 0 for inverter to run. P0003 (user access level) also determines access to parameters.		
Note:	<ul style="list-style-type: none"> • P0010 = 1 The inverter can be commissioned very quickly and easily by setting P0010 = 1. After that only the important parameters (e.g.: P0304, P0305, etc.) are visible. The value of these parameters must be entered one after the other. The end of quick commissioning and the start of internal calculation will be done by setting P3900 = 1 - 3. Afterwards parameter P0010 and P3900 will be reset to zero automatically. • P0010 = 2 For service purposes only. • P0010 = 29 To transfer a parameter file via PC tool (e.g.: STARTER) parameter P0010 will be set to 29 by the PC tool. When download has been finished PC tool resets parameter P0010 to zero. • P0010 = 30 When resetting the parameters of inverter P0010 must be set to 30. Resetting of the parameters will be started by setting parameter P0970 = 1. The inverter will automatically reset all its parameters to their default settings. This can prove beneficial if you experience problems during parameter setup and wish to start again. Duration of factory setting will take about 60 s. • P0010 = 95 For changing the safety parameters select access level 3 and set the safety password. Only then P0010 can be set to 95. The safety commissioning including safety dynamization will take about 2 s. For finishing the safety commissioning, see P3900. 		
p0011	Lock for user defined parameter / LockUserDefinedPar		
	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: C, U, T	Calculated: -	
	Min	Max	Factory setting
	0	65535	0
Note:	See parameter P0013 (user defined parameter)		
p0012	Key for user defined parameter / Key UserDefinedPar		
	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: C, U, T	Calculated: -	
	Min	Max	Factory setting
	0	65535	0
Note:	See parameter P0013 (user defined parameter).		

p0013[0...19]	User defined parameter / User-defined par		
	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: C, U, T	Calculated: -	
	Min	Max	Factory setting
	0	65535	0
Description:	Defines a limited set of parameters to which the end user will have access.		
	Instructions for use:		
	<ol style="list-style-type: none"> 1. Set P0003 = 3 (expert user). 2. Go to P0013 indices 0 to 16 (user list) 3. Enter into P0013 index 0 to 16 the parameters required to be visible in the user-defined list. The following values are fixed and cannot be changed: <ul style="list-style-type: none"> - P0013 index 17 = 3 (user access level) - P0013 index 18 = 10 (commissioning parameter filter) - P0013 index 19 = 12 (key for user defined parameter) 4. Set P0003 = 0 to activate the user defined parameter. 		
Index:	<p>[0] = 1st user parameter [1] = 2nd user parameter [2] = 3rd user parameter [3] = 4th user parameter [4] = 5th user parameter [5] = 6th user parameter [6] = 7th user parameter [7] = 8th user parameter [8] = 9th user parameter [9] = 10th user parameter [10] = 11th user parameter [11] = 12th user parameter [12] = 13th user parameter [13] = 14th user parameter [14] = 15th user parameter [15] = 16th user parameter [16] = 17th user parameter [17] = 18th user parameter [18] = 19th user parameter [19] = 20th user parameter</p>		
Dependency:	<p>First, set P0011 ("lock") to a different value then P0012 ("key") to prevent changes to user-defined parameter. Then, set P0003 to 0 to activate the user-defined list. When locked and the user-defined parameter is activated, the only way to exit the user-defined parameter (and view other parameters) is to set P0012 ("key") to the value in P0011 ("lock").</p>		
Note:	The default values of P0011 ("lock") and P0012 ("key") are the same.		

p0014[0...2]	Store mode / Store mode		
	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0	Max 1	Factory setting 0
Description:	Sets the store mode for parameters. The store mode can be configured for all interfaces listed under "Index".		
Value:	0: Volatile (RAM) 1: Nonvolatile (EEPROM)		
Index:	[0] = USS on RS485 [1] = USS on RS232 [2] = Fieldbus		
Note:	An independent store request may be part of the serial communications (e.g. PKE bits 15-12 of USS protocol), set by a PLC or PC tools like STARTER. See the table below for an influence on the settings of P0014.		

Value of p0014[x]	Store request via USS/PROFIBUS	Result
RAM	EEPROM	EEPROM
EEPROM	EEPROM	EEPROM
RAM	RAM	RAM
EEPROM	RAM	EEPROM

1. With the BOP the parameter will always be stored in the EEPROM.
2. P0014 itself will always be stored in the EEPROM.
3. P0014 will not be changed by performing a factory reset (P0010 = 30 and P0970 = 1).
4. P0014 can be transferred during a download (P0010 = 29).

When transferring parameter p0014, the inverter uses its processor to carry-out internal calculations. Communications - both via USS as well as via the Fieldbus - are interrupted for the time that it takes to make these calculations. This can result in the following error messages at the connected SIMATIC S7 control (communications via fieldbus):

- Parameter fault 30
- Drive fault 70
- Drive fault 75

When using STARTER (USS) to commission the drive system, data cannot be entered while these calculations are being made.

The faults can be acknowledged as soon as the calculations have been completed in the frequency inverter. These calculations can take up to one minute to complete.

r0018	Firmware version / Firmware version		
	Access level: 1	P-Group: Converter	Data type: FloatingPoint32
	Unit: -	Calculated: -	Data set: -
Description:	Displays version number of installed firmware.		

r0019.0...14	CO/BO: BOP control word / BOP CtrlWd		
	Access level: 3	P-Group: Commands	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays status of operator panel commands. The settings below are used as the "source" codes for keypad control when connecting to BICO input parameters.		
Bit field:	Bit	Signal name	1 signal 0 signal FP
	00	ON/OFF1	Yes No -
	01	OFF2: Electrical stop	No Yes -
	08	JOG right	Yes No -
	11	Reverse (setpoint inversion)	Yes No -
	13	Motor potentiometer MOP up	Yes No -
	14	Motor potentiometer MOP down	Yes No -
Note:	When BICO technology is used to allocate functions to panel buttons, this parameter displays the actual status of the relevant command.		
r0020	CO: Freq. setpoint before RFG / Setp before RFG		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays actual frequency setpoint (input of ramp function generator). This value is available filtered (r0020) and unfiltered (r1119). The actual frequency setpoint after RFG is displayed in r1170.		
r0021	CO: Act. filtered frequency / Act. filt. freq.		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays actual inverter output frequency (r0024) excluding slip compensation, resonance damping and frequency limitation.		
r0022	Act. filtered rotor speed / Act fil rotorspeed		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [RPM]	Calculated: -	Data set: -
Description:	Displays calculated rotor speed based on r0021 (filtered output frequency [Hz] x 120 / number of poles). The value is updated every 128 ms.		
Note:	This calculation makes no allowance for load-dependent slip.		
r0024	CO: Act. filt. output frequency / Act. outp. freq		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays actual filtered output frequency (slip compensation, resonance damping and frequency limitation are included). See also r0021. This value is available filtered (r0024) and unfiltered (r0066).		
r0025	CO: Act. output voltage / Act.outp. volt		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays filtered [rms] voltage applied to motor. This value is available filtered (r0025) and unfiltered (r0072).		

r0026[0...1]	CO: Act. filtered DC-link volt. / Act. fil. Vdc		
	Access level: 2	P-Group: Converter	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays filtered DC-link voltage. This value is available filtered (r0026) and unfiltered (r0070).		
Index:	[0] = Compensation DC voltage Channel [1] = Measurement/Monitoring DC voltage Channel		
Note:	r0026[0] = Main DC-link voltage r0026[1] = Decoupled DC-link voltage for internal supply (e.g. for CU). It depends on the drive topology. If it is not available it shows the value 0.		
r0027	CO: Act. output current / Act. outp. cur		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [A]	Calculated: -	Data set: -
Description:	Displays rms value of motor current [A]. This value is available filtered (r0027) and unfiltered (r0068).		
r0029	CO: Flux gen. current / Flux gen. cur.		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [A]	Calculated: -	Data set: -
Description:	Displays flux-generating current component. This value is available filtered (r0029) and unfiltered (r0076). The flux-generating current component is based on the nominal flux, which is calculated from the motor parameters (P0340 - Calculation of motor parameters).		
Dependency:	Applies when vector control is selected in P1300 (control mode); otherwise, the display shows the value zero.		
Note:	The flux-generating current component is generally constant up to the base speed of the motor; above base speed, this component is weakened (field weakening) thus enabling an increase in motor speed but at reduced torque.		
r0030	CO: Torque gen. current / Torque gen.cur		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [A]	Calculated: -	Data set: -
Description:	Displays torque-generating current component. This value is available filtered (r0030) and unfiltered (r0078). The torque-generating current component is calculated from the torque setpoint values delivered by the speed controller.		
Dependency:	Applies when vector control is selected in P1300 (control mode); otherwise, the display shows the value zero.		
Note:	For asynchronous motors, a limit is calculated for the torque generating current component (in conjunction with the maximum possible output voltage (r0071), motor leakage and current field weakening (r0377)) and this prevents motor stalling.		
r0031	CO: Act. filtered torque / Act fil torque		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Nm]	Calculated: -	Data set: -
Description:	Displays electrical torque. Output value will be zero at low speeds when current injection is active (r1751.4 = 1). This value is available filtered (r0031) and unfiltered (r0080).		
Note:	The electrical torque is not the same as the mechanical torque, which can be measured on the shaft. Due to windage and friction a part of the electrical torque is lost in the motor.		

r0032	CO: Act. filtered power / Act fil. power		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: -	Calculated: -	Data set: -
Description:	<p>Displays (mechanical) shaft power.</p> <p>Value is displayed in [kW] or [hp] depending on setting for P0100 (operation for Europe / North America).</p> <p>$P_{\text{mech}} = 2 * \text{Pi} * f * M$ --></p> <p>$r0032[\text{kW}] = (2 * \text{Pi} / 1000) * (r0022 / 60)[1/\text{min}] * r0031[\text{Nm}]$</p> <p>$r0032[\text{hp}] = r0032[\text{kW}] / 0.75$</p>		
r0035[0...2]	CO: Act. motor temperature / Act. mot.temp.		
	Access level: 2	P-Group: Motor	Data type: FloatingPoint32
	Unit: [°C]	Calculated: -	Data set: DDS
Description:	Displays measured motor temperature.		
r0036	CO: Inverter overload utilization / Invert ovl util		
	Access level: 4	P-Group: Converter	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	<p>Displays inverter overload utilization calculated via the I2t model.</p> <p>The actual I2t value relative to the max. possible I2t value supplies utilization in [%].</p> <p>If the current exceeds the threshold for P0294 (inverter I2t overload warning), warning A0505 (inverter I2t) is generated and the output current of the inverter reduced via P0290 (inverter overload reaction).</p> <p>If 100 % utilization is exceeded, fault F0005 (inverter I2t) is tripped.</p>		
Dependency:	<p>r0036 > 0:</p> <p>If the nominal current (see r0207) of the inverter is exceed, utilization will be displayed, otherwise, 0 % utilization is displayed.</p>		
r0037[0...4]	CO: Inverter temperature [°C] / Inverter temp.		
	Access level: 3	P-Group: Converter	Data type: FloatingPoint32
	Unit: [°C]	Calculated: -	Data set: -
Description:	Displays measured heatsink temperature and calculated junction temperature of IGBTs based on thermal model.		
Index:	<p>[0] = Measured heat sink temperature</p> <p>[1] = Total Chip Junction Temperature</p> <p>[2] = Rectifier temperature</p> <p>[3] = Inverter ambient temperature</p> <p>[4] = Control board temperature</p>		
Note:	The values are updated every 128 ms.		
r0038	CO: Fil. power factor / Fil.power fact		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: -	Calculated: -	Data set: -
Description:	Displays the filtered power factor.		
r0039	CO: Energy consumpt. meter [kWh] / Energy meter		
	Access level: 2	P-Group: Converter	Data type: FloatingPoint32
	Unit: [kWh]	Calculated: -	Data set: -
Description:	Displays electrical energy used by inverter since display was last reset (see P0040 - reset energy consumption meter).		
Dependency:	Value is reset when P0040 = 1 (reset energy consumption meter).		

p0040	Reset energy consumption meter / Reset energy meter		
	Access level: 2	P-Group: Converter	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min 0	Max 1	Factory setting 0
Description:	Resets value of parameter r0039 (energy consumption meter) to zero.		
Value:	0: No reset 1: Reset r0039 to 0		

r0050	CO/BO: Active Command Dataset / Active CDS		
	Access level: 2	P-Group: Commands	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays currently active Command Dataset (CDS).		
Value:	0: Command Dataset 0 (CDS) 1: Command Dataset 1 (CDS) 2: Command Dataset 2 (CDS)		
Note:	See parameter P0810.		

r0051[0...1]	CO: Active Drive Dataset (DDS) / Active DDS		
	Access level: 2	P-Group: Commands	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays currently selected and active Drive Dataset (DDS).		
Value:	0: Drive Dataset 0 (DDS0) 1: Drive Dataset 1 (DDS1) 2: Drive Dataset 2 (DDS2)		
Index:	[0] = Selected Drive Dataset [1] = Active Drive Dataset		
Note:	See parameter P0820.		

r0052.0...15	CO/BO: Act. status word 1 / Act StatWd1				
	Access level: 2	P-Group: Commands	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays first active status word of inverter (bit format) and can be used to diagnose inverter status.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Drive ready	Yes	No	-
	01	Drive ready to run	Yes	No	-
	02	Drive running	Yes	No	-
	03	Drive fault active	Yes	No	-
	04	OFF2 active	No	Yes	-
	05	OFF3 active	No	Yes	-
	06	ON inhibit active	Yes	No	-
	07	Drive warning active	Yes	No	-
	08	Deviation setpoint / act. value	No	Yes	-
	09	PZD control	Yes	No	-
	10	f_act >= P1082 (f_max)	Yes	No	-
	11	Warning: Motor current/torque limit	No	Yes	-
	12	Brake open	Yes	No	-
	13	Motor overload	No	Yes	-
	14	Motor runs right	Yes	No	-
	15	Inverter overload	No	Yes	-
Dependency:	r0052 Bit03 "Drive fault active": Output of Bit3 (Fault) will be inverted on digital output (Low = Fault, High = No Fault).				
Note:	See parameters r2197 and r2198.				

r0053.0...15		CO/BO: Act. status word 2 / Act StatWd2			
PM240	Access level: 2	P-Group: Commands	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays second status word of inverter (in bit format).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DC brake active	Yes	No	-
	01	f_act > P2167 (f_off)	Yes	No	-
	02	f_act > P1080 (f_min)	Yes	No	-
	03	Act. current r0068 >= P2170	Yes	No	-
	04	f_act > P2155 (f_1)	Yes	No	-
	05	f_act <= P2155 (f_1)	Yes	No	-
	06	f_act >= setpoint (f_set)	Yes	No	-
	07	Act. unfilt. Vdc < P2172	Yes	No	-
	08	Act. unfilt. Vdc > P2172	Yes	No	-
	09	Ramping finished	Yes	No	-
	10	PID output r2294 == P2292 (PID_min)	Yes	No	-
	11	PID output r2294 == P2291 (PID_max)	Yes	No	-
	14	Download Dataset 0 from OP	Yes	No	-
	15	Download Dataset 1 from OP	Yes	No	-
Notice:	r0053 Bit00 "DC brake active" ==> see parameter P1233				
Note:	See parameters r2197 and r2198.				

r0053.1...15		CO/BO: Act. status word 2 / Act StatWd2			
PM250	Access level: 2	P-Group: Commands	Data type: Unsigned16		
PM260	Unit: -	Calculated: -	Data set: -		
Description:	Displays second status word of inverter (in bit format).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	01	f_act > P2167 (f_off)	Yes	No	-
	02	f_act > P1080 (f_min)	Yes	No	-
	03	Act. current r0068 >= P2170	Yes	No	-
	04	f_act > P2155 (f_1)	Yes	No	-
	05	f_act <= P2155 (f_1)	Yes	No	-
	06	f_act >= setpoint (f_set)	Yes	No	-
	09	Ramping finished	Yes	No	-
	10	PID output r2294 == P2292 (PID_min)	Yes	No	-
	11	PID output r2294 == P2291 (PID_max)	Yes	No	-
	14	Download Dataset 0 from OP	Yes	No	-
	15	Download Dataset 1 from OP	Yes	No	-
Note:	See parameters r2197 and r2198.				

r0054.0...15		CO/BO: Act. control word 1 / Act CtrlWd1			
	Access level: 3	P-Group: Commands	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays first control word of inverter (in bit format) and can be used to diagnose which commands are active.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	ON/OFF1	Yes	No	-
	01	OFF2: Electrical stop	No	Yes	-
	02	OFF3: Fast stop	No	Yes	-
	03	Pulse enable	Yes	No	-
	04	RFG enable	Yes	No	-
	05	RFG start	Yes	No	-
	06	Setpoint enable	Yes	No	-
	07	Fault acknowledge	Yes	No	-
	08	JOG right	Yes	No	-
	09	JOG left	Yes	No	-
	10	Control from PLC	Yes	No	-
	11	Reverse (setpoint inversion)	Yes	No	-
	13	Motor potentiometer MOP up	Yes	No	-
	14	Motor potentiometer MOP down	Yes	No	-
	15	CDS Bit 0 (Hand/Auto)	Yes	No	-
Notice:	r0054 is identical to r2036 if USS is selected as command source via P0700 or P0719.				

r0055.0...15		CO/BO: Act. control word 2 / Act CtrlWd2			
PM240	Access level: 3	P-Group: Commands	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays additional control word of inverter (in bit format) and can be used to diagnose which commands are active.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fixed frequency Bit 0	Yes	No	-
	01	Fixed frequency Bit 1	Yes	No	-
	02	Fixed frequency Bit 2	Yes	No	-
	03	Fixed frequency Bit 3	Yes	No	-
	04	Drive Dataset (DDS) Bit 0	Yes	No	-
	05	Drive Dataset (DDS) Bit 1	Yes	No	-
	08	Enable PID	Yes	No	-
	09	Enable DC brake	Yes	No	-
	11	Enable Droop	Yes	No	-
	12	Torque control	Yes	No	-
	13	External fault 1	No	Yes	-
	15	Command Dataset (CDS) Bit 1	Yes	No	-
Notice:	r0055 is identical to r2037 if USS is selected as command source via P0700 or P0719.				

r0055.0...15		CO/BO: Act. control word 2 / Act CtrlWd2			
PM250	Access level: 3	P-Group: Commands	Data type: Unsigned16		
PM260	Unit: -	Calculated: -	Data set: -		
Description:	Displays additional control word of inverter (in bit format) and can be used to diagnose which commands are active.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fixed frequency Bit 0	Yes	No	-
	01	Fixed frequency Bit 1	Yes	No	-
	02	Fixed frequency Bit 2	Yes	No	-
	03	Fixed frequency Bit 3	Yes	No	-
	04	Drive Dataset (DDS) Bit 0	Yes	No	-
	05	Drive Dataset (DDS) Bit 1	Yes	No	-
	08	Enable PID	Yes	No	-
	11	Enable Droop	Yes	No	-
	12	Torque control	Yes	No	-
	13	External fault 1	No	Yes	-
	15	Command Dataset (CDS) Bit 1	Yes	No	-
Notice:	r0055 is identical to r2037 if USS is selected as command source via P0700 or P0719.				

r0056.0...15		CO/BO: Status of motor control / Stat MotCtrl			
PM240	Access level: 3	P-Group: Closed-loop control	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays status of motor control (in bit format), which can be used to diagnose inverter status.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Init. control finished	Yes	No	-
	01	Motor demagnetizing finished	Yes	No	-
	02	Pulses enabled	Yes	No	-
	03	Voltage soft start select	Yes	No	-
	04	Motor excitation finished	Yes	No	-
	05	Starting boost active	Yes	No	-
	06	Acceleration boost active	Yes	No	-
	07	Frequency is negative	Yes	No	-
	08	Field weakening active	Yes	No	-
	09	Volts setpoint limited	Yes	No	-
	10	Slip frequency limited	Yes	No	-
	11	f _{out} > f _{max} Freq. limited	Yes	No	-
	12	Phase reversal selected	Yes	No	-
	13	I _{max} controller active/torque limit reached	Yes	No	-
	14	V _{dc} -max controller active	Yes	No	-
	15	KIB (V _{dc} -min control) active	Yes	No	-
Notice:	The I _{max} controller (r0056 Bit13) will be activated when the actual output current (r0027) exceeds the current limit in r0067.				

r0056.0...13	CO/BO: Status of motor control / Stat MotCtrl		
PM250	Access level: 3	P-Group: Closed-loop control	Data type: Unsigned16
PM260	Unit: -	Calculated: -	Data set: -
Description:	Displays status of motor control (in bit format), which can be used to diagnose inverter status.		
Bit field:	Bit	Signal name	1 signal 0 signal FP
	00	Init. control finished	Yes No -
	01	Motor demagnetizing finished	Yes No -
	02	Pulses enabled	Yes No -
	03	Voltage soft start select	Yes No -
	04	Motor excitation finished	Yes No -
	05	Starting boost active	Yes No -
	06	Acceleration boost active	Yes No -
	07	Frequency is negative	Yes No -
	08	Field weakening active	Yes No -
	09	Volts setpoint limited	Yes No -
	10	Slip frequency limited	Yes No -
	11	f_out > f_max Freq. limited	Yes No -
	12	Phase reversal selected	Yes No -
	13	I_max controller active/torque limit reached	Yes No -
Notice:	The I-max controller (r0056 Bit13) will be activated when the actual output current (r0027) exceeds the current limit in r0067.		
r0061	CO: Act. rotor speed / Act rotor speed		
CU240S	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
CU240S DP	Unit: [Hz]	Calculated: -	Data set: -
CU240S DP-F			
CU240S PN			
CU240S PN-F			
Description:	Displays current speed detected by encoder.		
Dependency:	r0061 displays the value zero with P0400 = 0.		
r0062	CO: Freq. setpoint / Freq. setpoint		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays speed setpoint in Hz of vector speed controller.		
Dependency:	r0062 = 0 in V/f control modes (P1300 = 0...19).		
r0063	CO: Act. frequency / Act. frequency		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays actual motor frequency in Hz. This value is available filtered (r0021) and unfiltered (r0063).		
r0064	CO: Dev. frequency controller / Dev. freq ctrl		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays actual deviation of speed controller. This value is calculated from the speed setpoint (r0062) and the actual speed (r0063).		
Dependency:	Applies when vector control is selected in P1300 (control mode); otherwise, the display shows the value zero.		
r0065	CO: Slip frequency / Slip frequency		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays slip frequency of motor in [%] relative to the rated motor frequency (P0310).		

Note: For V/f control, see also P1335 (slip compensation).

r0066	CO: Act. output frequency / Act. outp freq		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -

Description: Displays actual output frequency in Hz. This value is available filtered (r0024) and unfiltered (r0066).

Note: The output frequency is limited by the values entered in P1080 (min. frequency) and P1082 (max. frequency).

r0067	CO: Act. output current limit / Outp cur limit		
PM240	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [A]	Calculated: -	Data set: -

Description: Displays valid maximum output current of inverter.
Parameter r0067 is influenced/determined by the following factors:

- Rated motor current P0305
- Motor overload factor P0640
- Motor protection in dependency of P0610
- r0067 is less than or equal to maximum inverter current r0209
- Inverter protection in dependency of P0290

Note: A reduction of r0067 may indicate an inverter overload or a motor overload.

r0067	CO: Act. output current limit / Outp cur limit		
PM250	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
PM260	Unit: [A]	Calculated: -	Data set: -

Description: Displays valid maximum output current of inverter.
Parameter r0067 is influenced/determined by the following factors:

- Rated motor current P0305
- Motor overload factor P0640
- Motor protection in dependency of P0610
- r0067 is less than or equal to maximum inverter current r0209
- Inverter protection in dependency of P0290
- r0067 is affected by the regeneration power limit when regenerating

Note: A reduction of r0067 may indicate an inverter overload or a motor overload.

r0068	CO: Output current / Output current		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [A]	Calculated: -	Data set: -

Description: Displays unfiltered [rms] value of motor current [A]. This value is available filtered (r0027) and unfiltered (r0068).

Note: Used for process control purposes (in contrast to r0027, which is filtered and used as display value).

r0069[0...5]	CO: Act. phase currents / Act. phase cur		
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [A]	Calculated: -	Data set: -
Description:	Displays measured phase currents.		
Index:	[0] = U_phase [1] = V_phase [2] = W_phase [3] = Offset U_phase [4] = Offset V_phase [5] = Offset W_phase		
r0070	CO: Act. DC-link voltage / Act. Vdc		
	Access level: 3	P-Group: Converter	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays DC-link voltage. This value is available filtered (r0026) and unfiltered (r0070).		
Note:	Used for process control purposes (in contrast to r0026 (actual DC-link voltage), which is filtered and used as display value).		
r0071	CO: Max. output voltage / Max. outp.volt		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays maximum output voltage.		
Dependency:	Actual maximum output voltage depends on the actual input supply voltage.		
r0072	CO: Act. output voltage / Act. outp.volt		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays output voltage. This value is available filtered (r0025) and unfiltered (r0072).		
r0074	CO: Act. modulation / Act modulation		
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays actual modulation index. The modulation index is defined as ratio between the magnitude of the fundamental component in the inverter phase output voltage and half of the DC-link voltage.		
r0075	CO: Current setpoint Isd / Cur. setp. Isd		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [A]	Calculated: -	Data set: -
Description:	Displays setpoint of flux generating current component.		
Dependency:	Applies when vector control is selected in P1300 (control mode); otherwise, the display shows the value zero.		
r0076	CO: Act. current Isd / Act. cur. Isd		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [A]	Calculated: -	Data set: -
Description:	Displays flux generating current component. This value is available filtered (r0029) and unfiltered (r0076).		
Dependency:	Applies when vector control is selected in P1300 (control mode); otherwise, the display shows the value zero.		

r0077	CO: Current setpoint Isq / Cur. setp. Isq	Access level: 3 Unit: [A]	P-Group: Closed-loop control Calculated: -	Data type: FloatingPoint32 Data set: -
Description:	Displays setpoint for component of torque generating current.			
Dependency:	Applies when vector control is selected in P1300 (control mode); otherwise, the display shows the value zero.			
r0078	CO: Act. current Isq / Act. cur. Isq	Access level: 3 Unit: [A]	P-Group: Closed-loop control Calculated: -	Data type: FloatingPoint32 Data set: -
Description:	Displays component of torque generating current. This value is available filtered (r0030) and unfiltered (r0078).			
r0079	CO: Torque setpoint (total) / Total trq setp	Access level: 3 Unit: [Nm]	P-Group: Closed-loop control Calculated: -	Data type: FloatingPoint32 Data set: -
Description:	Displays total torque setpoint after limitation.			
Dependency:	Applies when vector control is selected in P1300 (control mode); otherwise, the display shows the value zero.			
r0080	CO: Act. torque / Act. torque	Access level: 4 Unit: [Nm]	P-Group: Closed-loop control Calculated: -	Data type: FloatingPoint32 Data set: -
Description:	Displays actual torque. Output value will be zero at low speeds when current injection is active (r1751.4 = 1). This value is available filtered (r0031) and unfiltered (r0080).			
r0084	CO: Act. air gap flux / Air gap flux	Access level: 4 Unit: [%]	P-Group: Closed-loop control Calculated: -	Data type: FloatingPoint32 Data set: -
Description:	Displays air gap flux in [%] relative to the rated motor flux.			
r0085	CO: Act. re-active current / Act.re-active cur	Access level: 3 Unit: [A]	P-Group: Closed-loop control Calculated: -	Data type: FloatingPoint32 Data set: -
Description:	Displays re-active (imaginary part) of motor current.			
Dependency:	Applies when V/f control is selected in P1300 (control mode); otherwise, the display shows the value zero.			
r0086	CO: Act. active current / Act.active cur	Access level: 3 Unit: [A]	P-Group: Closed-loop control Calculated: -	Data type: FloatingPoint32 Data set: -
Description:	Displays active (real part) of motor current.			
Dependency:	Applies when V/f control is selected in P1300 (control mode); otherwise, the display shows the value zero.			
r0087	CO: Act. power factor / Act.power fact	Access level: 3 Unit: -	P-Group: Closed-loop control Calculated: -	Data type: FloatingPoint32 Data set: -
Description:	Displays the actual power factor.			

r0090	CO: Act. rotor angle / Act rotor angle		
CU240S	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
CU240S DP	Unit: [°]	Calculated: -	Data set: -
CU240S DP-F			
CU240S PN			
CU240S PN-F			
Description:	Indicates the current angle of the rotor.		
r0094	CO: Transformation angle / Transf. angle		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [°]	Calculated: -	Data set: -
Description:	Displays the transformation angle (flux angle in VC mode or angle from frequency in Vf mode)		
p0095[0...9]	CI: Display PZD signals / PZD signals		
	Access level: 3	P-Group: Closed-loop control	Data type: U32 / Integer16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Selects source of display for PZD signals.		
Index:	[0] = 1st PZD signal [1] = 2nd PZD signal [2] = 3rd PZD signal [3] = 4th PZD signal [4] = 5th PZD signal [5] = 6th PZD signal [6] = 7th PZD signal [7] = 8th PZD signal [8] = 9th PZD signal [9] = 10th PZD signal		
r0096[0...9]	PZD signals / PZD signals		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays PZD signals in [%].		
Index:	[0] = 1st PZD signal [1] = 2nd PZD signal [2] = 3rd PZD signal [3] = 4th PZD signal [4] = 5th PZD signal [5] = 6th PZD signal [6] = 7th PZD signal [7] = 8th PZD signal [8] = 9th PZD signal [9] = 10th PZD signal		
Note:	r0096 = 100 % corresponds to 4000 hex.		

p0100	Europe / North America / Europe / Nth Amer.		
	Access level: 1	P-Group: -	Data type: Unsigned16
	Quick comm. YES	Active: NO	Data set: -
	Can be changed: C(1)	Calculated: -	
	Min 0	Max 2	Factory setting 0
Description:	Determines whether power settings are expressed in [kW] or [hp] (e.g. Rated motor power P0307). The default settings for the rated motor frequency P0310 and maximum frequency P1082 are set automatically here, in addition to reference frequency P2000.		
Value:	0: Europe [kW], motor base frequency is 50 Hz 1: North America [hp], motor base frequency is 60 Hz 2: North America [kW], motor base frequency is 60 Hz		
Dependency:	Where: <ul style="list-style-type: none"> • Stop drive first (i.e. disable all pulses) before you change this parameter. • Parameter P0100 can only be changed with P0010 = 1 (Commissioning mode) via the respective interface (e.g. USS on RS232). • Changing P0100 resets all rated motor parameters as well as other parameters that depend on the rated motor parameters (see P0340 - calculation of motor parameters). 		
r0191[0...2]	Configuration Control Unit / Config CU		
	Access level: 3	P-Group: -	Data type: Unsigned32
	Unit: -	Calculated: -	Data set: -
Description:	Displays the actual HW-configuration (SZL vector) of the Control Unit.		
Index:	[0] = SZL Vector CU and PM combined [1] = SZL Vector CU [2] = SZL Vector PM		
p0199	Equipment system number / Equip. system no.		
	Access level: 2	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0	Max 255	Factory setting 0
Description:	Equipment system number. This parameter has no operation effect (only for factory purposes).		
p0201[0...2]	Act. power module code number / Act.Pmod. code no		
	Access level: 3	P-Group: Converter	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min 0	Max 65535	Factory setting 0
Description:	Identifies hardware variant.		
Index:	[0] = Powerstack code [1] = Functionality version - Last Digit of MLFB [2] = Last used PS Id		
Notice:	Parameter P0201 = 0 indicates that no power module has been identified.		

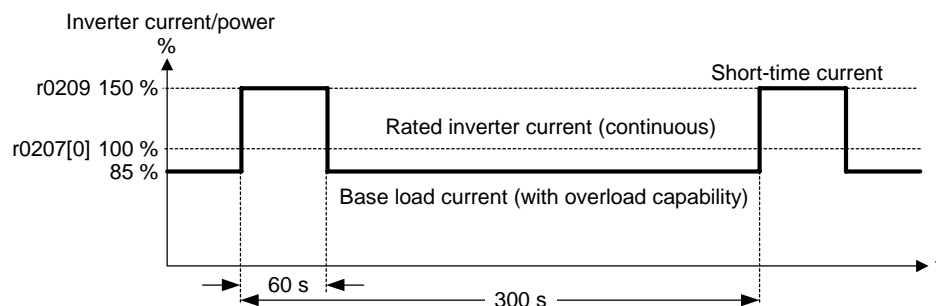
r0203		Act. inverter type / Act. inverter type	
	Access level: 3	P-Group: Converter	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Type number of actual inverter identified.		
Value:	0: No PS Data/Module 1: reserved 2: reserved 3: reserved 4: reserved 5: reserved 6: reserved 7: reserved 110: SINAMICS G110 111: SINAMICS IPM25 114: SINAMICS PM240 115: SINAMICS PM250 117: SINAMICS PM240 PX 125: SINAMICS ET200PRO 130: SINAMICS PM DCP		

r0204		Power module features / Pmodule features			
PM240	Access level: 3	P-Group: Converter	Data type: Unsigned32		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays hardware features of power module.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DC input voltage	Yes	No	-
	01	RFI filter	Yes	No	-
	02	Active Line Module	Yes	No	-
	03	SLM	Yes	No	-
	04	BLM with thyristor	Yes	No	-
	05	BLM with Diode	Yes	No	-
	06	Water Cooled	Yes	No	-
	12	Safe Brake	Yes	No	-
	13	Safety Enabled	Yes	No	-
	14	Integrated Output Filter	Yes	No	-
Note:	Parameter r0204 = 0 indicates that no power module has been identified.				

r0204		Power module features / Pmodule features			
PM250	Access level: 3	P-Group: Converter	Data type: Unsigned32		
PM260	Unit: -	Calculated: -	Data set: -		
Description:	Displays hardware features of power module.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	DC input voltage	Yes	No	-
	01	RFI filter	Yes	No	-
	02	Active Line Module	Yes	No	-
	03	SLM	Yes	No	-
	04	BLM with thyristor	Yes	No	-
	05	BLM with Diode	Yes	No	-
	06	Water Cooled	Yes	No	-
	07	F3E Powerstack	Yes	No	-
	12	Safe Brake	Yes	No	-
	13	Safety Enabled	Yes	No	-
	14	Integrated Output Filter	Yes	No	-
Note:	Parameter r0204 = 0 indicates that no power module has been identified.				

p0205	Inverter application / Inverter appl.		
	Access level: 3	P-Group: Converter	Data type: Unsigned16
	Quick comm. YES	Active: NO	Data set: -
	Can be changed: C(1)	Calculated: -	
	Min 0	Max 1	Factory setting 0
Description:	<p>Selects inverter application.</p> <p>The inverter and motor requirements are determined by the speed range and torque requirements of the load. Dependent on the frequency/torque characteristic of the application this parameter can be set to high overload (HO) or light overload (LO).</p> <ul style="list-style-type: none"> • High overload (HO): HO is used if the application needs a high overload on the whole frequency range. Many loads can be considered to be high overloads. Typical high overloads are conveyors, compressors and positive displacement pumps. • Light overload (LO): LO is used if the application has a parabolic frequency/torque characteristic like many fans and pumps. Light overload offers the following possibilities with the same inverter: <ul style="list-style-type: none"> - Higher rated inverter current r0207 - Higher rated inverter power r0206 - Higher threshold for I2t protection <p>If P0205 is modified in quick commissioning it immediately calculates various motor parameters:</p> <ol style="list-style-type: none"> 1. P0305 Rated motor current 2. P0307 Rated motor power 3. P0640 Motor overload factor <p>It is recommended to modify P0205 first. Afterwards motor parameter may be adapted. Motor parameter will be overridden by changing this sequence.</p>		
Value:	0: High overload 1: Light overload		
Notice:	Use setting 1 (light overload) only for light-overload applications (e.g. pumps and fans). If used for high-overload applications, I2t warning will be produced too late, causing overheating in the motor.		
Note:	The parameter value is not reset by the factory setting (see P0970).		
r0206	Rated inverter power [kW] / [hp] / Rated power[kW/hp]		
	Access level: 2	P-Group: Converter	Data type: FloatingPoint32
	Unit: -	Calculated: -	Data set: -
Description:	Displays nominal rated motor power from inverter.		
Dependency:	Value is displayed in [kW] or [hp] depending on setting for P0100 (operation for Europe / North America).		

r0207[0...2]	Rated inverter current / Rated inverter cur		
	Access level: 2	P-Group: Converter	Data type: FloatingPoint32
	Unit: [A]	Calculated: -	Data set: -
Description:	Displays rated inverter current.		
Index:	[0] = Rated inverter current [1] = Rated LO current [2] = Rated HO current		
Note:	The rated light overload (LO) current r0207[1] and rated high overload (HO) current r0207[2] values correspond to suitable 4-pole Siemens standard motors (IEC) for the selected load cycle (see diagram). The parameters r0207[1], r0207[2] are the default value of P0305 in association with the HO/LO application (load cycle). If r0207[1] = r0207[2], then no differentiation is possible between HO/LO applications.		



r0208	Rated inverter voltage / Rated voltage		
	Access level: 2	P-Group: Converter	Data type: Unsigned32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays nominal AC supply voltage of inverter.		
Note:	r0208 = 230 : 200 - 240 V +/- 10 % r0208 = 400 : 380 - 480 V +/- 10 % r0208 = 575 : 500 - 600 V +/- 10 %		

r0209	Maximum inverter current / Max. inverter cur		
	Access level: 2	P-Group: Converter	Data type: FloatingPoint32
	Unit: [A]	Calculated: -	Data set: -
Description:	Displays maximum output current of inverter.		
Dependency:	Parameter r0209 depends on the derating which is affected by pulse frequency P1800, ambient temperature and altitude. The data of deration is given in the Operating Instructions.		

Parameter	Parameter Name	Access level:	P-Group:	Data type:	
p0210	Supply voltage / Supply voltage	3	Converter	Unsigned16	
	Quick comm.	NO	Active: YES	Data set: -	
	Can be changed:	T	Calculated: -		
	Min	0 [V]	Max	1000 [V]	
			Factory setting	400 [V]	
	Description:	Parameter P0210 defines the supply voltage. Its default value depends upon the type of inverter. If P0210 does not correspond to the supply voltage, then it must be modified.			
	Dependency:	Optimizes Vdc controller, which extends the ramp-down time if regenerative energy from motor would otherwise cause DC-link overvoltage trips. Reducing the value enables controller to cut in earlier and reduce the risk of overvoltage. Set P1254 ("Auto detect Vdc switch-on levels") = 0. Cut-in levels for Vdc-controller and compound braking are then derived directly from P0210 (supply voltage). <ul style="list-style-type: none"> Vdc_min switch-on level = $p1245 * \sqrt{2} * p0210$ Vdc_max switch-on level = $1.15 * \sqrt{2} * p0210$ Dynamic braking switch-on level = $1.13 * \sqrt{2} * p0210$ Compound braking switch-on level = $1.13 * \sqrt{2} * p0210$ 			
	Note:	If mains voltage is higher than value entered, automatic deactivation of the Vdc controller may occur to avoid acceleration of the motor. A warning will be issued in this case (A0910). Default value is depending on inverter type and its rating data.			
	<hr/>				
	p0230	Output filter / Output filter	1	Motor	Unsigned16
Quick comm.		YES	Active: NO	Data set: -	
Can be changed:		C(1)	Calculated: -		
Min		0	Max	4	
			Factory setting	0	
Description:		Shows the selected output filter.			
Value:		0: No output filter 1: Output choke 3: Appropriate SiemensSinus-/LC-fil 4: Custom Sinus-/LC-filter			
Dependency:		If a Sinus-/LC-filter [P0230 = 3 or (P0230 = 4 and P0234 > 0)] is selected: <ul style="list-style-type: none"> the modulation index is limited to 100 % (P1803 = 100) what limits the output voltage. the modulation type is set to SVM (P1802 = 2). the resultant max. output frequency r1084 is limited depending on the filter and motor specifications. 			
Caution:		Inverter size and motor size (nominal power) should fit together. Do not start the drive if a LC-filter is connected and no load is present. This could damage the filter.			
Note:		If a filter type is not available for the used inverter, the option is not selectable. The parameter is only changeable in quick commissioning. In case of an internal Sinus-/LC- output filter it will be set to LC-filter (P0230 = 3) and is not visible and changeable.			

r0231[0...1]	Max. cable length / Max. cable length		
	Access level: 3	P-Group: Converter	Data type: Unsigned16
	Unit: [m]	Calculated: -	Data set: -
Description:	Indexed parameter to display maximum allowable cable length between inverter and motor.		
Index:	[0] = Max. allowed unscreened cable length [1] = Max. allowed screened cable length		
Notice:	For full EMC compliance, the screened cable must not exceed 25 m in length when an EMC filter is fitted.		
p0233	Filter inductance / Filter inductance		
	Access level: 1	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. YES	Active: YES	Data set: -
	Can be changed: C(1)	Calculated: -	
	Min 0.00000	Max 1000.00000	Factory setting 0.00000
Description:	The inductance of the used output filter (phase value in mH).		
Note:	The parameter is only changable if a custom filter is selected (P0230 = 4).		
p0234	Filter capacity / Filter capacity		
	Access level: 1	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. YES	Active: YES	Data set: -
	Can be changed: C(1)	Calculated: -	
	Min 0.00000	Max 1000.00000	Factory setting 0.00000
Description:	The capacity of the used output filter (value in μF):		
	<ul style="list-style-type: none"> star connection: p0234 = capacity per phase delta connection: p0234 = 3 * capacity between 2 phases 		
Note:	The parameter is only changable if a custom filter is selected (P0230 = 4).		

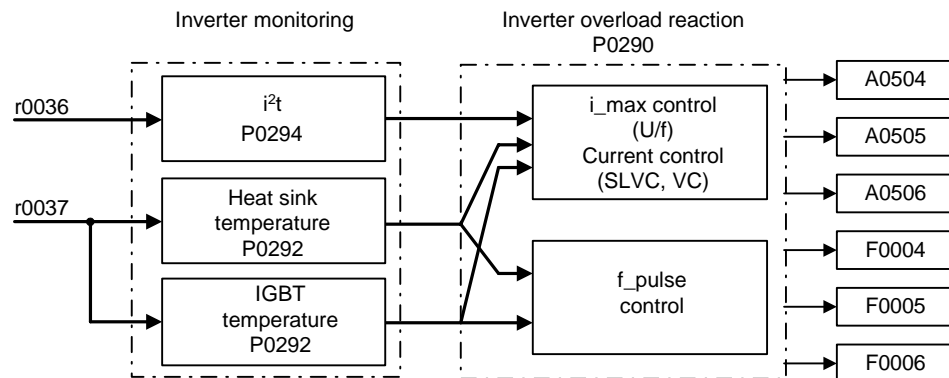
p0290	Inverter overload reaction / Overload reaction		
Access level: 3	P-Group: Converter	Data type: Unsigned16	
Quick comm. NO	Active: NO	Data set: -	
Can be changed: T	Calculated: -		
Min 0	Max 3	Factory setting 2	

Description: Selects reaction of inverter to an internal thermal overload condition.

Value:
 0: Reduce output frequency and output current
 1: No reduction, trip (F0004/ 5/ 6) when thermal limits reached
 2: Reduce pulse frequency, output current and output frequency
 3: Reduce pulse freq. only and trip (F0006) when overload too high

Dependency: Following physical values influence the inverter overload protection (see diagram):

- Heat sink temperature (r0037.0); causes A0504 and F0004.
- IGBT Junction temperature (r0037.1); causes F0004 or F0006.
- Delta temperature between heat sink and junction temperature; causes A0504 and F0006.
- Inverter I2t (r0036); causes A0505 and F0005.



Notice:

P0290 = 0, 2:

- Reduction of output frequency is only effective if the load is also reduced. This is for example valid for light overload applications with a quadratic torque characteristic as pumps or fans.
- For settings P0290 = 0 or 2, the I-max controller will act upon the output current limit (r0067) in case of overtemperature.

P0290 = 0:

- With pulse frequencies above nominal, pulse frequency will be reduced to nominal immediately in the event of r0027 greater than r0067 (current limit).

P0290 = 2, 3:

- The pulse frequency P1800 is reduced only if higher than 2 kHz and if the operating frequency is below 2 Hz.
- The actual pulse frequency is displayed in parameter r1801.0 and the minimal pulse frequency for reduction is displayed in r1801.1.
- Inverter I2t acts upon output current and output frequency, but not on pulse frequency.

A trip will always result, if the action taken does not sufficiently reduce internal temperatures.

p0291[0...2]	Inverter protection / Inverter protect.			
	Access level: 4	P-Group: Converter	Data type: Unsigned16	
	Quick comm. NO	Active: YES	Data set: DDS	
	Can be changed: T	Calculated: -		
	Min	Max	Factory setting	
	-	-	0001 bin	
Description:	Bit 00 for enabling/disabling automatic pulse frequency reduction at output frequencies below 2 Hz. The benefit is to reduce the noises at frequencies below 2 Hz. Bit 02 shows if phase loss detection (input phase) of 3 phase inverters is enabled after factory reset. Default setting of phase loss is disabled for FSA - FSC. FSD and greater it is enabled.			
Bit field:	Bit	Signal name	1 signal	0 signal
	01	reserved	Yes	No
	02	Phase loss detection enable	Yes	No
Note:	See P0290 (inverter overload reaction)			
p0292	Inverter temperature warning / Inv. temp. warn.			
	Access level: 3	P-Group: Converter	Data type: Unsigned16	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	0 [°C]	25 [°C]	5 [°C]	
Description:	Defines the temperature difference (in °C) between the overtemperature trip threshold (F0004) and the warning threshold (A0504) of the inverter. The trip threshold is stored internally by the inverter and cannot be changed by the user.			
p0294	Inverter I2t warning / Inv. I2t warn.			
	Access level: 4	P-Group: Converter	Data type: FloatingPoint32	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	10.0 [%]	100.0 [%]	95.0 [%]	
Description:	Defines the [%] value at which warning A0505 (inverter I2t) is generated. Inverter I2t calculation is used to determine a maximum tolerable period for inverter overload. The I2t calculation value is deemed = 100 % when this maximum tolerable period is reached.			
Dependency:	<ul style="list-style-type: none"> The output current of the inverter has been reduced. The value of I2t does not exceed 100 %. 			
Note:	P0294 = 100 % corresponds to stationary nominal load.			
p0295	Inverter fan off delay time / Fan delay time			
	Access level: 3	P-Group: Terminals	Data type: Unsigned16	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	0 [s]	3600 [s]	0 [s]	
Description:	Defines inverter fan switch off delay time in seconds after drive has stopped.			
Note:	Setting to 0, inverter fan will switch off when the drive stops, that means no delay.			

p0300[0...2]	Select motor type / Select motor type		
PM240	Access level: 2	P-Group: Motor	Data type: Unsigned16
	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1)	Calculated: -	
	Min 1	Max 2	Factory setting 1
Description:	<p>Selects motor type.</p> <p>This parameter is required during commissioning to select motor type and optimize inverter performance. Most motors are asynchronous; if in doubt, use the following formula .</p> $60 * P0310 / P0311$ <p>(the ratio of rated frequency (P0310) and rated motor speed (P0311))</p> <p>If the result is a whole number, the motor is synchronous.</p>		
Value:	<p>1: Asynchronous rotational motor</p> <p>2: Synchronous rotational motor</p>		
Dependency:	<p>Changeable only when P0010 = 1 (quick commissioning).</p> <p>P1233 DC braking</p> <p>If synchronous motor is selected, the following functions are not available:</p> <p>P0308 Power factor</p> <p>P0309 Motor efficiency</p> <p>P0346 Magnetization time</p> <p>P0347 Demagnetization time</p> <p>P1335 Slip compensation</p> <p>P1336 Slip limit</p> <p>P0320 Motor magnetizing current</p> <p>P0330 Rated motor slip</p> <p>P0331 Rated magnetization current</p> <p>P0332 Rated power factor</p> <p>P0384 Rotor time constant</p> <p>P1200, P1202, P1203 Flying start</p> <p>P1230, P1232, P1233 DC braking</p>		

p0300[0...2]	Select motor type / Select motor type		
PM250	Access level: 2	P-Group: Motor	Data type: Unsigned16
PM260	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1)	Calculated: -	
	Min	Max	Factory setting
	1	2	1

Description: Selects motor type.
 This parameter is required during commissioning to select motor type and optimize inverter performance.
 Most motors are asynchronous; if in doubt, use the following formula .
 $60 * P0310 / P0311$ (the ratio of rated frequency (P0310) and rated motor speed (P0311)
 If the result is a whole number, the motor is synchronous.

Value:
 1: Asynchronous rotational motor
 2: Synchronous rotational motor

Dependency: Changeable only when P0010 = 1 (quick commissioning).
 If synchronous motor is selected, the following functions are not available:
 P0308 Power factor
 P0309 Motor efficiency
 P0346 Magnetization time
 P0347 Demagnetization time
 P1335 Slip compensation
 P1336 Slip limit
 P0320 Motor magnetizing current
 P0330 Rated motor slip
 P0331 Rated magnetization current
 P0332 Rated power factor
 P0384 Rotor time constant
 P1200, P1202, P1203 Flying start

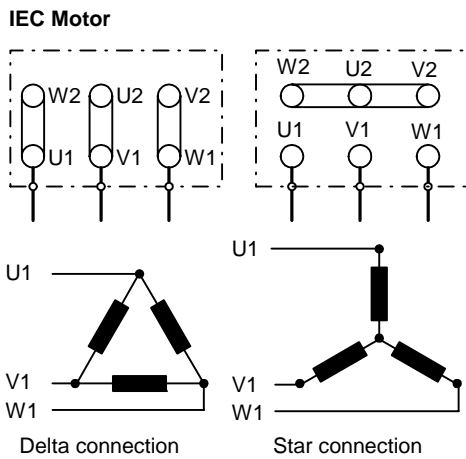
p0304[0...2]	Rated motor voltage / Rated mot. voltage		
	Access level: 1	P-Group: Motor	Data type: Unsigned16
	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1)	Calculated: -	
	Min	Max	Factory setting
	10 [V]	2000 [V]	400 [V]

Description: Nominal motor voltage [V] from rating plate.

Dependency: Changeable only when P0010 = 1 (quick commissioning).
 Default value is depending on inverter type and its rating data.

Caution: The input of rating plate data must correspond with the wiring of the motor (star / delta).
 This means, if delta wiring is used for the motor, delta rating plate data has to be entered.



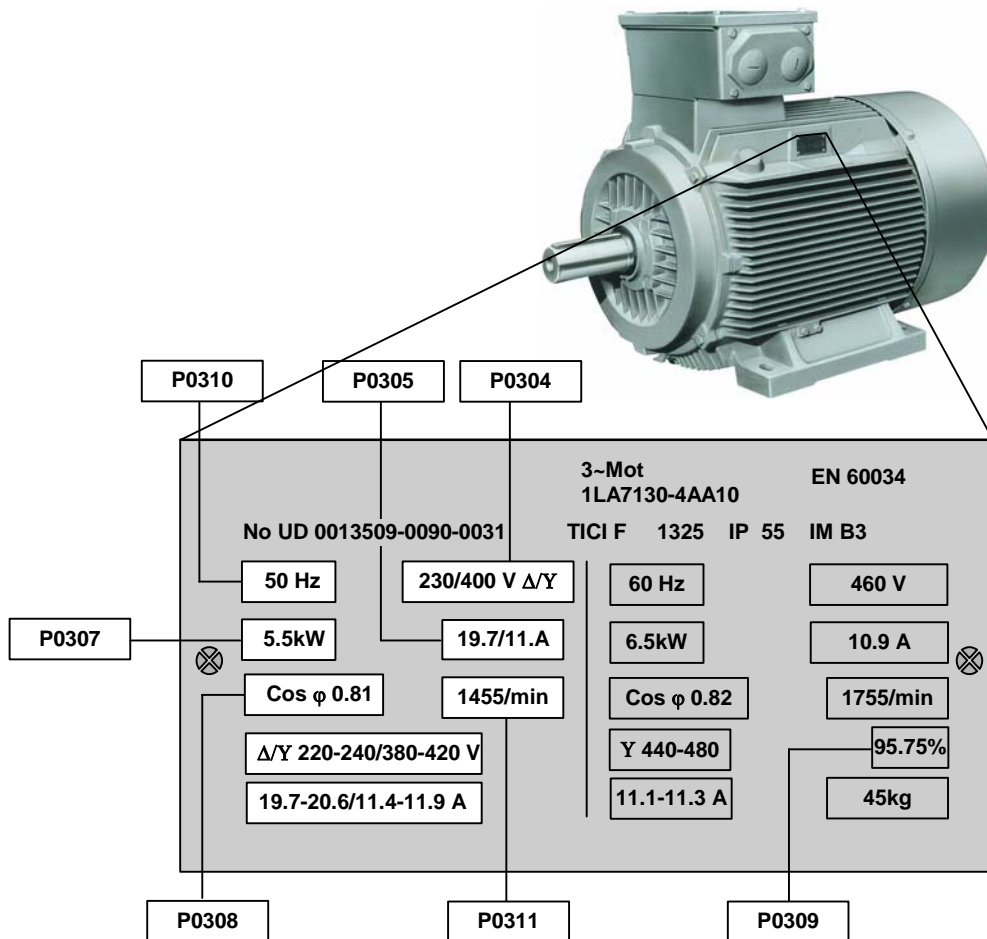


Safety Integrated:

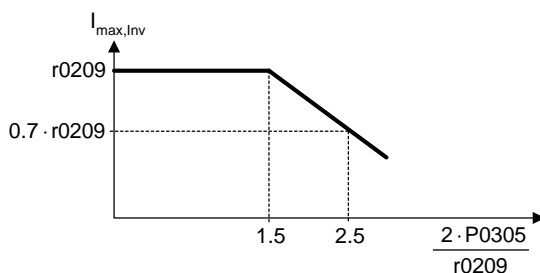
If driving loads occur in the application, the motor must be dimensioned so that its slip in supersynchronous operation always remains within the rated slip.

Note:

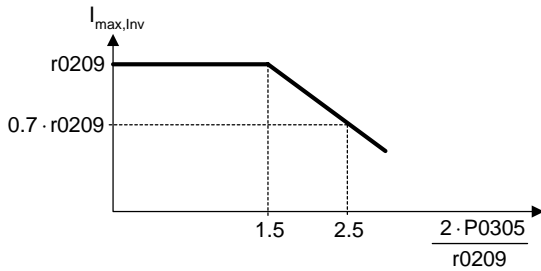
Following diagram shows a typical rating plate with the locations of the relevant motor data.



p0305[0...2]	Rated motor current / Rated mot. current		
CU240E	Access level: 1	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1)	Calculated: -	
	Min 0.01 [A]	Max 10000.00 [A]	Factory setting 1.86 [A]
Description:	Nominal motor current [A] from rating plate.		
Dependency:	Changeable only when P0010 = 1 (quick commissioning). Depends also on P0320 (motor magnetization current).		
Note:	The maximum value of P0305 depends on the maximum inverter current r0209 and the motor type: Asynchronous motor : P0305_max = P0209 Synchronous motor : P0305_max = 2 * P0209 (for HO operation) and P0305_max = P0209 (for LO operation) It is recommended that the ratio of P0305 (rated motor current) and r0207 (rated inverter current) should not be lower than: for V/f operation : $(1 / 8) \leq (p0305 / r0207)$ for SLVC : $(1 / 4) \leq (p0305 / r0207)$ When the relation of the nominal motor current P0305 and half of the maximal inverter current (r0209) exceeds 1.5 an additional current derating is applied. This is necessary to protect the inverter from harmonic current waves.		



Default value is depending on inverter type and its rating data.

p0305[0...2]		Rated motor current / Rated mot. current	
CU240S	Access level: 1	P-Group: Motor	Data type: FloatingPoint32
CU240S DP	Quick comm. YES	Active: NO	Data set: DDS
CU240S DP-F	Can be changed: C(1)	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min 0.01 [A]	Max 10000.00 [A]	Factory setting 1.86 [A]
Description:	Nominal motor current [A] from rating plate.		
Dependency:	Changeable only when P0010 = 1 (quick commissioning). Depends also on P0320 (motor magnetization current).		
Note:	The maximum value of P0305 depends on the maximum inverter current r0209 and the motor type: Asynchronous motor : P0305_max = P0209 Synchronous motor : P0305_max = 2 * P0209 (for HO operation) and P0305_max = P0209 (for LO operation) It is recommended that the ratio of P0305 (rated motor current) and r0207 (rated inverter current) should not be lower than: for V/f operation : $(1 / 8) \leq (p0305 / r0207)$ for SLVC and VC: $(1 / 4) \leq (p0305 / r0207)$ When the relation of the nominal motor current P0305 and half of the maximal inverter current (r0209) exceeds 1.5 an additional current derating is applied. This is necessary to protect the inverter from harmonic current waves.		
			
	Default value is depending on inverter type and its rating data.		
p0307[0...2]		Rated motor power / Rated motor power	
	Access level: 1	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1)	Calculated: -	
	Min 0.01	Max 2000.00	Factory setting 0.75
Description:	Nominal motor power [kW/hp] from rating plate.		
Dependency:	If P0100 = 1, values will be in [hp]. Changeable only when P0010 = 1 (quick commissioning).		
Note:	Default value is depending on inverter type and its rating data.		

p0308[0...2]	Rated motor cosPhi / Rated mot. cosPhi		
	Access level: 1	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1)	Calculated: -	
	Min 0.000	Max 1.000	Factory setting 0.000
Description:	Nominal motor power factor (cosPhi) from rating plate.		
Dependency:	Changeable only when P0010 = 1 (quick commissioning). Visible only when P0100 = 0 or 2, (motor power entered in [kW]). Setting 0 causes internal calculation of value. The value is displayed in r0332.		

p0309[0...2]	Rated motor efficiency / Rated efficiency		
	Access level: 1	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1)	Calculated: -	
	Min 0.0 [%]	Max 99.9 [%]	Factory setting 0.0 [%]
Description:	Nominal motor efficiency in [%] from rating plate.		
Dependency:	Changeable only when P0010 = 1 (quick commissioning). Visible only when P0100 = 1, (i.e. motor power entered in [hp]). Setting 0 causes internal calculation of value. The value is displayed in r0332.		

p0310[0...2]	Rated motor frequency / Rated motor freq.		
	Access level: 1	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1)	Calculated: -	
	Min 12.00 [Hz]	Max 650.00 [Hz]	Factory setting 50.00 [Hz]
Description:	Nominal motor frequency [Hz] from rating plate.		
Dependency:	Changeable only when P0010 = 1 (quick commissioning).		
Note:	Pole pair number recalculated automatically if parameter is changed. Changes to P0310 can influence the maximum motor frequency. For further information see P1082.		

p0311[0...2]	Rated motor speed / Rated motor speed		
	Access level: 1	P-Group: Motor	Data type: Unsigned16
	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1)	Calculated: -	
	Min 0 [RPM]	Max 40000 [RPM]	Factory setting 1395 [RPM]
Description:	Nominal motor speed [rpm] from rating plate.		
Dependency:	Changeable only when P0010 = 1 (quick commissioning). Setting 0 causes internal calculation of value. Required for vector control and V/f control with speed controller. Slip compensation in V/f control requires rated motor speed for correct operation. Pole pair number recalculated automatically if parameter is changed.		
Note:	Default value is depending on inverter type and its rating data.		


r0313[0...2]	Motor pole pairs / Motor pole pairs		
	Access level: 3	P-Group: Motor	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: DDS
Description:	Displays number of motor pole pairs that the inverter is currently using for internal calculations.		
Dependency:	Recalculated automatically when P0310 (rated motor frequency) or P0311 (rated motor speed) is changed. r0313 = 1 : 2-pole motor r0313 = 2 : 4-pole motor etc.		
p0314[0...2]	Motor pole pair number / Motor pole pair no		
	Access level: 3	P-Group: Motor	Data type: Unsigned16
	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1)	Calculated: -	
	Min 0	Max 99	Factory setting 0
Description:	Specifies number of pole pairs of motor.		
Dependency:	Changeable only when P0010 = 1 (quick commissioning). Setting 0 causes r0313 (calculated motor pole pairs) to be used during operation. Setting to > 0 overrides r0313. P0314 = 1 : 2-pole motor P0314 = 2 : 4-pole motor etc.		
p0320[0...2]	Motor magnetizing current / Motor magnet. cur.		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. YES	Active: YES	Data set: DDS
	Can be changed: C(1), T	Calculated: -	
	Min 0.0 [%]	Max 99.0 [%]	Factory setting 0.0 [%]
Description:	Defines motor magnetization current in [%] relative to P0305 (rated motor current).		
Dependency:	Setting 0 causes calculation by P0340 = 1 (data entered from rating plate) or by P3900 = 1 - 3 (end of quick commissioning). The calculated value is displayed in parameter r0331.		
r0330[0...2]	Rated motor slip / Rated motor slip		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: DDS
Description:	Displays nominal motor slip in [%] relative to P0310 (rated motor frequency) and P0311 (rated motor speed). $r0330[\%] = ((p0310 - r0313 * (p0311 / 60)) / p0310) * 100\%$		
r0331[0...2]	Rated magnetization current / Rated magnet. cur.		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Unit: [A]	Calculated: -	Data set: DDS
Description:	Displays calculated magnetizing current of motor in [A].		
r0332[0...2]	Rated power factor / Rated power factor		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Unit: -	Calculated: -	Data set: DDS
Description:	Displays power factor for motor.		
Dependency:	Value is calculated internally if P0308 (rated motor cosPhi) set to 0; otherwise, value entered in P0308 is displayed.		

r0333[0...2]	Rated motor torque / Rated motor torque		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Unit: [Nm]	Calculated: -	Data set: DDS
Description:	Displays rated motor torque.		
Dependency:	Value is calculated from P0307 (rated motor power) and P0311 (rated motor speed). $r0333[\text{Nm}] = (p0307[\text{kW}] * 1000) / ((p0311[1/\text{min}] / 60) * 2 * \text{Pi})$		
p0335[0...2]	Motor cooling / Motor cooling		
	Access level: 2	P-Group: Motor	Data type: Unsigned16
	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1), T	Calculated: -	
	Min 0	Max 3	Factory setting 0
Description:	Selects motor cooling system used.		
Value:	0: Self-cooled: Shaft mounted fan attached motor (IC410 or IC411) 1: Force-cooled: Separately powered cooling fan (IC416) 2: Self-cooled and internal fan 3: Force-cooled and internal fan		
p0340[0...2]	Calculation of motor parameters / Calc of mot.params		
	Access level: 2	P-Group: Motor	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: T	Calculated: -	
	Min 0	Max 4	Factory setting 0
Description:	Calculates various motor parameters.		
Value:	0: No calculation 1: Complete parameterization 2: Calculation of equivalent circuit data 3: Calculation of V/f and vector control data 4: Calculation of controller settings only		
Note:	<p>This parameter is required during commissioning to optimize inverter performance. If there is a large mismatch in Power ratings of Inverter to Motor it is possible that r0384 and r0386 may not be calculated correct. In these cases use P1910.</p> <p>When transferring parameter p0340, the frequency inverter uses its processor to carry-out internal calculations. Communications - both via USS as well as via the Fieldbus - are interrupted for the time that it takes to make these calculations.</p> <p>This can result in the following error messages at the connected SIMATIC S7 control (communications via fieldbus):</p> <ul style="list-style-type: none"> • Parameter fault 30 • Drive fault 70 • Drive fault 75 <p>When using STARTER (USS) to commission the drive system, data cannot be entered while these calculations are being made.</p> <p>The faults can be acknowledged as soon as the calculations have been completed in the frequency inverter. These calculations can take up to one minute to complete.</p>		

	P0340 = 1	P0340 = 2	P0340 = 3	P0340 = 4
P0341[3] Motor inertia [kg*m^2]	x			
P0342[3] Total/motor inertia ratio	x			
P0344[3] Motor weight	x			
P0346[3] Magnetization time	x		x	
P0347[3] Demagnetization time	x		x	
P0350[3] Stator resistance (line-to-line)	x	x		
P0352[3] Cable resistance	x	x		
P0354[3] Rotor resistance	x	x		
P0356[3] Stator leakage inductance	x	x		
P0358[3] Rotor leakage inductance	x	x		
P0360[3] Main inductance	x	x		
P0362[3] Magnetizing curve flux 1	x	x		
P0363[3] Magnetizing curve flux 2	x	x		
P0364[3] Magnetizing curve flux 3	x	x		
P0365[3] Magnetizing curve flux 4	x	x		
P0366[3] Magnetizing curve imag 1	x	x		
P0367[3] Magnetizing curve imag 2	x	x		
P0368[3] Magnetizing curve imag 3	x	x		
P0369[3] Magnetizing curve imag 4	x	x		
P0492[3] Allowed speed difference	x			
P0494[3] Delay speed loss reaction	x			
P0625[3] Ambient motor temperature	x	x		
P1253[3] Controller output limitation	x		x	
P1316[3] Boost end frequency	x		x	
P1338[3] Resonance damping gain V/f	x		x	x
P1341[3] I _{max} controller integral time	x		x	x
P1345[3] I _{max} voltage ctrl. prop. gain	x		x	x
P1346[3] I _{max} voltage ctrl. integral time	x		x	x
P1460[3] Gain speed controller	x		x	x
P1462[3] Integral time speed controller	x		x	x
P1470[3] Gain speed controller (SLVC)	x		x	x
P1472[3] Integral time n-ctrl. (SLVC)	x		x	x
P1520[3] CO: Upper torque limit	x			
P1521[3] CO: Lower torque limit	x			
P1530[3] Motoring power limitation	x			
P1531[3] Regenerative power limitation	x			
P1715[3] Gain current controller	x		x	x
P1717[3] Integral time current controller	x		x	x
P1764[3] K _p of n-adaption (SLVC)	x		x	x
P1767[3] T _n of n-adaption (SLVC)	x		x	x
P2002[3] Reference current	x			
P2003[3] Reference torque	x			
P2174[3] Torque threshold M_thresh	x			
P2178[3] Delay time for motor pulled out	x		x	
P2185[3] Upper torque threshold 1	x			
P2187[3] Upper torque threshold 2	x			
P2189[3] Upper torque threshold 3	x			

p0341[0...2]	Motor inertia [kg*m²] / Inertia [kg*m²]		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_ALL	
	Min 0.00010	Max 1000.00000	Factory setting 0.00180
Description:	Sets no-load inertia of motor. Together with P0342 (inertia ratio total/motor) and P1496 (scaling factor acceleration), this value produces the acceleration torque (r1518), which can be added to any additional torque produced from a BICO source (P1511), and incorporated in the torque control function.		
Note:	The result of P0341 * P0342 is included in the speed controller calculation. P0341 * P0342 (inertia ratio total/motor) = total motor inertia P1496 (scaling factor acceleration) = 100 % activates acceleration pre-control for the speed controller and calculates the torque from P0341 (motor inertia) and P0342 (inertia ratio total/motor).		
p0342[0...2]	Total/motor inertia ratio / Tot/mot inert.rat.		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_ALL	
	Min 1.000	Max 400.000	Factory setting 1.000
Description:	Specifies ratio between total inertia (load + motor) and motor inertia.		
p0344[0...2]	Motor weight / Motor weight		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_ALL	
	Min 1.0 [kg]	Max 6500.0 [kg]	Factory setting 9.4 [kg]
Description:	Specifies motor weight [kg].		
Note:	This value is used in the motor thermal model. It is normally calculated automatically from P0340 (motor parameters) but can also be entered manually. Default value is depending on inverter type and its rating data.		
r0345[0...2]	Motor start-up time / Mot. start-up time		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Unit: [s]	Calculated: -	Data set: DDS
Description:	Displays motor start-up time. This time corresponds to the standardized motor inertia. The start-up time is the time taken to reach rated motor speed from standstill at acceleration with rated motor torque (r0333).		

p0346[0...2]	Magnetization time / Magnetization time		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_REG	
	Min 0.000 [s]	Max 20.000 [s]	Factory setting 1.000 [s]
Description:	Sets magnetization time [s], i.e. waiting time between pulse enable and start of ramp-up. Motor magnetization builds up during this time. Magnetization time is normally calculated automatically from the motor data and corresponds to the rotor time constant.		
Notice:	An excessive reduction of this time can result in insufficient motor magnetization.		
Note:	If boost settings are higher than 100 %, magnetization time may be reduced. Default value is depending on inverter type and its rating data.		
p0347[0...2]	Demagnetization time / Demagnet. time		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_REG	
	Min 0.000 [s]	Max 20.000 [s]	Factory setting 1.000 [s]
Description:	Changes time allowed after OFF2 / fault condition, before pulses can be re-enabled.		
Notice:	Not active following a normally completed ramp-down, e.g. after OFF1, OFF3 or JOG. Overcurrent trips will occur if the time is decreased excessively.		
Note:	The demagnetization time is approximately 2.5 x rotor time constant in seconds. Default value is depending on inverter type and its rating data.		
p0350[0...2]	Stator resistance (line) / Stator res. (L)		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_EQU	
	Min 0.00001 [Ohm]	Max 2000.00000 [Ohm]	Factory setting 2.00000 [Ohm]
Description:	Stator resistance value in [Ohms] for connected motor (line value). The parameter value doesn't include the cable resistance.		
Note:	There are three ways to determine the value for this parameter: <ol style="list-style-type: none"> Calculate using <ul style="list-style-type: none"> - P0340 = 1 (data entered from rating plate) or - P0010 = 1, P3900 = 1, 2 or 3 (end of quick commissioning). Measure using P1900 = 2 (standard motor data identification - value for stator resistance is overwritten). Measure using P1900 = 3 (complete motor data identification - same like setting 2; additional detection of the saturation curve) Measure manually using an Ohmmeter. <p>Since the manually measured resistor is a line-to-line value, which includes the cable resistors, the measured value has to be divided by two and the cable resistor of a line has to be subtracted from that value. The value entered in P0350 (stator resistance) is the one obtained by the method last used. Default value is depending on inverter type and its rating data.</p>		


p0352[0...2]	Cable resistance / Cable resistance		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_EQU	
	Min 0.0 [Ohm]	Max 120.0 [Ohm]	Factory setting 0.0 [Ohm]
Description:	Describes cable resistance between inverter and motor for one phase. The value corresponds to the resistance of the cable between the inverter and the motor, relative to the rated impedance.		
p0354[0...2]	Rotor resistance / Rotor resistance		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_EQU	
	Min 0.0 [Ohm]	Max 300.0 [Ohm]	Factory setting 10.0 [Ohm]
Description:	Sets rotor resistance of motor equivalent circuit (phase value).		
Dependency:	Calculated automatically using the motor model or determined using P1900 (motor identification).		
p0356[0...2]	Stator leakage inductance / Stator leak.induct		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_EQU	
	Min 0.00001	Max 1000.00000	Factory setting 10.00000
Description:	Sets stator leakage inductance [mH] of motor equivalent circuit (phase value).		
Dependency:	Calculated automatically using the motor model or determined using P1900 (motor identification).		
p0358[0...2]	Rotor leakage inductance / Rotor leak.induct.		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_EQU	
	Min 0.0	Max 1000.0	Factory setting 10.0
Description:	Sets rotor leakage inductance [mH] of motor equivalent circuit (phase value).		
Dependency:	Calculated automatically using the motor model or determined using P1900 (motor identification).		
p0360[0...2]	Main inductance / Main inductance		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_EQU	
	Min 0.0	Max 10000.0	Factory setting 10.0
Description:	Sets main inductance [mH] of the motor equivalent circuit (phase value).		
Dependency:	Calculated automatically using the motor model or determined using P1900 (motor identification).		
Caution:	The data of equivalent circuit relates to the star equivalent circuit. Any data of the delta equivalent circuit available, therefore must be transformed to the star equivalent circuit before entering into the inverter.		
			

p0362[0...2]	Magnetizing curve flux 1 / Magnet.curve flux1		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_EQU	
	Min 20.0 [%]	Max 200.0 [%]	Factory setting 60.0 [%]
Description:	Specifies first flux value of saturation characteristic in [%] relative to rated motor voltage (P0304). The saturation characteristic is defined using 4 points (P0362 - P0365, P0366 - P0369). This parameter specifies the y coordinate (flux) for the first value pair of the characteristic.		
Dependency:	The following applies for the flux values: P0362 < P0363 < P0364 < P0365, otherwise a linear characteristic is applied internally.		
Note:	P0362 = 100 % corresponds to rated motor flux. Rated flux = rated EMF		
p0363[0...2]	Magnetizing curve flux 2 / Magnet.curve flux2		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_EQU	
	Min 20.0 [%]	Max 200.0 [%]	Factory setting 85.0 [%]
Description:	Specifies second flux value of saturation characteristic in [%] relative to rated motor voltage (P0304). The saturation characteristic is defined using 4 points (P0362 - P0365, P0366 - P0369). This parameter specifies the y coordinate (flux) for the second value pair of the characteristic.		
Dependency:	The following applies for the flux values: P0362 < P0363 < P0364 < P0365, otherwise a linear characteristic is applied internally.		
Note:	P0363 = 100 % corresponds to rated motor flux. Rated flux = rated EMF		
p0364[0...2]	Magnetizing curve flux 3 / Magnet.curve flux3		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_EQU	
	Min 20.0 [%]	Max 200.0 [%]	Factory setting 115.0 [%]
Description:	Specifies third flux value of saturation characteristic in [%] relative to rated motor voltage (P0304). The saturation characteristic is defined using 4 points (P0362 - P0365, P0366 - P0369). This parameter specifies the y coordinate (flux) for the third value pair of the characteristic. Specifies third flux value of saturation characteristic in [%] relative to rated motor voltage (P0304). The saturation characteristic is defined using 4 points. This parameter specifies the y coordinate (flux) for the third value pair.		
Dependency:	The following applies for the flux values: P0362 < P0363 < P0364 < P0365, otherwise a linear characteristic is applied internally.		
Note:	P0364 = 100 % corresponds to rated motor flux. Rated flux = rated EMF		

p0365[0...2]	Magnetizing curve flux 4 / Magnet.curve flux4		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_EQU	
	Min 20.0 [%]	Max 200.0 [%]	Factory setting 125.0 [%]
Description:	Specifies fourth flux value of saturation characteristic in [%] relative to rated motor voltage (P0304). The saturation characteristic is defined using 4 points (P0362 - P0365, P0366 - P0369). This parameter specifies the y coordinate (flux) for the fourth value pair of the characteristic.		
Dependency:	The following applies for the flux values: P0362 < P0363 < P0364 < P0365, otherwise a linear characteristic is applied internally.		
Note:	P0365 = 100 % corresponds to rated motor flux. Rated flux = rated EMF		
p0366[0...2]	Magnetizing curve imag 1 / Magnet.curve imag1		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_EQU	
	Min 20.0 [%]	Max 250.0 [%]	Factory setting 50.0 [%]
Description:	Specifies first magnetizing current value of the saturation characteristic in [%] relative to the rated magnetizing current (P0331). The saturation characteristic is defined using 4 points (P0362 - P0365, P0366 - P0369). This parameter specifies the x coordinate (magnetizing current) for the first value pair of the characteristic.		
Dependency:	Affects P0320 (motor magnetizing current). The following applies for the magnetizing currents: P0366 < P0367 < P0368 < P0369, otherwise a linear characteristic is applied internally.		
p0367[0...2]	Magnetizing curve imag 2 / Magnet.curve imag2		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_EQU	
	Min 20.0 [%]	Max 250.0 [%]	Factory setting 75.0 [%]
Description:	Specifies second magnetizing current value of the saturation characteristic in [%] relative to rated magnetizing current (P0331). The saturation characteristic is defined using 4 points (P0362 - P0365, P0366 - P0369). This parameter specifies the x coordinate (magnetizing current) for the second value pair of the characteristic.		
Dependency:	Affects P0320 (motor magnetizing current). The following applies for the magnetizing currents: P0366 < P0367 < P0368 < P0369, otherwise a linear characteristic is applied internally.		

p0368[0...2]	Magnetizing curve imag 3 / Magnet.curve imag3		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_EQU	
	Min 20.0 [%]	Max 250.0 [%]	Factory setting 135.0 [%]
Description:	Specifies third magnetizing current value of the saturation characteristic in [%] relative to rated magnetizing current (P0331). The saturation characteristic is defined using 4 points (P0362 - P0365, P0366 - P0369). This parameter specifies the x coordinate (magnetizing current) for the third value pair of the characteristic.		
Dependency:	Affects P0320 (motor magnetizing current). The following applies for the magnetizing currents: P0366 < P0367 < P0368 < P0369, otherwise a linear characteristic is applied internally.		
p0369[0...2]	Magnetizing curve imag 4 / Magnet.curve imag4		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_EQU	
	Min 20.0 [%]	Max 250.0 [%]	Factory setting 170.0 [%]
Description:	Specifies fourth magnetizing current value of the saturation characteristic in [%] relative to rated magnetizing current (P0331). The saturation characteristic is defined using 4 points (P0362 - P0365, P0366 - P0369). This parameter specifies the x coordinate (magnetizing current) for the fourth value pair of the characteristic.		
Dependency:	Affects P0320 (motor magnetizing current). The following applies for the magnetizing currents: P0366 < P0367 < P0368 < P0369, otherwise a linear characteristic is applied internally.		
r0370[0...2]	Stator resistance [%] / Stator res. [%]		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: DDS
Description:	Displays standardized stator resistance of motor equivalent circuit (phase value) in [%].		
r0372[0...2]	Cable resistance [%] / Cable res. [%]		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: DDS
Description:	Displays standardized cable resistance of motor equivalent circuit (phase value) in [%]. It is estimated to be 20 % of the stator resistance.		
r0373[0...2]	Rated stator resistance [%] / Rated stat.res.[%]		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: DDS
Description:	Displays rated stator resistance of the motor equivalent circuit (phase value) in [%].		
r0374[0...2]	Rotor resistance [%] / Rotor res. [%]		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: DDS
Description:	Displays standardized rotor resistance of the motor equivalent circuit (phase value) in [%].		

r0376[0...2]	Rated rotor resistance [%] / Rated rot. res. [%]		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: DDS
Description:	Displays rated rotor resistance of the motor equivalent circuit (phase value) in [%].		
r0377[0...2]	Total leakage reactance [%] / Tot.leak.react. [%]		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: DDS
Description:	Displays standardized total leakage reactance of the motor equivalent circuit (phase value) in [%].		
Note:	If an output filter is selected the inductance of the filter (p0233) is added to the leakage inductance (the value is not stored in p0233 for Siemens filters).		
r0382[0...2]	Main reactance [%] / Main reactance [%]		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: DDS
Description:	Displays standardized main reactance of the motor equivalent circuit (phase value) in [%].		
r0384[0...2]	Rotor time constant / Rotor time const.		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Unit: [ms]	Calculated: -	Data set: DDS
Description:	Displays calculated rotor time constant [ms].		
r0386[0...2]	Total leakage time constant / Total leak. Tconst		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Unit: [ms]	Calculated: -	Data set: DDS
Description:	Displays total leakage time constant of motor.		
r0394	CO: Stator resistance IGBT [%] / Stat. res.IGBT		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays stator resistance calculated in [%] from IGBT ON voltage and current amplitude.		
r0395	CO: Total stator resistance [%] / Total stat.res		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays stator resistance of motor as [%] of combined stator/cable resistance.		
r0396	CO: Act. rotor resistance / Act rotor res.		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays (adapted) rotor resistance of the motor equivalent circuit (phase value) in [%].		
Notice:	Values greater than 25 % tend to produce excessive motor slip. Check rated motor speed [rpm] value (P0311).		

p0400[0...2] Select encoder type / Select enc. type			
CU240S	Access level: 2	P-Group: Encoder	Data type: Unsigned16
CU240S DP	Quick comm. YES	Active: YES	Data set: DDS
CU240S DP-F	Can be changed: C(1), T	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min	Max	Factory setting
	0	12	0
Description:	Selects encoder type (number of encoder channels).		
Value:	0: Disabled 2: Quadrature encoder without zero pulse 12: Quadrature encoder with zero pulse		
Caution:	 <p>When using Vector Control with encoder-feedback, the direction of rotation of the encoder and motor must be the same. If this is not achieved, then the functional operation of the Vector Control will not be guaranteed (positive instead of negative feedback).</p> <p>Extreme care must therefore be taken with respect to the connection of the motor to the inverter as well as the correct connection of the encoder to the inverter. Motor and encoder must not be incorrectly wired up !</p> <p>P0400 = 12 (quadrature encoder and zero pulse) will not detect encoder loss on Zero pulse. Zero pulse is only used to synchronise measured angle.</p>		
Note:	<p>If the encoder is enabled (P0400 > 0) and the motor holding brake is enabled (P1215 > 0), then the following should be observed in order to stop encoder loss trips when the brake is applied:</p> <ul style="list-style-type: none"> • The delay speed loss reaction should be > brake holding times (i.e. P0494 > P1216 and P0494 > P1217) • The delay time for motor pulled out should be > brake holding times (i.e. P2178 > P1216 and P2178 > P1217) • The allowed speed difference P0492 should be > f_min P1080 		

r0403.0...4 CO/BO: Encoder status word / Enc. StatWd					
CU240S	Access level: 2	P-Group: Commands	Data type: Unsigned16		
CU240S DP	Unit: -	Calculated: -	Data set: -		
CU240S DP-F					
CU240S PN					
CU240S PN-F					
Description:	Displays status word of encoder (in bit format).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Encoder active	Yes	No	-
	01	Encoder error	Yes	No	-
	02	Signal o.k.	Yes	No	-
	03	Encoder Low Speed Loss	Yes	No	-
	04	Speed measurement using one encoder pulse edge	Yes	No	-

p0405[0...2] Enables selection of pulse types / Enables pulse type			
CU240S	Access level: 2	P-Group: Converter	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: YES	Data set: DDS
CU240S DP-F	Can be changed: T	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min	Max	Factory setting
	-	-	0000 bin
Description:	Enables selection of various pulse types.		

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	not used	Yes	No	-
	01	not used	Yes	No	-
	02	not used	Yes	No	-
	03	not used	Yes	No	-
	04	invert Z-pulse	Yes	No	-
	05	Z-pulse = Z-pulse & A-pulse & B-pulse	Yes	No	-
	06	not used	Yes	No	-
	07	not used	Yes	No	-
	08	not used	Yes	No	-

p0408[0...2] Encoder pulses per revolution / Enc pulses per rev

CU240S	Access level: 2	P-Group: Encoder	Data type: Unsigned16
CU240S DP	Quick comm. YES	Active: YES	Data set: DDS
CU240S DP-F	Can be changed: C(1), T	Calculated: -	
CU240S PN			
CU240S PN-F			

Min	Max	Factory setting
2	20000	1024

Description: Specifies the number of encoder pulses per revolution.

Note: The encoder resolution (pulses per revolution P0408) which may be entered will be limited by the max. pulse frequency of the encoder circuits ($f_{max} = 300 \text{ kHz}$).

The following equation calculates the encoder frequency depending on the encoder resolution and the rotational speed (rpm). The encoder frequency has to be less than the max. pulse frequency:

$$f_{max} > f = (p0408 * \text{rpm}) / 60$$

p0410[0...2] Reverses internal direction sense / Rev dir sense

CU240S	Access level: 2	P-Group: Encoder	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: YES	Data set: DDS
CU240S DP-F	Can be changed: T	Calculated: -	
CU240S PN			
CU240S PN-F			

Min	Max	Factory setting
0	1	0


Description: Reverses internal direction sense of the encoder signal. This does the same thing as switching the ENC_A and ENC_B signals.


Value:
 0: Encoder Normal Rotation
 1: Encoder Reverse Rotation

r0485 CO: Encoder counter value / Encoder count val.

CU240S	Access level: 2	P-Group: Closed-loop control	Data type: Unsigned32
CU240S DP	Unit: -	Calculated: -	Data set: -
CU240S DP-F			
CU240S PN			
CU240S PN-F			

Description: Shows the internal counter value of the encoder pulses.

p0491[0...2] Reaction on speed signal loss / Select enc. type			
CU240S	Access level: 2	P-Group: Encoder	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: NO	Data set: DDS
CU240S DP-F	Can be changed: T	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min 0	Max 1	Factory setting 0
Description:	Selects reaction on loss of speed signal.		
Value:	0: Trip the drive 1: Warn and switch to SLVC if in VC		
p0492[0...2] Allowed speed difference / Allowed speed dif			
CU240S	Access level: 2	P-Group: Encoder	Data type: FloatingPoint32
CU240S DP	Quick comm. NO	Active: YES	Data set: DDS
CU240S DP-F	Can be changed: T	Calculated: CALC_MOD_ALL	
CU240S PN			
CU240S PN-F			
	Min 0.00 [Hz]	Max 100.00 [Hz]	Factory setting 10.00 [Hz]
Description:	Parameter P0492 is used for high and low speed encoder loss detection (fault: F0090). High speed encoder loss detection: This condition occurs when the allowed frequency and the allowed difference of the speed signals between samples, set in P0492 is exceeded. <ul style="list-style-type: none"> • f_{act} and $f(t_2) - f(t_1) > P0492$ Low speed encoder loss detection: This condition occurs when the actual frequency is $< P0492$ when encoder loss occurs. <ul style="list-style-type: none"> • Condition 1: <ul style="list-style-type: none"> - $r0061 = 0$ and torque limit and then - $r0061 = 0$ with setpoint frequency > 0 for time $> P0494$ • Condition 2: <ul style="list-style-type: none"> - Act. freq. $< P0492$ and $f(t_2) < P0492$ and ASIC detects channel B loss 		
Dependency:	This parameter is updated when motor start-up time P0345 is changed or when a speedloop optimisation is performed (P1960 = 1). There is a fixed delay of 40 ms before acting upon loss of encoder at high speeds. P0492 = 0 (disabled):		
Caution:	 <p>When allowed speed difference is set to 0, both the high speed and low speed encoder loss detection are disabled, thus encoder loss will not be detected. If encoder loss detection is disabled and encoder loss occurs, then operation of the motor may become unstable. Consideration also needs to be given to drive operation when the drive is operating in vector speed control or vector torque control mode (P1300 = 21, 23) and the drive attempts to start the motor while it has a failed encoder. Under these circumstances, the drive uses parameters P1520 and P1521 (the upper and lower torque limits respectively) to decide when to trip. In the case of a very low frequency set point, it may take the drive a considerable period to reach this condition, during which time the drive can lose orientation.</p>		
Note:	If the encoder is enabled (P0400 > 0) and the motor holding brake is enabled (P1215 > 0) then in order to stop encoder loss trips when the brake is applied, the allowed speed difference P0492 should be $> f_{min}$ (P1080). The Factory setting depends on motor power.		

p0494[0...2] Delay speed loss reaction / Dly speed loss rec			
CU240S	Access level: 2	P-Group: Encoder	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: NO	Data set: DDS
CU240S DP-F	Can be changed: U, T	Calculated: CALC_MOD_ALL	
CU240S PN			
CU240S PN-F			
	Min 0 [ms]	Max 65000 [ms]	Factory setting 10 [ms]
Description:	This parameter is used for low speed encoder loss detection. It selects the delay between loss of encoder at low speed and reaction to the encoder loss. If the motor shaft speed is less than P0492 then encoder loss is detected using a low speed encoder loss detection algorithm.		
Dependency:	This parameter is updated when motor start-up time P0345 is changed or when a speedloop optimisation is performed (P1960 = 1).		
Caution:	P0494 = 0 (disabled): When the delay in P0494 is set to 0, then low speed encoder loss detection is disabled and low speed encoder loss cannot be detected (high speed encoder loss detection will still operate if P0492 > 0). If low speed encoder loss detection is disabled and encoder should be lost at low speed, then operation of motor may become unstable.		
			
Note:	If the encoder is enabled (P0400 > 0) and the motor holding brake is enabled (P1215 > 0), then in order to stop encoder loss trips when the brake is applied, the delay speed loss reaction should be > brake holding times (i.e. P0494 > P1216 and P494 > P1217). The Factory setting depends on motor power.		

p0500[0...2] Technological application / Techn. application			
	Access level: 3	P-Group: Applications	Data type: Unsigned16
	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1), T	Calculated: -	
	Min 0	Max 1	Factory setting 0
Description:	Selects technological application. Sets control mode (P1300).		
Value:	0: High overload 1: Pumps and fans		
Dependency:	See parameter P0205.		

p0601[0...2] Motor temperature sensor / Motor temp. sensor			
CU240E	Access level: 2	P-Group: Motor	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0	Max 4	Factory setting 0
Description:	Selects motor temperature sensor.		
Value:	0: No sensor 1: PTC thermistor 2: KTY84 4: ThermoClick sensor		
Dependency:	The motor overheating warning threshold needs to be assigned with parameter P0604 (factory setting: 130 °C). This warning threshold depends on the motor's thermal class. The motor overheating disturbance threshold is automatically set by the inverter at 10 % higher than the temperature declared in parameter P0604. In parameter P0610 is set, how the inverter reacts on overtemperature.		
Note:	<ul style="list-style-type: none"> • P0601 = 0 (No sensor) The motor temperature monitoring will be done based on the estimated value of the thermal motor model. • P0601 = 1 (PTC thermistor) The motor is monitored by the thermal motor model and additionally by the PTC thermistor, thus providing a redundant system for monitoring the motor temperature. Should the resistance value of 2000 Ohm be exceeded, the inverter trips with fault F0011 (motor overheating). If the resistance value is below 10 Ohm, then the fault F0015 (motor temperature signal lost) is output. This protects the motor from overheating and also from a sensor wire breakage. 		

p0601[0...2] Motor temperature sensor / Motor temp. sensor			
CU240S	Access level: 2	P-Group: Motor	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: NO	Data set: DDS
CU240S DP-F	Can be changed: U, T	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min 0	Max 4	Factory setting 0
Description:	Selects motor temperature sensor.		
Value:	0: No sensor 1: PTC thermistor 2: KTY84 4: ThermoClick sensor		
Dependency:	The motor overheating warning threshold needs to be assigned with parameter P0604 (factory setting: 130 °C). This warning threshold depends on the motor's thermal class. The motor overheating disturbance threshold is automatically set by the inverter at 10 % higher than the temperature declared in parameter P0604. In parameter P0610 is set, how the inverter reacts on overtemperature.		
Note:	<ul style="list-style-type: none"> • P0601 = 0 (No sensor) The motor temperature monitoring will be done based on the estimated value of the thermal motor model. • P0601 = 1 (PTC thermistor) The motor is monitored by the thermal motor model and additionally by the PTC thermistor, thus providing a redundant system for monitoring the motor temperature. Should the resistance value of 2000 Ohm be exceeded, the inverter trips with fault F0011 (motor overheating). If the resistance value is below 10 Ohm, then the fault F0015 (motor temperature signal lost) is output. This protects the motor from overheating and also from a sensor wire breakage. • P0601 = 2 (KTY84) The temperature of the sensor (thus that of the motor windings) is written to parameter r0035. This motor temperature is then additionally calculated via the thermal motor model. If the electric circuit to the KTY84 sensor is open or if a short circuit occurs, fault F0015 (motor temperature signal lost) is generated. • P0601 = 4 (ThermoClick sensor) The motor is monitored by the thermal motor model and additionally by the ThermoClick sensor, thus providing a redundant system for monitoring the motor temperature. Should the resistance value of 2000 Ohm be exceeded, the inverter trips with fault F0011 (motor overheating). This protects the motor from overheating and also from a sensor wire breakage. 		
p0604[0...2] Threshold motor temperature / Thresh. mot. temp.			
	Access level: 2	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [°C]	Max 200.0 [°C]	Factory setting 130.0 [°C]
Description:	Enters warning threshold for motor temperature protection. The trip temperature defined is always 10 % higher than the warning threshold P0604. When actual motor temperature exceeds trip temperature then inverter trips as defined in P0610.		
Dependency:	This value should be at least 40°C higher than the motor ambient temperature P0625.		
Note:	Default value depends on P0300 (select motor type).		

p0610[0...2]	Motor I2t temperature reaction / I2t temp. reaction		
	Access level: 3	P-Group: Motor	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: T	Calculated: -	
	Min 0	Max 2	Factory setting 2
Description:	Defines reaction when motor temperature reaches warning threshold.		
Value:	0: No reaction, warning only 1: Warning and I _{max} reduction (result: red. freq., trip (F0011)) 2: Warning and trip (F0011)		
Dependency:	Trip level = P0604 (motor temperature threshold) * 110 %		
Note:	The purpose of motor I2t is to calculate or measure (KTY84) the motor temperature and disable the inverter if the motor is in danger of overheating. I2t operation: The measured motor current is displayed in r0027. The motor temperature in °C is displayed in r0035. This temperature is derived either from a KTY84 temperature sensor mounted in the motor, or from a calculated value. The value from the KTY84 is used only when P0601 = 2; in all other cases (including motor temperature signal lost) the calculated value is used. The reaction to the warning can be changed from this default using P0610. Parameter r0035 is particularly useful to monitor if the calculated motor temperature is rising excessively.		
p0621[0...2]	Motor temp. ident after restart / Mot.temp ident.		
	Access level: 2	P-Group: Motor	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0	Max 2	Factory setting 0
Description:	Starts the motor temperature identification after power on or start up.		
Value:	0: No identification 1: Temperature identification only after power on 2: Temperature identification after every power on		
Note:	It is necessary to run the motor data identification before using the motor temperature identification. If that wasn't done the results of the motor temperature identifications are wrong.		
p0622[0...2]	Magnetizing time for temp id after start up / Magnet. t temp id		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.000 [ms]	Max 20000.000 [ms]	Factory setting 0.000 [ms]
Description:	Specifies the magnetization time for stator resistance identification.		
Note:	This parameter will be set as a result of the motor data identification according to the identified rotor time constant r1913.		
r0623[0...2]	CO: Display for the identified stator resistance / Act. stator resist		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Unit: [Ohm]	Calculated: -	Data set: DDS
Description:	Display of the actual identified stator resistance after temperature identification.		

p0625[0...2]	Ambient motor temperature / Ambient mot. temp.		
	Access level: 3	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. YES	Active: YES	Data set: DDS
	Can be changed: C(1), U, T	Calculated: CALC_MOD_EQU	
	Min -40.0 [°C]	Max 80.0 [°C]	Factory setting 20.0 [°C]
Description:	Ambient temperature of motor at time of motor data identification. It is only allowed to change the value when the motor is cold. A motor identification has to be made after changing the value.		

p0626[0...2]	Overtemperature stator iron / Overtemp.stat.iron		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 20.0 [°C]	Max 200.0 [°C]	Factory setting 50.0 [°C]
Description:	Overtemperature of stator iron.		
Note:	Temperature rises are valid for sinusoidal operations (line supply temperature rises). Temperature rises due to converter operation (modulation losses) and output filter are also considered.		

p0627[0...2]	Overtemperature stator winding / Overtemp.stat.wind		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 20.0 [°C]	Max 200.0 [°C]	Factory setting 80.0 [°C]
Description:	Overtemperature of the stator winding. It is only allowed to change the value when the motor is cold. A motor identification has to be made after changing the value.		
Note:	Temperature rises are valid for sinusoidal operations (line supply temperature rises). Temperature rises due to converter operation (modulation losses) and output filter are also considered.		

p0628[0...2]	Overtemperature rotor winding / Overtemp.rot. wind		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 20.0 [°C]	Max 200.0 [°C]	Factory setting 100.0 [°C]
Description:	Overtemperature of the rotor winding.		
Note:	Temperature rises are valid for sinusoidal operations (line supply temperature rises). Temperature rises due to converter operation (modulation losses) and output filter are also considered.		

r0630[0...2]	CO: Motor model ambient temperature / Mot. model amb. te		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Unit: [°C]	Calculated: -	Data set: DDS
Description:	Displays ambient temperature of motor mass model.		

r0631[0...2]	CO: Stator iron temperature / Stat.iron temp		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Unit: [°C]	Calculated: -	Data set: DDS
Description:	Displays iron temperature of motor mass model.		
r0632[0...2]	CO: Stator winding temperature / Stat.wind.temp		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Unit: [°C]	Calculated: -	Data set: DDS
Description:	Displays stator winding temperature of motor mass model.		
r0633[0...2]	CO: Rotor winding temperature / Rot. wind.temp		
	Access level: 4	P-Group: Motor	Data type: FloatingPoint32
	Unit: [°C]	Calculated: -	Data set: DDS
Description:	Displays rotor winding temperature of motor mass model.		
p0640[0...2]	Motor overload factor [%] / Motor ovl fact [%]		
	Access level: 2	P-Group: Motor	Data type: FloatingPoint32
	Quick comm. YES	Active: YES	Data set: DDS
	Can be changed: C(1), U, T	Calculated: -	
	Min 10.0 [%]	Max 400.0 [%]	Factory setting 200.0 [%]
Description:	Defines motor overload current limit in [%] relative to P0305 (rated motor current).		
Dependency:	Limited to maximum inverter current or to 400 % of rated motor current (P0305), whichever is the lower. p0640_max = (min(r0209, 4 * p0305) / p0305) * 100		
Note:	Changes to P640 will be effective only after the next off state. See function diagram for current limitation.		

p0700[0...2] Selection of command source / Command source sel			
CU240E	Access level: 1	P-Group: Commands	Data type: Unsigned16
CU240S	Quick comm. YES	Active: NO	Data set: CDS
	Can be changed: C(1), T	Calculated: -	
	Min 0	Max 5	Factory setting 2
Description:	Selects digital command source.		
Value:	0: Factory default setting 1: BOP (keypad) 2: Terminal 4: USS on RS232 5: USS on RS485		
Dependency:	Changing this parameter sets (to default) all settings on item selected. These are the following parameters: P0701, ... (function of DI), P0731, P0732, P0733, P0800, P0801, P0840, P0842, P0844, P0845, P0848, P0849, P0852, P1020, P1021, P1022, P1023, P1035, P1036, P1055, P1056, P1074, P1110, P1113, P1124, P1140, P1141, P1142, P1230, P1477, P1501, P2103, P2104, P2106, P2200, P2220, P2221, P2222, P2223, P2226, P2228, P2235, P2236		
Caution:	Be aware, by changing of parameter P0700 all BI parameters are reset to the default value.		



p0700[0...2] Selection of command source / Command source sel			
CU240S DP	Access level: 1	P-Group: Commands	Data type: Unsigned16
CU240S DP-F	Quick comm. YES	Active: NO	Data set: CDS
CU240S PN	Can be changed: C(1), T	Calculated: -	
CU240S PN-F	Min 0	Max 6	Factory setting 6
Description:	Selects digital command source.		
Value:	0: Factory default setting 1: BOP (keypad) 2: Terminal 4: USS on RS232 6: Fieldbus		
Dependency:	Changing this parameter sets (to default) all settings on item selected. These are the following parameters: P0701, ... (function of DI), P0731, P0732, P0733, P0800, P0801, P0840, P0842, P0844, P0845, P0848, P0849, P0852, P1020, P1021, P1022, P1023, P1035, P1036, P1055, P1056, P1074, P1110, P1113, P1124, P1140, P1141, P1142, P1230, P1477, P1501, P2103, P2104, P2106, P2200, P2220, P2221, P2222, P2223, P2226, P2228, P2235, P2236		
Caution:	Be aware, by changing of parameter P0700 all BI parameters are reset to the default value.		



p0701[0...2]	Function of digital input 0 / Function of DI0		
CU240E	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S	Quick comm. NO	Active: NO	Data set: CDS
PM240	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	0	99	1
Description:	Selects function of digital input 0.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 25: DC brake enable 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Dependency:	Setting 99 (enable BICO parameterization) requires: <ul style="list-style-type: none"> • P0700 command source or • P0010 = 1, P3900 = 1, 2 or 3 (quick commissioning) or • P0010 = 30, P0970 = 1 factory reset in order to reset 		
Note:	"ON/OFF1" can only be selected for one digital input (e.g. P0700 = 2 and P0701 = 1). Configuring DI1 with P0702 = 1 will disable DI0 by setting P0701 = 0. Only the last activated digital input serves as a command source. "ON/OFF1" on a digital input can be combined with "ON reverse/OFF1" on another digital input.		

p0701[0...2]	Function of digital input 0 / Function of DI0		
CU240E	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S	Quick comm. NO	Active: NO	Data set: CDS
PM250, PM260	Can be changed: T	Calculated: -	
	Min 0	Max 99	Factory setting 1
Description:	Selects function of digital input 0.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Dependency:	Setting 99 (enable BICO parameterization) requires: <ul style="list-style-type: none"> • P0700 command source or • P0010 = 1, P3900 = 1, 2 or 3 (quick commissioning) or • P0010 = 30, P0970 = 1 factory reset in order to reset 		
Note:	"ON/OFF1" can only be selected for one digital input (e.g. P0700 = 2 and P0701 = 1). Configuring DI1 with P0702 = 1 will disable DI0 by setting P0701 = 0. Only the last activated digital input serves as a command source. "ON/OFF1" on a digital input can be combined with "ON reverse/OFF1" on another digital input.		

p0701[0...2] Function of digital input 0 / Function of DI0			
CU240S DP	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
CU240S PN	Can be changed: T	Calculated: -	
CU240S PN-F			
PM240			
	Min 0	Max 99	Factory setting 0
Description:	Selects function of digital input 0.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 25: DC brake enable 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Dependency:	Setting 99 (enable BICO parameterization) requires: <ul style="list-style-type: none"> • P0700 command source or • P0010 = 1, P3900 = 1, 2 or 3 (quick commissioning) or • P0010 = 30, P0970 = 1 factory reset in order to reset 		
Note:	"ON/OFF1" can only be selected for one digital input (e.g. P0700 = 2 and P0701 = 1). Configuring DI1 with P0702 = 1 will disable DI0 by setting P0701 = 0. Only the last activated digital input serves as a command source. "ON/OFF1" on a digital input can be combined with "ON reverse/OFF1" on another digital input.		

p0701[0...2] Function of digital input 0 / Function of DI0			
CU240S DP	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
CU240S PN	Can be changed: T	Calculated: -	
CU240S PN-F			
PM250, PM260			
	Min 0	Max 99	Factory setting 0
Description:	Selects function of digital input 0.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Dependency:	Setting 99 (enable BICO parameterization) requires: <ul style="list-style-type: none"> • P0700 command source or • P0010 = 1, P3900 = 1, 2 or 3 (quick commissioning) or • P0010 = 30, P0970 = 1 factory reset in order to reset 		
Note:	"ON/OFF1" can only be selected for one digital input (e.g. P0700 = 2 and P0701 = 1). Configuring DI1 with P0702 = 1 will disable DI0 by setting P0701 = 0. Only the last activated digital input serves as a command source. "ON/OFF1" on a digital input can be combined with "ON reverse/OFF1" on another digital input.		

p0702[0...2] Function of digital input 1 / Function of DI1			
CU240E	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S	Quick comm. NO	Active: NO	Data set: CDS
PM240	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	0	99	12
Description:	Selects function of digital input 1.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 25: DC brake enable 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input0).		

p0702[0...2] Function of digital input 1 / Function of DI1			
CU240E	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S	Quick comm. NO	Active: NO	Data set: CDS
PM250, PM260	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	0	99	12
Description:	Selects function of digital input 1.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input0).		

p0702[0...2] Function of digital input 1 / Function of DI1			
CU240S DP	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
CU240S PN	Can be changed: T	Calculated: -	
CU240S PN-F			
PM240			
	Min 0	Max 99	Factory setting 0
Description:	Selects function of digital input 1.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 25: DC brake enable 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input0).		

p0702[0...2] Function of digital input 1 / Function of DI1			
CU240S DP	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
CU240S PN	Can be changed: T	Calculated: -	
CU240S PN-F			
PM250, PM260			
	Min 0	Max 99	Factory setting 0
Description:	Selects function of digital input 1.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input0).		

p0703[0...2] Function of digital input 2 / Function of DI2			
PM240	Access level: 2	P-Group: Commands	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min 0	Max 99	Factory setting 9
Description:	Selects function of digital input 2.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 25: DC brake enable 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0).		

p0703[0...2] Function of digital input 2 / Function of DI2			
PM250	Access level: 2	P-Group: Commands	Data type: Unsigned16
PM260	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min 0	Max 99	Factory setting 9
Description:	Selects function of digital input 2.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0).		

p0704[0...2] Function of digital input 3 / Function of DI3			
PM240	Access level: 2	P-Group: Commands	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min 0	Max 99	Factory setting 15
Description:	Selects function of digital input 3.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 25: DC brake enable 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0).		

p0704[0...2] Function of digital input 3 / Function of DI3			
PM250	Access level: 2	P-Group: Commands	Data type: Unsigned16
PM260	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min 0	Max 99	Factory setting 15
Description:	Selects function of digital input 3.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0).		

p0705[0...2] Function of digital input 4 / Function of DI4			
PM240	Access level: 2	P-Group: Commands	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	0	99	16
Description:	Selects function of digital input 4.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 25: DC brake enable 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0).		

p0705[0...2] Function of digital input 4 / Function of DI4			
PM250	Access level: 2	P-Group: Commands	Data type: Unsigned16
PM260	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	0	99	16
Description:	Selects function of digital input 4.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0).		

p0706[0...2] Function of digital input 5 / Function of DI5			
PM240	Access level: 2	P-Group: Commands	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min 0	Max 99	Factory setting 17
Description:	Selects function of digital input 5.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 25: DC brake enable 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0).		

p0706[0...2] Function of digital input 5 / Function of DI5			
PM250	Access level: 2	P-Group: Commands	Data type: Unsigned16
PM260	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min 0	Max 99	Factory setting 17
Description:	Selects function of digital input 5.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0).		

p0707[0...2] Function of digital input 6 / Function of DI6			
CU240S	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: NO	Data set: CDS
CU240S PN	Can be changed: T	Calculated: -	
PM240			
	Min	Max	Factory setting
	0	99	18
Description:	Selects function of digital input 6.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 25: DC brake enable 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0).		

p0707[0...2] Function of digital input 6 / Function of DI6			
CU240S	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: NO	Data set: CDS
CU240S PN	Can be changed: T	Calculated: -	
PM250, PM260			
	Min	Max	Factory setting
	0	99	18
Description:	Selects function of digital input 6.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0).		

p0708[0...2] Function of digital input 7 / Function of DI7			
CU240S	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: NO	Data set: CDS
CU240S PN	Can be changed: T	Calculated: -	
PM240			
	Min	Max	Factory setting
	0	99	0
Description:	Selects function of digital input 7.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 25: DC brake enable 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0).		

p0708[0...2] Function of digital input 7 / Function of DI7			
CU240S	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: NO	Data set: CDS
CU240S PN	Can be changed: T	Calculated: -	
PM250, PM260			
	Min	Max	Factory setting
	0	99	0
Description:	Selects function of digital input 7.		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0).		

p0709[0...2] Function of digital input 8 / Function of DI8			
CU240S	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: NO	Data set: CDS
CU240S PN	Can be changed: T	Calculated: -	
PM240			
	Min	Max	Factory setting
	0	99	0
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 25: DC brake enable 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0).		

p0709[0...2] Function of digital input 8 / Function of DI8			
CU240S	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: NO	Data set: CDS
CU240S PN	Can be changed: T	Calculated: -	
PM250, PM260			
	Min	Max	Factory setting
	0	99	0
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0).		

p0712[0...2] Analog / digital input 0 / Ana/digi input 0			
PM240	Access level: 2	P-Group: Commands	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min 0	Max 99	Factory setting 0
Description:	Selects function of digital input AI0 (via analog input)		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 25: DC brake enable 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0). Signals above 4 V are active, signals below 1,6 V are inactive.		

p0712[0...2] Analog / digital input 0 / Ana/digi input 0			
PM250	Access level: 2	P-Group: Commands	Data type: Unsigned16
PM260	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min 0	Max 99	Factory setting 0
Description:	Selects function of digital input AI0 (via analog input)		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0). Signals above 4 V are active, signals below 1,6 V are inactive.		

p0713[0...2] Analog / digital input 1 / Ana/digi input 1			
PM240	Access level: 2	P-Group: Commands	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	0	99	0
Description:	Selects function of digital input AI1 (via analog input)		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 25: DC brake enable 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0). Signals above 4 V are active, signals below 1,6 V are inactive.		

p0713[0...2] Analog / digital input 1 / Ana/digi input 1			
PM250	Access level: 2	P-Group: Commands	Data type: Unsigned16
PM260	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	0	99	0
Description:	Selects function of digital input AI1 (via analog input)		
Value:	0: Digital input disabled 1: ON/OFF1 2: ON reverse /OFF1 3: OFF2 - coast to standstill 4: OFF3 - quick ramp-down 9: Fault acknowledge 10: JOG right 11: JOG left 12: Reverse 13: MOP up (increase frequency) 14: MOP down (decrease frequency) 15: Fixed frequency selector bit0 16: Fixed frequency selector bit1 17: Fixed frequency selector bit2 18: Fixed frequency selector bit3 27: Enable PID 29: External trip 33: Disable additional freq setpoint 99: Enable BICO parameterization		
Note:	See P0701 (function of digital input 0). Signals above 4 V are active, signals below 1,6 V are inactive.		

p0719[0...2] Selection of cmd. & freq. setp. / Cmd.&freq.setp.sel																																																																																							
CU240E	Access level: 4	P-Group: Commands	Data type: Unsigned16																																																																																				
CU240S	Quick comm. NO	Active: NO	Data set: CDS																																																																																				
	Can be changed: T	Calculated: -																																																																																					
	Min 0	Max 57	Factory setting 0																																																																																				
Description:	<p>Central switch to select control command source for inverter.</p> <p>Switches command and setpoint source between freely programmable BICO parameters and fixed command/setpoint profiles.</p> <p>Command and setpoint sources can be changed independently.</p> <p>The tens digit chooses the command source and the units digit chooses the setpoint source.</p>																																																																																						
Value:	<table> <tbody> <tr><td>0:</td><td>Cmd = BICO parameter</td><td>Setpoint = BICO parameter</td></tr> <tr><td>1:</td><td>Cmd = BICO parameter</td><td>Setpoint = MOP setpoint</td></tr> <tr><td>2:</td><td>Cmd = BICO parameter</td><td>Setpoint = Analog setpoint</td></tr> <tr><td>3:</td><td>Cmd = BICO parameter</td><td>Setpoint = Fixed frequency</td></tr> <tr><td>4:</td><td>Cmd = BICO parameter</td><td>Setpoint = USS on RS232</td></tr> <tr><td>5:</td><td>Cmd = BICO parameter</td><td>Setpoint = USS on RS485</td></tr> <tr><td>7:</td><td>Cmd = BICO parameter</td><td>Setpoint = Analog setpoint 2</td></tr> <tr><td>10:</td><td>Cmd = BOP</td><td>Setpoint = BICO parameter</td></tr> <tr><td>11:</td><td>Cmd = BOP</td><td>Setpoint = MOP setpoint</td></tr> <tr><td>12:</td><td>Cmd = BOP</td><td>Setpoint = Analog setpoint</td></tr> <tr><td>13:</td><td>Cmd = BOP</td><td>Setpoint = Fixed frequency</td></tr> <tr><td>14:</td><td>Cmd = BOP</td><td>Setpoint = USS on RS232</td></tr> <tr><td>15:</td><td>Cmd = BOP</td><td>Setpoint = USS on RS485</td></tr> <tr><td>17:</td><td>Cmd = BOP</td><td>Setpoint = Analog setpoint 2</td></tr> <tr><td>40:</td><td>Cmd = USS on RS232</td><td>Setpoint = BICO parameter</td></tr> <tr><td>41:</td><td>Cmd = USS on RS232</td><td>Setpoint = MOP setpoint</td></tr> <tr><td>42:</td><td>Cmd = USS on RS232</td><td>Setpoint = Analog setpoint</td></tr> <tr><td>43:</td><td>Cmd = USS on RS232</td><td>Setpoint = Fixed frequency</td></tr> <tr><td>44:</td><td>Cmd = USS on RS232</td><td>Setpoint = USS on RS232</td></tr> <tr><td>45:</td><td>Cmd = USS on RS232</td><td>Setpoint = USS on RS485</td></tr> <tr><td>47:</td><td>Cmd = USS on RS232</td><td>Setpoint = Analog setpoint 2</td></tr> <tr><td>50:</td><td>Cmd = USS on RS485</td><td>Setpoint = BICO parameter</td></tr> <tr><td>51:</td><td>Cmd = USS on RS485</td><td>Setpoint = MOP setpoint</td></tr> <tr><td>52:</td><td>Cmd = USS on RS485</td><td>Setpoint = Analog setpoint</td></tr> <tr><td>53:</td><td>Cmd = USS on RS485</td><td>Setpoint = Fixed frequency</td></tr> <tr><td>54:</td><td>Cmd = USS on RS485</td><td>Setpoint = USS on RS232</td></tr> <tr><td>55:</td><td>Cmd = USS on RS485</td><td>Setpoint = USS on RS485</td></tr> <tr><td>57:</td><td>Cmd = USS on RS485</td><td>Setpoint = Analog setpoint 2</td></tr> </tbody> </table>			0:	Cmd = BICO parameter	Setpoint = BICO parameter	1:	Cmd = BICO parameter	Setpoint = MOP setpoint	2:	Cmd = BICO parameter	Setpoint = Analog setpoint	3:	Cmd = BICO parameter	Setpoint = Fixed frequency	4:	Cmd = BICO parameter	Setpoint = USS on RS232	5:	Cmd = BICO parameter	Setpoint = USS on RS485	7:	Cmd = BICO parameter	Setpoint = Analog setpoint 2	10:	Cmd = BOP	Setpoint = BICO parameter	11:	Cmd = BOP	Setpoint = MOP setpoint	12:	Cmd = BOP	Setpoint = Analog setpoint	13:	Cmd = BOP	Setpoint = Fixed frequency	14:	Cmd = BOP	Setpoint = USS on RS232	15:	Cmd = BOP	Setpoint = USS on RS485	17:	Cmd = BOP	Setpoint = Analog setpoint 2	40:	Cmd = USS on RS232	Setpoint = BICO parameter	41:	Cmd = USS on RS232	Setpoint = MOP setpoint	42:	Cmd = USS on RS232	Setpoint = Analog setpoint	43:	Cmd = USS on RS232	Setpoint = Fixed frequency	44:	Cmd = USS on RS232	Setpoint = USS on RS232	45:	Cmd = USS on RS232	Setpoint = USS on RS485	47:	Cmd = USS on RS232	Setpoint = Analog setpoint 2	50:	Cmd = USS on RS485	Setpoint = BICO parameter	51:	Cmd = USS on RS485	Setpoint = MOP setpoint	52:	Cmd = USS on RS485	Setpoint = Analog setpoint	53:	Cmd = USS on RS485	Setpoint = Fixed frequency	54:	Cmd = USS on RS485	Setpoint = USS on RS232	55:	Cmd = USS on RS485	Setpoint = USS on RS485	57:	Cmd = USS on RS485	Setpoint = Analog setpoint 2
0:	Cmd = BICO parameter	Setpoint = BICO parameter																																																																																					
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12:	Cmd = BOP	Setpoint = Analog setpoint																																																																																					
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14:	Cmd = BOP	Setpoint = USS on RS232																																																																																					
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Dependency:	<p>P0719 has higher priority than P0700 and P1000.</p> <p>If set to a value other than 0 (i.e. BICO parameter is not the setpoint source), P0844 / P0848 (first source of OFF2 / OFF3) are not effective; instead, P0845 / P0849 (second source of OFF2 / OFF3) apply and the OFF commands are obtained via the particular source defined.</p> <p>BICO connections made previously remain unchanged.</p>																																																																																						
Notice:	<p>Particularly useful when e.g. changing command source temporarily from P0700 = 2.</p> <p>Settings in P0719 (contrary to P0700 settings) do not reset the digital inputs (P0701, P0702, ...)</p>																																																																																						

p0719[0...2] Selection of cmd. & freq. setp. / Cmd.&freq.setp.sel																																																																																							
CU240S DP	Access level: 4	P-Group: Commands	Data type: Unsigned16																																																																																				
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS																																																																																				
CU240S PN	Can be changed: T	Calculated: -																																																																																					
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	Min 0	Max 67	Factory setting 0																																																																																				
Description:	<p>Central switch to select control command source for inverter.</p> <p>Switches command and setpoint source between freely programmable BICO parameters and fixed command/setpoint profiles.</p> <p>Command and setpoint sources can be changed independently.</p> <p>The tens digit chooses the command source and the units digit chooses the setpoint source.</p>																																																																																						
Value:	<table border="0"> <tr> <td>0:</td> <td>Cmd = BICO parameter</td> <td>Setpoint = BICO parameter</td> </tr> <tr> <td>1:</td> <td>Cmd = BICO parameter</td> <td>Setpoint = MOP setpoint</td> </tr> <tr> <td>2:</td> <td>Cmd = BICO parameter</td> <td>Setpoint = Analog setpoint</td> </tr> <tr> <td>3:</td> <td>Cmd = BICO parameter</td> <td>Setpoint = Fixed frequency</td> </tr> <tr> <td>4:</td> <td>Cmd = BICO parameter</td> <td>Setpoint = USS on RS232</td> </tr> <tr> <td>6:</td> <td>Cmd = BICO parameter</td> <td>Setpoint = Fieldbus</td> </tr> <tr> <td>7:</td> <td>Cmd = BICO parameter</td> <td>Setpoint = Analog setpoint 2</td> </tr> <tr> <td>10:</td> <td>Cmd = BOP</td> <td>Setpoint = BICO parameter</td> </tr> <tr> <td>11:</td> <td>Cmd = BOP</td> <td>Setpoint = MOP setpoint</td> </tr> <tr> <td>12:</td> <td>Cmd = BOP</td> <td>Setpoint = Analog setpoint</td> </tr> <tr> <td>13:</td> <td>Cmd = BOP</td> <td>Setpoint = Fixed frequency</td> </tr> <tr> <td>14:</td> <td>Cmd = BOP</td> <td>Setpoint = USS on RS232</td> </tr> <tr> <td>16:</td> <td>Cmd = BOP</td> <td>Setpoint = Fieldbus</td> </tr> <tr> <td>17:</td> <td>Cmd = BOP</td> <td>Setpoint = Analog setpoint 2</td> </tr> <tr> <td>40:</td> <td>Cmd = USS on RS232</td> <td>Setpoint = BICO parameter</td> </tr> <tr> <td>41:</td> <td>Cmd = USS on RS232</td> <td>Setpoint = MOP setpoint</td> </tr> <tr> <td>42:</td> <td>Cmd = USS on RS232</td> <td>Setpoint = Analog setpoint</td> </tr> <tr> <td>43:</td> <td>Cmd = USS on RS232</td> <td>Setpoint = Fixed frequency</td> </tr> <tr> <td>44:</td> <td>Cmd = USS on RS232</td> <td>Setpoint = USS on RS232</td> </tr> <tr> <td>46:</td> <td>Cmd = USS on RS232</td> <td>Setpoint = Fieldbus</td> </tr> <tr> <td>47:</td> <td>Cmd = USS on RS232</td> <td>Setpoint = Analog setpoint 2</td> </tr> <tr> <td>60:</td> <td>Cmd = Fieldbus</td> <td>Setpoint = BICO parameter</td> </tr> <tr> <td>61:</td> <td>Cmd = Fieldbus</td> <td>Setpoint = MOP setpoint</td> </tr> <tr> <td>62:</td> <td>Cmd = Fieldbus</td> <td>Setpoint = Analog setpoint</td> </tr> <tr> <td>63:</td> <td>Cmd = Fieldbus</td> <td>Setpoint = Fixed frequency</td> </tr> <tr> <td>64:</td> <td>Cmd = Fieldbus</td> <td>Setpoint = USS on RS232</td> </tr> <tr> <td>66:</td> <td>Cmd = Fieldbus</td> <td>Setpoint = Fieldbus</td> </tr> <tr> <td>67:</td> <td>Cmd = Fieldbus</td> <td>Setpoint = Analog setpoint 2</td> </tr> </table>			0:	Cmd = BICO parameter	Setpoint = BICO parameter	1:	Cmd = BICO parameter	Setpoint = MOP setpoint	2:	Cmd = BICO parameter	Setpoint = Analog setpoint	3:	Cmd = BICO parameter	Setpoint = Fixed frequency	4:	Cmd = BICO parameter	Setpoint = USS on RS232	6:	Cmd = BICO parameter	Setpoint = Fieldbus	7:	Cmd = BICO parameter	Setpoint = Analog setpoint 2	10:	Cmd = BOP	Setpoint = BICO parameter	11:	Cmd = BOP	Setpoint = MOP setpoint	12:	Cmd = BOP	Setpoint = Analog setpoint	13:	Cmd = BOP	Setpoint = Fixed frequency	14:	Cmd = BOP	Setpoint = USS on RS232	16:	Cmd = BOP	Setpoint = Fieldbus	17:	Cmd = BOP	Setpoint = Analog setpoint 2	40:	Cmd = USS on RS232	Setpoint = BICO parameter	41:	Cmd = USS on RS232	Setpoint = MOP setpoint	42:	Cmd = USS on RS232	Setpoint = Analog setpoint	43:	Cmd = USS on RS232	Setpoint = Fixed frequency	44:	Cmd = USS on RS232	Setpoint = USS on RS232	46:	Cmd = USS on RS232	Setpoint = Fieldbus	47:	Cmd = USS on RS232	Setpoint = Analog setpoint 2	60:	Cmd = Fieldbus	Setpoint = BICO parameter	61:	Cmd = Fieldbus	Setpoint = MOP setpoint	62:	Cmd = Fieldbus	Setpoint = Analog setpoint	63:	Cmd = Fieldbus	Setpoint = Fixed frequency	64:	Cmd = Fieldbus	Setpoint = USS on RS232	66:	Cmd = Fieldbus	Setpoint = Fieldbus	67:	Cmd = Fieldbus	Setpoint = Analog setpoint 2
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Dependency:	<p>P0719 has higher priority than P0700 and P1000.</p> <p>If set to a value other than 0 (i.e. BICO parameter is not the setpoint source), P0844 / P0848 (first source of OFF2 / OFF3) are not effective; instead, P0845 / P0849 (second source of OFF2 / OFF3) apply and the OFF commands are obtained via the particular source defined.</p> <p>BICO connections made previously remain unchanged.</p> <p>USS on RS485 is not supported.</p>																																																																																						
Notice:	<p>Particularly useful when e.g. changing command source temporarily from P0700 = 2.</p> <p>Settings in P0719 (contrary to P0700 settings) do not reset the digital inputs (P0701, P0702, ...)</p>																																																																																						

r0720	Number of digital inputs / Number of DI		
	Access level: 3	P-Group: Commands	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -

Description: Displays number of digital inputs.

r0722.0...12	CO/BO: Binary input values / Bin.inp.val		
CU240E	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S DP-F	Unit: -	Calculated: -	Data set: -
CU240S PN-F			

Description: Displays status of digital inputs.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Digital input 0	Yes	No	-
	01	Digital input 1	Yes	No	-
	02	Digital input 2	Yes	No	-
	03	Digital input 3	Yes	No	-
	04	Digital input 4	Yes	No	-
	05	Digital input 5	Yes	No	-
	11	Digital input AI0	Yes	No	-
	12	Digital input AI1	Yes	No	-

Note: Segment is lit when signal is active.

r0722.0...12	CO/BO: Binary input values / Bin.inp.val		
CU240S	Access level: 2	P-Group: Commands	Data type: Unsigned16
CU240S DP	Unit: -	Calculated: -	Data set: -
CU240S PN			

Description: Displays status of digital inputs.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Digital input 0	Yes	No	-
	01	Digital input 1	Yes	No	-
	02	Digital input 2	Yes	No	-
	03	Digital input 3	Yes	No	-
	04	Digital input 4	Yes	No	-
	05	Digital input 5	Yes	No	-
	06	Digital input 6	Yes	No	-
	07	Digital input 7	Yes	No	-
	08	Digital input 8	Yes	No	-
	11	Digital input AI0	Yes	No	-
	12	Digital input AI1	Yes	No	-

Note: Segment is lit when signal is active.

p0724	Debounce time for digital inputs / Debounce time: DI		
	Access level: 3	P-Group: Commands	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	0	3	3

Description: Defines debounce time (filtering time) used for digital inputs.

Value:	0:	No debounce time
	1:	2.5 ms debounce time
	2:	8.2 ms debounce time
	3:	12.3 ms debounce time

p0725 PNP / NPN digital inputs / PNP/NPN DI

CU240E **Access level:** 3 **P-Group:** Commands **Data type:** Unsigned16
Quick comm. NO **Active:** YES **Data set:** -
Can be changed: T **Calculated:** -

Min **Max** **Factory setting**
0 1 1

Description: Switches between active high (PNP) and active low (NPN).
This is valid for all digital inputs simultaneously.
The following is valid by using the internal supply:

Value: 0: NPN mode ==> low active
1: PNP mode ==> high active

p0727[0...2] Selection of 2/3-wire method / 2/3-wire selection

Access level: 2 **P-Group:** - **Data type:** Unsigned16
Quick comm. YES **Active:** NO **Data set:** CDS
Can be changed: C(1), T **Calculated:** -

Min **Max** **Factory setting**
0 3 0

Description: Determines the control method using the terminals. This parameter allows the selection of the control philosophy.
The control philosophies exclude each other.

Value: 0: Siemens (start/dir)
1: 2-wire (fwd/rev)
2: 3-wire (fwd/rev)
3: 3-wire (start/dir)

Note: Where:

- P denotes Pulse
- FWD denotes FORWARD
- REV denotes REVERSE

When any of the control functions are selected using P0727, the setting for the digital inputs (P0701 - P0704) are redefined as follows:

Redefined Digital Inputs

Settings P0701 - P0704	P0727 = 0 (Siemens Standard Control)	P0727 = 1 (2-wire Control)	P0727 = 2 (3-wire Control)	P0727 = 3 (3-wire Control)
1	ON/OFF1	ON_FWD	STOP	ON_PULSE
2	ON_REV/OFF1	ON_REV	FWDP	OFF1/HOLD
12	REV	REV	REVP	REV

Regarding the use of fixed frequencies see P1000 and P1001.

r0730 Number of digital outputs / Number of DO

Access level: 3 **P-Group:** Commands **Data type:** Unsigned16
Unit: - **Calculated:** - **Data set:** -

Description: Displays number of digital outputs (relays).

p0731[0...2]	BI: Function of digital output 0 / Fct. of DO0		
PM240	Access level: 2	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	52.3
Description:	Defines source of digital output 0.		
Notice:	An inverse logic can be realised by inverting the digital outputs in P0748.		
Note:	Output of fault bit 52.3 is inverted on digital output. Monitor functions ==> see parameter r0052, r0053 Motor holding brake ==> see parameter P1215 DC-Brake ==> see parameter P1232, P1233		

p0731[0...2]	BI: Function of digital output 0 / Fct. of DO0		
PM250	Access level: 2	P-Group: Commands	Data type: U32 / Binary
PM260	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	52.3
Description:	Defines source of digital output 0.		
Notice:	An inverse logic can be realised by inverting the digital outputs in P0748.		
Note:	Output of fault bit 52.3 is inverted on digital output. Monitor functions ==> see parameter r0052, r0053 Motor holding brake ==> see parameter P1215		

p0732[0...2]	BI: Function of digital output 1 / Fct. of DO1		
	Access level: 2	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	52.7
Description:	Defines source of digital output 1.		

p0733[0...2]	BI: Function of digital output 2 / Fct. of DO2		
	Access level: 2	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Defines source of digital output 2.		

r0747.0...2	CO/BO: State of digital outputs / State DOs				
	Access level: 3	P-Group: Commands	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays status of digital outputs (also includes inversion of digital outputs via P0748).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Digital output 0 energized	Yes	No	-
	01	Digital output 1 energized	Yes	No	-
	02	Digital output 2 energized	Yes	No	-
Dependency:	Bit = 0 signal: Contacts open Bit = 1 signal: Contacts closed				
p0748	Invert digital outputs / Invert DOs				
	Access level: 3	P-Group: Commands	Data type: Unsigned16		
	Quick comm. NO	Active: NO	Data set: -		
	Can be changed: U, T	Calculated: -			
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Defines high and low states of relay for a given function.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Invert digital output 0	Yes	No	-
	01	Invert digital output 1	Yes	No	-
	02	Invert digital output 2	Yes	No	-
r0750	Number of AIs / Number of AIs				
	Access level: 3	P-Group: Terminals	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays number of analog inputs available.				
r0751.0...9	CO/BO: Status word of AI / AI status Wd				
	Access level: 3	P-Group: Terminals	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays status of analog input.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Signal lost on AI0	Yes	No	-
	01	Signal lost on AI1	Yes	No	-
	08	No signal lost on AI0	Yes	No	-
	09	No signal lost on AI1	Yes	No	-
r0752[0...1]	Act. input of AI [V] or [mA] / Act.AI inp.[V/mA]				
	Access level: 2	P-Group: Terminals	Data type: FloatingPoint32		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays smoothed analog input value in volts or milliamps before the scaling block.				
Index:	[0] = Analog input 0 (AI0) [1] = Analog input 1 (AI1)				
p0753[0...1]	Smooth time AI / Smooth time AI				
	Access level: 3	P-Group: Terminals	Data type: Unsigned16		
	Quick comm. NO	Active: NO	Data set: -		
	Can be changed: U, T	Calculated: -			
	Min	Max	Factory setting		
	0 [ms]	10000 [ms]	3 [ms]		
Description:	Defines filter time (PT1 filter) in [ms] for analog input.				

Index: [0] = Analog input 0 (AI0)
[1] = Analog input 1 (AI1)

Note: Increasing this time (smooth) reduces jitter but slows down response to the analog input.
P0753 = 0 : No filtering

r0754[0...1] **Act. AI value after scaling [%] / AI after scal.[%]**

Access level: 2 **P-Group:** Terminals **Data type:** FloatingPoint32

Unit: [%] **Calculated:** - **Data set:** -

Description: Shows smoothed value of analog input in [%] after scaling block.

Index: [0] = Analog input 0 (AI0)
[1] = Analog input 1 (AI1)

Dependency: P0757 to P0760 define range (AI scaling).

r0755[0...1] **CO: Act. AI after scal. [4000h] / CO:AI scal[4000h]**

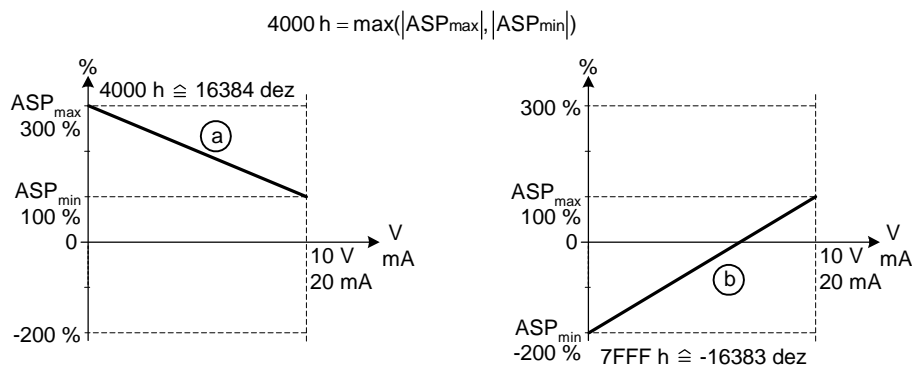
Access level: 2 **P-Group:** Terminals **Data type:** Integer16

Unit: - **Calculated:** - **Data set:** -

Description: Displays analog input, scaled using ASPmin and ASPmax (ASP = analog setpoint).
Analog setpoint (ASP) from the analog scaling block can vary from min. analog setpoint (ASPmin) to a max. analog setpoint (ASPmax).
The largest magnitude (value without sign) of ASPmin and ASPmax defines the scaling of 16384.
By associating parameter r0755 with an internal value (e.g. frequency setpoint), a scaled value is calculated internally by the inverter.
The frequency value is calculated using the following equation:
 $r0755[\text{Hz}] = (r0755[\text{hex}] / 4000[\text{hex}]) * p2000 * (\max(|\text{ASP}_{\text{max}}|, |\text{ASP}_{\text{min}}|) / 100\%)$

Example: Case a:
ASPmin = 300 %, ASPmax = 100 % then 16384 represents 300 %.
This parameter will vary from 5461 to 16384.

Case b:
ASPmin = -200 %, ASPmax = 100 % then 16384 represents 200 %.
This parameter will vary from -16384 to +8192.



Index: [0] = Analog input 0 (AI0)
[1] = Analog input 1 (AI1)

Note: This value is used as an input to analog BICO connectors.
ASPmax represents the highest analog setpoint (this may be at 10 V).
ASPmin represents the lowest analog setpoint (this may be at 0 V).
See parameters P0757 to P0760 (AI scaling)

p0756[0...1]	Type of AI / Type of AI		
	Access level: 2	P-Group: Terminals	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min 0	Max 4	Factory setting 0
Description:	<p>Defines type of analog input and also enables analog input monitoring. To switch over from voltage to current analog input it is not sufficient to merely modify parameter P0756. Rather, the general I/O DIP switches must also be set to the correct position. The DIP settings are as follows:</p> <ul style="list-style-type: none"> • OFF = voltage input (10 V) • ON = current input (20 mA) <p>Allocation of DIPs to analog inputs is as follows:</p> <ul style="list-style-type: none"> • DIP on left (DIP 1) = Analog input 0 • DIP on right (DIP 2) = Analog input 1 		
Value:	0: Unipolar voltage input (0 to +10 V) 1: Unipolar voltage input with monitoring (0 to 10 V) 2: Unipolar current input (0 to 20 mA) 3: Unipolar current input with monitoring (0 to 20 mA) 4: Bipolar voltage input (-10 V to +10 V)		
Index:	[0] = Analog input 0 (AI0) [1] = Analog input 1 (AI1)		
Dependency:	Function disabled if analog scaling block programmed to output negative setpoints (see P0757 to P0760).		
Notice:	When monitoring is enabled and a deadband defined (P0761), a fault condition will be generated (F0080) if the analog input voltage falls below 50 % of the deadband voltage. It is not possible to select the bipolar voltage for analog input 1.		
Note:	See P0757 to P0760 (AI scaling).		
p0757[0...1]	Value x1 of AI scaling / Value x1:AI scal.		
	Access level: 2	P-Group: Terminals	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min -20	Max 20	Factory setting 0
Description:	<p>Parameters P0757 - P0760 configure the input scaling. x1 is the first value of the two pairs of variants x1/y1 and x2/y2 which determine the straight line. The value x2 of AI scaling P0759 must be greater than the value x1 of AI scaling P0757.</p>		
Index:	[0] = Analog input 0 (AI0) [1] = Analog input 1 (AI1)		
Notice:	<ul style="list-style-type: none"> • Analog setpoints represent a [%] of the normalized frequency in P2000. • Analog setpoints may be larger than 100 %. • ASPmax represents highest analog setpoint (this may be at 10 V or 20 mA). • ASPmin represents lowest analog setpoint (this may be at 0 V or 20 mA). • Default values provide a scaling of 0 V or 0 mA = 0 %, and 10 V or 20 mA = 100 %. 		
p0758[0...1]	Value y1 of AI scaling / Value y1:AI scal.		
	Access level: 2	P-Group: Terminals	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min -99999.9 [%]	Max 99999.9 [%]	Factory setting 0.0 [%]
Description:	Sets value of y1 in [%] as described in P0757 (AI scaling)		

Index: [0] = Analog input 0 (AI0)
[1] = Analog input 1 (AI1)

Dependency: Affects P2000 to P2003 (reference frequency, voltage, current or torque) depending on which setpoint is to be generated.

p0759[0...1] Value x2 of AI scaling / Value x2:AI scal.

Access level: 2	P-Group: Terminals	Data type: FloatingPoint32
Quick comm. NO	Active: NO	Data set: -
Can be changed: U, T	Calculated: -	
Min -20	Max 20	Factory setting 10

Description: Sets value of x2 as described in P0757 (AI scaling).

Index: [0] = Analog input 0 (AI0)
[1] = Analog input 1 (AI1)

Notice: The value x2 of AI scaling P0759 must be greater than the value x1 of AI scaling P0757.

p0760[0...1] Value y2 of AI scaling / Value y2:AI scal.

Access level: 2	P-Group: Terminals	Data type: FloatingPoint32
Quick comm. NO	Active: NO	Data set: -
Can be changed: U, T	Calculated: -	
Min -99999.9 [%]	Max 99999.9 [%]	Factory setting 100.0 [%]

Description: Sets value of y2 in [%] as described in P0757 (AI scaling).

Index: [0] = Analog input 0 (AI0)
[1] = Analog input 1 (AI1)

Dependency: Affects P2000 to P2003 (reference frequency, voltage, current or torque) depending on which setpoint is to be generated.

p0761[0...1]	Width of AI deadband / AI deadband width		
	Access level: 2	P-Group: Terminals	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0	Max 20	Factory setting 0
Description:	Defines width of deadband on analog input.		
Example:	The below example produces a 2 to 10 V, 0 to 50 Hz analog input (AI value 2 to 10 V, 0 to 50 Hz):		
	<ul style="list-style-type: none"> • P2000 = 50 Hz • P0759 = 8 V P0760 = 75 % • P0757 = 2 V P0758 = 0 % • P0761 = 2 V • P0756 = 0 or 1 		
	The below example produces a 0 to 10 V analog input (-50 to +50 Hz) with center zero and a "holding point" 0.2 V wide (0.1 V to each side of center, AI value 0 to 10 V, -50 to +50 Hz):		
	<ul style="list-style-type: none"> • P2000 = 50 Hz • P0759 = 8 V P0760 = 75 % • P0757 = 2 V P0758 = -75 % • P0761 = 0.1 V • P0756 = 0 or 1 		
Index:	[0] = Analog input 0 (AI0) [1] = Analog input 1 (AI1)		
Notice:	Deadband starts from 0 V to value of P0761, if both values of P0758 and P0760 (y coordinates of AI scaling) are positive or negative respectively. However, deadband is active in both directions from point of intersection (x axis with AI scaling curve), if sign of P0758 and P0760 are opposite.		
Note:	P0761[x] = 0 : No deadband active. Min. frequency P1080 should be zero when using center zero setup. There is no hysteresis at the end of the deadband.		
p0762[0...1]	Delay for loss of signal action / Delay on sig. loss		
	Access level: 3	P-Group: Terminals	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0 [ms]	Max 10000 [ms]	Factory setting 10 [ms]
Description:	Defines time delay between loss of analog setpoint and appearance of fault code F0080.		
Index:	[0] = Analog input 0 (AI0) [1] = Analog input 1 (AI1)		
Note:	Expert users can choose the desired reaction to F0080 (default is OFF2).		
r0770	Number of AO / Number of AO		
	Access level: 3	P-Group: Terminals	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays number of analog outputs available.		

p0771[0...1]	CI: AO / AO		
	Access level: 2	P-Group: Terminals	Data type: U32 / Integer32
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min -	Max -	Factory setting 21[0]
Description:	Defines function of the analog output.		
Index:	[0] = Analog output 0 (AO0) [1] = Analog output 1 (AO1)		
<hr/>			
p0773[0...1]	Smooth time AO / Smooth time AO		
	Access level: 2	P-Group: Terminals	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0 [ms]	Max 1000 [ms]	Factory setting 2 [ms]
Description:	Defines smoothing time [ms] for analog output signal. This parameter enables smoothing for AO using a PT1 filter.		
Index:	[0] = Analog output 0 (AO0) [1] = Analog output 1 (AO1)		
Dependency:	P0773 = 0: Deactivates filter.		
<hr/>			
r0774[0...1]	Act. AO value [V] or [mA] / Act.AO val.[V/mA]		
	Access level: 2	P-Group: Terminals	Data type: FloatingPoint32
	Unit: -	Calculated: -	Data set: -
Description:	Shows value of analog output after filtering and scaling.		
Index:	[0] = Analog output 0 (AO0) [1] = Analog output 1 (AO1)		
<hr/>			
p0775[0...1]	Permit absolute value / Enable ab. value		
	Access level: 2	P-Group: Terminals	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min 0	Max 65535	Factory setting 0
Description:	Decides if the absolute value of the analog output is used. If enabled, this parameter will take the absolute value to be outputted. If the value was originally negative then the corresponding bit in r0785 is set, otherwise it is cleared.		
Index:	[0] = Analog output 0 (AO0) [1] = Analog output 1 (AO1)		

p0776[0...1]	Type of AO / Type of AO		
	Access level: 2	P-Group: Terminals	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min 0	Max 1	Factory setting 0
Description:	Defines type of analog output.		
Value:	0: Current output 1: Voltage output		
Index:	[0] = Analog output 0 (AO0) [1] = Analog output 1 (AO1)		
Note:	Analog Output 0 can be switched to a voltage output with a range 0...10 V. Analog Output 1 is only a current output. By connecting an external resistor of 500 Ohm to the terminals a voltage output with a range of 0...10 V can be created.		
p0777[0...1]	Value x1 of AO scaling / Value x1:AO scal.		
	Access level: 2	P-Group: Terminals	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min -99999.0 [%]	Max 99999.0 [%]	Factory setting 0.0 [%]
Description:	Defines x1 output characteristic in [%]. Scaling block is responsible for adjustment of output value defined in P0771 (AO connector input). x1 is the first value of the two pairs of variants x1/y1 and x2/y2 which determine the straight line. The two points P1 (x1, y1) and P2 (x2, y2) can be chosen freely.		
Index:	[0] = Analog output 0 (AO0) [1] = Analog output 1 (AO1)		
Dependency:	Affects P2000 to P2003 (referency frequency, voltage, current or torque) depending on which setpoint is to be generated.		
p0778[0...1]	Value y1 of AO scaling / Value y1:AO scal.		
	Access level: 2	P-Group: Terminals	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0	Max 20	Factory setting 0
Description:	Defines y1 of output characteristic.		
Index:	[0] = Analog output 0 (AO0) [1] = Analog output 1 (AO1)		
p0779[0...1]	Value x2 of AO scaling / Value x2:AO scal.		
	Access level: 2	P-Group: Terminals	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min -99999.0 [%]	Max 99999.0 [%]	Factory setting 100.0 [%]
Description:	Defines x2 of output characteristic in [%].		
Index:	[0] = Analog output 0 (AO0) [1] = Analog output 1 (AO1)		
Dependency:	Affects P2000 to P2003 (referency frequency, voltage, current or torque) depending on which setpoint is to be generated.		

p0780[0...1]	Value y2 of AO scaling / Value y2:AO scal.		
	Access level: 2	P-Group: Terminals	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0	Max 20	Factory setting 20
Description:	Defines y2 of output characteristic.		
Index:	[0] = Analog output 0 (AO0) [1] = Analog output 1 (AO1)		
p0781[0...1]	Width of AO deadband / AO deadband width		
	Access level: 2	P-Group: Terminals	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0	Max 20	Factory setting 0
Description:	Sets width of dead-band in [mA] for analog output.		
Index:	[0] = Analog output 0 (AO0) [1] = Analog output 1 (AO1)		
r0785.0...1	CO/BO: Status word of AO / AO stat Wd		
	Access level: 2	P-Group: Terminals	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays status of analog output. Bit 0 indicates that the value of analog output 0 is negative. Bit 1 indicates that the value of analog output 1 is negative.		
Bit field:	Bit	Signal name	1 signal
	00	Analog output 0 negative	Yes
	01	Analog output 1 negative	Yes
			0 signal
			No
			No
			FP
			-
			-
p0800[0...2]	BI: Download parameter set 0 / Dwnl.par.set 0		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	Defines source of command to start download of parameter set 0 from attached OP. The first three digits describe the parameter number of the command source, the last digit refers to the bit setting for that parameter.		
Note:	Signal of digital input: 0 = No download 1 = Start download parameter set 0 from OP.		

p0801[0...2]	BI: Download parameter set 1 / Dwnl.par.set 1		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Defines sources of command to start download of parameter set 1 from attached OP. The first three digits describe the parameter number of the command source, the last digit refers to the bit setting for that parameter.		
Note:	Signal of digital input: 0 = No download 1 = Start download parameter set 1 from OP.		
p0802	Transfer data from EEPROM / Transf.Drive->Ext		
CU240E	Access level: 3	P-Group: Factory settings	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min	Max	Factory setting
	0	1	0
Description:	Transfers values from drive to External device when none 0. Parameter P0010 must be set to 30 for this to be possible.		
Value:	0: Disabled 1: Start OP Transfer		
Note:	Parameter is automatically reset to 0 (default) after transfer. P0010 will be reset to 0 on successful completion.		
p0802	Transfer data from EEPROM / Transf.Drive->Ext		
CU240S	Access level: 3	P-Group: Factory settings	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: NO	Data set: -
CU240S DP-F	Can be changed: -	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min	Max	Factory setting
	0	2	0
Description:	Transfers values from drive to External device when none 0. Parameter P0010 must be set to 30 for this to be possible.		
Value:	0: Disabled 1: Start OP Transfer 2: Start MMC Transfer		
Note:	Parameter is automatically reset to 0 (default) after transfer. P0010 will be reset to 0 on successful completion. Ensure that enough space exists on the MMC card before transferring data (8kb).		

p0803	Transfer data to EEPROM / Transf.Ext->Drive		
CU240E	Access level: 3	P-Group: Factory settings	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 0	Max 1	Factory setting 0
Description:	Transfers values from External to drive when none 0. Parameter P0010 must be set to 30 for this to be possible.		
Value:	0: Disabled 1: Start OP Transfer		
Note:	Parameter is automatically reset to 0 (default) after transfer. P0010 will be reset to 0 on successful completion.		

p0803	Transfer data to EEPROM / Transf.Ext->Drive		
CU240S	Access level: 3	P-Group: Factory settings	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: NO	Data set: -
CU240S DP-F	Can be changed: -	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min 0	Max 2	Factory setting 0
Description:	Transfers values from External to drive when none 0. Parameter P0010 must be set to 30 for this to be possible.		
Value:	0: Disabled 1: Start OP Transfer 2: Start MMC Transfer		
Note:	Parameter is automatically reset to 0 (default) after transfer. P0010 will be reset to 0 on successful completion.		

p0804	Select Clone file / Select Clone file		
CU240S	Access level: 3	P-Group: Factory settings	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: NO	Data set: -
CU240S DP-F	Can be changed: -	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min 0	Max 99	Factory setting 0
Description:	Select clone file to up/down load. if P0804 = 0 then file name is clone00.bin if P0804 = 1 then file name is clone01.bin etc.		

p0806	BI: Inhibit panel access / Inhibit panel acce		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	Binector input to lock control panel access through external client.		

r0807.0	BO: Displays client access / Displays client ac			
	Access level: 3	P-Group: Commands	Data type: Unsigned16	
	Unit: -	Calculated: -	Data set: -	
Description:	Binector output to display whether command and setpoint source is connected to an external client.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Master control active	Yes	No
				FP -
p0809[0...2]	Copy Command Dataset (CDS) / Copy CDS			
	Access level: 2	P-Group: Commands	Data type: Unsigned16	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: T	Calculated: -		
	Min	Max	Factory setting	
	0	2	0	
Description:	Calls 'Copy Command Dataset (CDS)' function. The list of all Command Datasets (CDS) parameters is shown in Section 1.3 of this Parameter List (PLI).			
Example:	Copying of all values from CDS0 to CDS2 can be accomplished by the following procedure: P0809[0] = 0 Copy from CDS0 P0809[1] = 2 Copy to CDS2 P0809[2] = 1 Start copy			
Index:	[0] = Copy from CDS [1] = Copy to CDS [2] = Start copy			
Note:	Start value in index 2 is automatically reset to '0' after execution of function.			
p0810	BI: CDS bit 0 (Hand/Auto) / CDS bit 0			
	Access level: 2	P-Group: Commands	Data type: U32 / Binary	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	-	-	0	
Description:	Selects command source from which to read Bit 0 for selecting a Command Dataset (CDS). The actual selected CDS is displayed in r0054.15 (CDS bit 0) and r0055.15 (CDS bit 1). The actual active CDS is displayed in r0050.			
Example:	Typical procedure for CDS switch-over: <ul style="list-style-type: none"> • CDS0: Command source via terminal and setpoint source via analog input (AI) • CDS1: Command source via USS on RS232 and setpoint source via MOP • CDS switch-over takes place via digital input 3 (DI3) Steps: <ol style="list-style-type: none"> 1. Commissioning of inverter / drive 2. CDS0 set parameters (P0700[0] = 2 and P1000[0] = 2) 3. Connect P0810 (P0811 if necessary) with the source of CDS switch-over (P0704[0] = 99, P0810 = 722.3) 4. Copy CDS0 to CDS1 (P0809[0] = 0, P0809[1] = 1, P0809[2] = 2) 5. Change CDS1 parameter as required (set parameters for CDS2 [P0700 = 4 and P1000 = 1]) 			
Note:	P0811 is also relevant for Command Dataset (CDS) set selection.			

p0811	BI: CDS bit 1 / CDS bit 1		
	Access level: 2	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Selects command source from which to read Bit 1 for selecting a Command Dataset (see P0810).		
Note:	P0810 is also relevant for Command Dataset (CDS) selection.		
p0819[0...2]	Copy Drive Dataset (DDS) / Copy DDS		
	Access level: 2	P-Group: Commands	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	0	2	0
Description:	Calls 'Copy Drive Dataset (DDS)' function. The list of all Drive Dataset (DDS) parameters is shown in Section 1.3 of the Parameter List (PLI).		
Example:	Copying of all values from DDS0 to DDS2 can be accomplished by the following procedure: P0819[0] = 0 Copy from DDS0 P0819[1] = 2 Copy to DDS2 P0819[2] = 1 Start copy		
Index:	[0] = Copy from DDS [1] = Copy to DDS [2] = Start copy		
Note:	Start value in index 2 is automatically reset to '0' after execution of function.		
p0820	BI: DDS bit 0 / DDS bit 0		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Selects command source from which to read Bit 0 for selecting a Drive Dataset (DDS). The actual selected Drive Dataset (DDS) is displayed in parameter r0051[0]. The actual active Drive Dataset (DDS) is displayed in parameter r0051[1].		
Dependency:	When Standard Telegram 350 and Fieldbus is selected (p0700 = 6, p0922 = 350), parameter cannot be changed.		
Note:	P0821 is also relevant for Drive Dataset (DDS) selection.		
p0821	BI: DDS bit 1 / DDS bit 1		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Selects command source from which Bit 1 for selecting a Drive Dataset is to be read in (see parameter P0820).		
Dependency:	When Standard Telegram 350 and Fieldbus selected (p0700 = 6, p0922 = 350), parameter cannot be changed.		
Note:	P0820 is also relevant for Drive Dataset (DDS) selection.		

p0840[0...2]	BI: ON/OFF1 / ON/OFF1		
CU240E	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	722.0
Description:	Allows ON/OFF1 command source to be selected using BICO.		
Dependency:	For digital inputs as command source BICO requires P0700 set to 2 (enable BICO). The default setting (ON right) is digital input 0 (722.0). Alternative source possible only when function of digital input 0 is changed (via P0701) before changing value of P0840. When Standard Telegram selected (p0700 = 6, p0922 = Standard Telegram), parameter cannot be changed.		
p0840[0...2]	BI: ON/OFF1 / ON/OFF1		
CU240S DP	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	2090.0
Description:	Allows ON/OFF1 command source to be selected using BICO.		
Dependency:	When Standard Telegram selected (p0700 = 6, p0922 = Standard Telegram), parameter cannot be changed.		
p0840[0...2]	BI: ON/OFF1 / ON/OFF1		
CU240S PN	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S PN-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	8890.0
Description:	Allows ON/OFF1 command source to be selected using BICO.		
Dependency:	When Standard Telegram selected (p0700 = 6, p0922 = Standard Telegram), parameter cannot be changed.		
p0842[0...2]	BI: ON reverse/OFF1 / ON reverse/OFF1		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Allows ON/OFF1 reverse command source to be selected using BICO. In general a positive frequency setpoint is run up counterclockwise (negative frequency).		

p0844[0...2]	BI: 1. OFF2 / 1. OFF2		
CU240E	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	1
Description:	Defines first source of OFF2 when P0719 = 0 (BICO).		
Dependency:	If one of the digital inputs is selected for OFF2, the inverter will not run unless the digital input is active. When Standard Telegram selected (p0700 = 6, p0922 = Standard Telegram), parameter cannot be changed.		
Note:	OFF2 means immediate pulse-disabling; the motor is coasting. OFF2 is low-active, i.e. : 0 = Pulse disabling. 1 = Operating condition.		
p0844[0...2]	BI: 1. OFF2 / 1. OFF2		
CU240S DP	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	2090.1
Description:	Defines first source of OFF2 when P0719 = 0 (BICO).		
Dependency:	If one of the digital inputs is selected for OFF2, the inverter will not run unless the digital input is active. When Standard Telegram selected (p0700 = 6, p0922 = Standard Telegram), parameter cannot be changed.		
Note:	OFF2 means immediate pulse-disabling; the motor is coasting. OFF2 is low-active, i.e. : 0 = Pulse disabling. 1 = Operating condition.		
p0844[0...2]	BI: 1. OFF2 / 1. OFF2		
CU240S PN	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S PN-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	8890.1
Description:	Defines first source of OFF2 when P0719 = 0 (BICO).		
Dependency:	If one of the digital inputs is selected for OFF2, the inverter will not run unless the digital input is active. When Standard Telegram selected (p0700 = 6, p0922 = Standard Telegram), parameter cannot be changed.		
Note:	OFF2 means immediate pulse-disabling; the motor is coasting. OFF2 is low-active, i.e. : 0 = Pulse disabling. 1 = Operating condition.		

p0845[0...2]	BI: 2. OFF2 / 2. OFF2		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	19.1
Description:	Defines second source of OFF2.		
Dependency:	In contrast to P0844 (first source of OFF2), this parameter is always active, independent of P0719 (selection of command and frequency setpoint). If one of the digital inputs is selected for OFF2, the inverter will not run unless the digital input is active.		
Note:	OFF2 means immediate pulse-disabling; the motor is coasting. OFF2 is low-active, i.e. : 0 = Pulse disabling. 1 = Operating condition.		
p0848[0...2]	BI: 1. OFF3 / 1. OFF3		
CU240E	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	1
Description:	Defines first source of OFF3 when P0719 = 0 (BICO).		
Dependency:	If one of the digital inputs is selected for OFF3, the inverter will not run unless the digital input is active. When Standard Telegram selected (p0700 = 6, p0922 = Standard Telegram), parameter cannot be changed.		
Note:	OFF3 means quick ramp-down to 0. OFF3 is low-active, i.e. 0 = Quick ramp-down. 1 = Operating condition.		
p0848[0...2]	BI: 1. OFF3 / 1. OFF3		
CU240S DP	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	2090.2
Description:	Defines first source of OFF3 when P0719 = 0 (BICO).		
Dependency:	If one of the digital inputs is selected for OFF3, the inverter will not run unless the digital input is active. When Standard Telegram selected (p0700 = 6, p0922 = Standard Telegram), parameter cannot be changed.		
Note:	OFF3 means quick ramp-down to 0. OFF3 is low-active, i.e. 0 = Quick ramp-down. 1 = Operating condition.		

p0848[0...2]	BI: 1. OFF3 / 1. OFF3		
CU240S PN	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S PN-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	8890.2
Description:	Defines first source of OFF3 when P0719 = 0 (BICO).		
Dependency:	If one of the digital inputs is selected for OFF3, the inverter will not run unless the digital input is active. When Standard Telegram selected (p0700 = 6, p0922 = Standard Telegram), parameter cannot be changed.		
Note:	OFF3 means quick ramp-down to 0. OFF3 is low-active, i.e. 0 = Quick ramp-down. 1 = Operating condition.		
p0849[0...2]	BI: 2. OFF3 / 2. OFF3		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	1
Description:	Defines second source of OFF3.		
Dependency:	In contrast to P0848 (first source of OFF3), this parameter is always active, independent of P0719 (selection of command and frequency setpoint). If one of the digital inputs is selected for OFF3, the inverter will not run unless the digital input is active.		
Note:	OFF3 means quick ramp-down to 0. OFF3 is low-active, i.e. 0 = Quick ramp-down. 1 = Operating condition.		
p0852[0...2]	BI: Pulse enable / Pulse enable		
CU240E	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	1
Description:	Defines source of pulse enable/disable signal.		
Dependency:	Active only when P0719 = 0 (Auto selection of command/setpoint source). When Standard Telegram selected (p0700 = 6, p0922 = Standard Telegram), parameter cannot be changed.		
p0852[0...2]	BI: Pulse enable / Pulse enable		
CU240S DP	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	2090.3
Description:	Defines source of pulse enable/disable signal.		
Dependency:	Active only when P0719 = 0 (Auto selection of command/setpoint source). When Standard Telegram selected (p0700 = 6, p0922 = Standard Telegram), parameter cannot be changed.		

p0852[0...2]		BI: Pulse enable / Pulse enable	
CU240S PN	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S PN-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	8890.3
Description:	Defines source of pulse enable/disable signal.		
Dependency:	Active only when P0719 = 0 (Auto selection of command/setpoint source). When Standard Telegram selected (p0700 = 6, p0922 = Standard Telegram), parameter cannot be changed.		
p0918		PROFIBUS address / PROFIBUS address	
CU240S DP	Access level: 2	P-Group: Communications	Data type: Unsigned16
CU240S DP-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	1	126	3
Description:	Defines PROFIBUS address. There are two ways to set the bus address: 1. via DIP switches on the control unit 2. via a user-entered value		
Note:	Possible PROFIBUS settings: 1 ... 125 0, 126, 127 are not allowed The following applies when PROFIBUS is used: All PROFIBUS DIP switches = OFF --> Address defined in P0918 is valid otherwise the DIP switch setting has priority and P0918 indicates DIP switch setting.		

p0922 Selection of PROFIdrive Standard Telegram / Standard Telegram				
CU240S DP	Access level: 3	P-Group: Communications	Data type: Unsigned16	
CU240S DP-F	Quick comm. NO	Active: NO	Data set: -	
CU240S PN	Can be changed: T	Calculated: -		
CU240S PN-F				
	Min 1	Max 999	Factory setting 1	
Description:	Selects the PROFIdrive Standard Telegram.			
Value:	1: Standard Telegram 1 20: Standard Telegram 20 350: Standard Telegram 350 352: Standard Telegram 352 353: Standard Telegram 353 354: Standard Telegram 354 999: Free BICO connection			
Dependency:	Setting Standard Telegram has effect only when PROFIBUS is selected.			
Note:	With this parameter the type of Standard Telegram is selected and the corresponding BICO connections will be frozen during Standard Telegram. Setting P0922 from Standard Telegram to 999, the BICO connections are kept but BICO connection can be changed freely. Only Standard Telegram 350 has effect on control word 2. On PROFINET devices changing P0922 might cause a reset of PROFINET communication. Change of P0922 also resets all the BICO connections corresponding to settings in P0700. Example: P0700 = 4, P0922 = 1, P0840 = 2032.0 Change P0840 = 722.0 Now change P0922 to other Standard Telegram : the parameter P0840 will be reset to 2032.0 (due to P0700 = 4) When P0922 is changed the following parameters can be modified : <ul style="list-style-type: none"> • For the control word 1: P0840, P0844, P0848, P0852, P1140, P1141, P1142, P2104, P1055, P1056, P1113, P1035, P1036, P0810, P0820 • For the control word 2: P1020, P1021, P1022, P1023, P0820, P0821, P2200, P1230, P1501, P2106. Switching to / from Standard Telegram 20 (VIK/Namur) : Changing P0922 to 20 (Telegram 20) automatically switches P2038 to 2 (VIK/Namur). Changing P0922 to another value switches P2038 to 0 (PROFIdrive Profil). Changing P0922 NEVER affects P2042 (Ident number). P2042 must be switched manually, and a power cycle must be done after.			
p0927 Parameter changeable via / Change par. via				
CU240E	Access level: 2	P-Group: Communications	Data type: Unsigned16	
CU240S	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: U, T	Calculated: -		
	Min -	Max -	Factory setting 1111 bin	
Description:	Specifies the interfaces which can be used to change parameters. This parameter allows the user to easily protect the inverter from unauthorized modification of parameters. Annotation: Parameter P0927 is not password protected.			
Example:	Default: All bits are set. The default setting allows parameters to be changed via any interface.			
Bit field:	Bit	Signal name	1 signal	0 signal
	01	BOP	Yes	No
	02	USS on RS232	Yes	No
	03	USS on RS485	Yes	No
				FP
				-
				-
				-

p0927		Parameter changeable via / Change par. via			
CU240S DP	Access level: 2	P-Group: Communications	Data type: Unsigned16		
CU240S DP-F	Quick comm. NO	Active: NO	Data set: -		
CU240S PN	Can be changed: U, T	Calculated: -			
CU240S PN-F					
	Min	Max	Factory setting		
	-	-	1111 bin		
Description:	Specifies the interfaces which can be used to change parameters. This parameter allows the user to easily protect the inverter from unauthorized modification of parameters. Annotation: Parameter P0927 is not password protected.				
Example:	Default: All bits are set: The default setting allows parameters to be changed via any interface.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fieldbus	Yes	No	-
	01	BOP	Yes	No	-
	02	USS on RS232	Yes	No	-

r0944		Total number of messages / Total nb Mes		
	Access level: 3	P-Group: Messages	Data type: Unsigned16	
	Unit: -	Calculated: -	Data set: -	
Description:	Displays the total number of messages available			

r0947[0...63]		CO: Last fault code / Last fault code		
CU240E	Access level: 2	P-Group: Messages	Data type: Unsigned16	
CU240S	Unit: -	Calculated: -	Data set: -	
CU240S DP				
CU240S PN				
Description:	Displays fault history.			
Index:	[0] = Recent fault trip --, fault 1 [1] = Recent fault trip --, fault 2 [2] = Recent fault trip --, fault 3 [3] = Recent fault trip --, fault 4 [4] = Recent fault trip --, fault 5 [5] = Recent fault trip --, fault 6 [6] = Recent fault trip --, fault 7 [7] = Recent fault trip --, fault 8 [8] = Recent fault trip -1, fault 1			
Note:	See Chapter "Faults and Warnings".			

r0947[0...63]	CO: Last fault code / Last fault code		
CU240S DP-F	Access level: 2	P-Group: Messages	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -
Description:	Displays fault history.		
Index:	[0] = Recent fault trip --, fault 1 [1] = Recent fault trip --, fault 2 [2] = Recent fault trip --, fault 3 [3] = Recent fault trip --, fault 4 [4] = Recent fault trip --, fault 5 [5] = Recent fault trip --, fault 6 [6] = Recent fault trip --, fault 7 [7] = Recent fault trip --, fault 8 [8] = Recent fault trip -1, fault 1		
Notice:	It is possible that this parameter is empty but a fault is still indicated by the drive. The reason for this is most likely due to a SAFE condition still existing in the system. In this situation the fault is cleared from this parameter and it makes no sense to go back to a READY state. First remove the reason for the SAFE condition and then the drive will be able to change to a READY state. (SAFE condition example is "safety function is activated").		
Note:	See Chapter "Faults and Warnings".		
r0948[0...63]	Fault time / Fault time		
CU240E	Access level: 3	P-Group: Messages	Data type: Unsigned32
CU240S	Unit: -	Calculated: -	Data set: -
Description:	Time stamp to indicate when a fault has occurred. P2114 (run-time counter) or P2115 (real time clock) are the possible sources of the time stamp. In case of PROFIdrive Profile 3.1 or higher configuration, P0969 (system run time counter) is used.		
Index:	[0] = Recent fault trip --, fault time 1 [1] = Recent fault trip --, fault time 2 [2] = Recent fault trip --, fault time 3 [3] = Recent fault trip --, fault time 4 [4] = Recent fault trip --, fault time 5 [5] = Recent fault trip --, fault time 6 [6] = Recent fault trip --, fault time 7 [7] = Recent fault trip --, fault time 8 [8] = Recent fault trip -1, fault time 1		
Note:	P2115 can be updated via Starter, DriveMonitor, etc.		
r0948[0...63]	Fault time / Fault time		
CU240S DP	Access level: 3	P-Group: Messages	Data type: Unsigned32
CU240S DP-F	Unit: -	Calculated: -	Data set: -
CU240S PN			
CU240S PN-F			
Description:	Time stamp to indicate when a fault has occurred. P2114 (run-time counter) or P2115 (real time clock) are the possible sources of the time stamp. In case of PROFIdrive Profile 3.1 or higher configuration, P0969 (system run time counter) is used.		
Example:	The time is taken from P2115 if this parameter has been updated with the real time. If not, P2114 is used. If P2038 is set to PROFIdrive or Namur, P0969 is used.		
Index:	[0] = Recent fault trip --, fault time 1 [1] = Recent fault trip --, fault time 2 [2] = Recent fault trip --, fault time 3 [3] = Recent fault trip --, fault time 4 [4] = Recent fault trip --, fault time 5 [5] = Recent fault trip --, fault time 6 [6] = Recent fault trip --, fault time 7 [7] = Recent fault trip --, fault time 8 [8] = Recent fault trip -1, fault time 1		
Note:	P2115 can be updated via Starter, DriveMonitor, etc.		

r0949[0...63]	CO: Fault value / Fault value		
	Access level: 3	P-Group: Messages	Data type: Unsigned32
	Unit: -	Calculated: -	Data set: -
Description:	Displays drive fault values. It is for service purposes and indicate the type of fault reported. The values are not documented. They are listed in the code where faults are reported.		
Index:	[0] = Recent fault trip --, fault value 1 [1] = Recent fault trip --, fault value 2 [2] = Recent fault trip --, fault value 3 [3] = Recent fault trip --, fault value 4 [4] = Recent fault trip --, fault value 5 [5] = Recent fault trip --, fault value 6 [6] = Recent fault trip --, fault value 7 [7] = Recent fault trip --, fault value 8 [8] = Recent fault trip -1, fault value 1		
p0952	Total number of faults / Total faults		
	Access level: 3	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min 0	Max 65535	Factory setting 0
Description:	Displays number of faults stored in P0947 (last fault code).		
Dependency:	Setting 0 resets fault history. (changing to 0 also resets parameter r0948 - fault time).		
r0964[0...6]	Firmware version data / FW version data		
	Access level: 3	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Firmware version data.		
Index:	[0] = Company (Siemens = 42) [1] = Product type [2] = Firmware version [3] = Firmware date (year) [4] = Firmware date (day/month) [5] = Number of drive objects [6] = Firmware version		
r0965	PROFdrive Profile / PROFdrive Profile		
	Access level: 3	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Identification for PROFdrive Profile number and version.		

r0967		Control word 1 / Control word 1			
Access level: 3		P-Group: Communications		Data type: Unsigned16	
Unit: -		Calculated: -		Data set: -	
Description:		Displays control word 1.			
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	ON/OFF1	Yes	No	-
	01	OFF2: Electrical stop	No	Yes	-
	02	OFF3: Fast stop	No	Yes	-
	03	Pulse enable	Yes	No	-
	04	RFG enable	Yes	No	-
	05	RFG start	Yes	No	-
	06	Setpoint enable	Yes	No	-
	07	Fault acknowledge	Yes	No	-
	08	JOG right	Yes	No	-
	09	JOG left	Yes	No	-
	10	Control from PLC	Yes	No	-
	11	Reverse (setpoint inversion)	Yes	No	-
	13	Motor potentiometer MOP up	Yes	No	-
	14	Motor potentiometer MOP down	Yes	No	-
	15	CDS Bit 0 (Hand/Auto)	Yes	No	-

r0968		Status word 1 / Status word 1			
Access level: 3		P-Group: Communications		Data type: Unsigned16	
Unit: -		Calculated: -		Data set: -	
Description:		Displays active status word of inverter (in binary) and can be used to diagnose which commands are active.			
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Drive ready	Yes	No	-
	01	Drive ready to run	Yes	No	-
	02	Drive running	Yes	No	-
	03	Drive fault active	Yes	No	-
	04	OFF2 active	No	Yes	-
	05	OFF3 active	No	Yes	-
	06	ON inhibit active	Yes	No	-
	07	Drive warning active	Yes	No	-
	08	Deviation setpoint / act. value	No	Yes	-
	09	PZD control	Yes	No	-
	10	f_act >= P1082 (f_max)	Yes	No	-
	11	Warning: Motor current/torque limit	No	Yes	-
	12	Brake open	Yes	No	-
	13	Motor overload	No	Yes	-
	14	Motor runs right	Yes	No	-
	15	Inverter overload	No	Yes	-

p0969		Resetable system run time counter / Rst counter		
Access level: 3		P-Group: Messages		Data type: Unsigned32
Quick comm. NO		Active: YES		Data set: -
Can be changed: T		Calculated: -		
Min		Max		Factory setting
0		4294967295		0
Description:		Resetable system run time counter.		

p0970 Factory reset / Factory reset			
CU240E	Access level: 1	P-Group: Factory settings	Data type: Unsigned16
CU240S	Quick comm. NO	Active: NO	Data set: -
CU240S DP	Can be changed: -	Calculated: -	
CU240S PN			
	Min	Max	Factory setting
	0	10	0
Description:	P0970 = 1 resets all parameters to their default values.		
Value:	0: Disabled 1: Parameter reset 10: Safety reset		
Dependency:	First set P0010 = 30 (factory settings). Stop drive (i.e. disable all pulses) before you can reset parameters to default values.		
Note:	The following parameters retain their values after a factory reset: <ul style="list-style-type: none"> • r0039 CO: Energy consumption meter [kWh] • P0014 Store mode • P0100 Europe / North America • P0918 PROFIBUS address • P2010 USS baud rate • P2011 USS address When transferring parameter p0970, the frequency inverter uses its processor to carry-out internal calculations. Communications - both via USS as well as via the Fieldbus - are interrupted for the time that it takes to make these calculations. This can result in the following error messages at the connected SIMATIC S7 control (communications via fieldbus): <ul style="list-style-type: none"> • Parameter fault 30 • Drive fault 70 • Drive fault 75 When using STARTER (USS) to commission the drive system, data cannot be entered while these calculations are being made. The faults can be acknowledged as soon as the calculations have been completed in the frequency inverter. These calculations can take up to one minute to complete.		

p0970 Factory reset / Factory reset			
CU240S DP-F	Access level: 1	P-Group: Factory settings	Data type: Unsigned16
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min	Max	Factory setting
	0	10	0
Description:	P0970 = 1 resets all parameters to their default values.		
Value:	0: Disabled 1: Parameter reset 10: Safety reset		
Dependency:	First set P0010 = 30 (factory settings). Stop drive (i.e. disable all pulses) before you can reset parameters to default values.		
Note:	The following parameters retain their values after a factory reset: <ul style="list-style-type: none"> • r0039 CO: Energy consumption meter [kWh] • P0014 Store mode • P0100 Europe / North America • P0918 PROFIBUS address • P2010 USS baud rate • P2011 USS address <p>On the safety module (F-CU) setting 10 is available to reset the safety parameters to their default values. Only the safety parameters will be reset.</p> <p>Select P0010 = 30 before and set the safety password.</p> <p>The reset of safety parameters including safety dynamization will take about 5 s.</p> <p>When transferring parameter p0970, the frequency inverter uses its processor to carry-out internal calculations. Communications - both via USS as well as via the Fieldbus - are interrupted for the time that it takes to make these calculations.</p> <p>This can result in the following error messages at the connected SIMATIC S7 control (communications via fieldbus):</p> <ul style="list-style-type: none"> • Parameter fault 30 • Drive fault 70 • Drive fault 75 <p>When using STARTER (USS) to commission the drive system, data cannot be entered while these calculations are being made.</p> <p>The faults can be acknowledged as soon as the calculations have been completed in the frequency inverter. These calculations can take up to one minute to complete.</p>		
p0971 Transfer data from RAM to EEPROM / Transf.RAM->EEPROM			
	Access level: 3	P-Group: Communications	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	0	1	0
Description:	Transfers values from RAM to EEPROM when set to 1.		
Value:	0: Disabled 1: Start transfer		
Note:	All values in RAM are transferred to EEPROM. Parameter is automatically reset to 0 (default) after successful transfer. The storage from RAM to EEPROM is accomplished via P0971. The communications are reset, if the transfer was successful. During the reset process communications will be interrupted. This creates the following conditions: <ul style="list-style-type: none"> • PLC (e.g. SIMATIC S7) enters Stop mode • Starter automatically recovers communications once they are re-established. • BOP displays "busy" <p>After completion of the transfer process, the communication between the inverter and the PC-tools (e.g. STARTER) or BOP is automatically re-established.</p>		


r0975[0...10]	DO identification / DO ident.		
CU240S PN	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -
Description:	Drive object identification		
Index:	[0] = Company [1] = Drive object type [2] = Firmware version [3] = Firmware date (year) [4] = Firmware date (day/month) [5] = Profidrive drive object class [6] = Profidrive drive object subclass 1 [7] = Drive Object ID (DO-ID) [8] = unused [9] = unused [10] = Firmware path/hotfix		
r0980[0...99]	List of available parameter numbers / Parameter list		
	Access level: 2	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Contains 100 parameter numbers index 0 - 99.		
Index:	[0] = Parameter 1 [1] = Parameter 2 [2] = Parameter 3 [3] = Parameter 4 [4] = Parameter 5 [5] = Parameter 6 [6] = Parameter 7 [7] = Parameter 8 [8] = Parameter 9 [9] = Parameter 10		
Note:	The parameter list array has 2 elements to reduce memory consumption. On each access to an element index 0-99, the individual result is determined dynamically by the 'BeforeAccess' function. The last element contains the number of the following parameter array, 0 indicates end of list		
r0981[0...99]	List of available parameter numbers / Parameter list		
	Access level: 2	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Contains 100 parameter numbers index 100 - 199.		
Index:	[0] = Parameter 1 [1] = Parameter 2 [2] = Parameter 3 [3] = Parameter 4 [4] = Parameter 5 [5] = Parameter 6 [6] = Parameter 7 [7] = Parameter 8 [8] = Parameter 9 [9] = Parameter 10		
Note:	The parameter list array has 2 elements to reduce memory consumption. On each access to an element index 0-99, the individual result is determined dynamically by the 'BeforeAccess' function. The last element contains the number of the following parameter array, 0 indicates end of list		

r0982[0...99]	List of available parameter numbers / Paramter list		
	Access level: 2	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Contains 100 parameter numbers index 200 - 299.		
Index:	[0] = Parameter 1 [1] = Parameter 2 [2] = Parameter 3 [3] = Parameter 4 [4] = Parameter 5 [5] = Parameter 6 [6] = Parameter 7 [7] = Parameter 8 [8] = Parameter 9 [9] = Parameter 10		
Note:	The parameter list array has 2 elements to reduce memory consumption. On each access to an element index 0-99, the individual result is determined dynamically by the 'BeforeAccess' function. The last element contains the number of the following parameter array, 0 indicates end of list		
r0983[0...99]	List of available parameter numbers / Paramter list		
	Access level: 2	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Contains 100 parameter numbers index 300 - 399.		
Index:	[0] = Parameter 1 [1] = Parameter 2 [2] = Parameter 3 [3] = Parameter 4 [4] = Parameter 5 [5] = Parameter 6 [6] = Parameter 7 [7] = Parameter 8 [8] = Parameter 9 [9] = Parameter 10		
Note:	The parameter list array has 2 elements to reduce memory consumption. On each access to an element index 0-99, the individual result is determined dynamically by the 'BeforeAccess' function. The last element contains the number of the following parameter array, 0 indicates end of list		
r0984[0...99]	List of available parameter numbers / Paramter list		
	Access level: 2	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Contains 100 parameter numbers index 400 - 499.		
Index:	[0] = Parameter 1 [1] = Parameter 2 [2] = Parameter 3 [3] = Parameter 4 [4] = Parameter 5 [5] = Parameter 6 [6] = Parameter 7 [7] = Parameter 8 [8] = Parameter 9 [9] = Parameter 10		
Note:	The parameter list array has 2 elements to reduce memory consumption. On each access to an element index 0-99, the individual result is determined dynamically by the 'BeforeAccess' function. The last element contains the number of the following parameter array, 0 indicates end of list		

r0985[0...99]	List of available parameter numbers / Parameter list		
	Access level: 2	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Contains 100 parameter numbers index 500 - 599.		
Index:	[0] = Parameter 1 [1] = Parameter 2 [2] = Parameter 3 [3] = Parameter 4 [4] = Parameter 5 [5] = Parameter 6 [6] = Parameter 7 [7] = Parameter 8 [8] = Parameter 9 [9] = Parameter 10		
Note:	The parameter list array has 2 elements to reduce memory consumption. On each access to an element index 0-99, the individual result is determined dynamically by the 'BeforeAccess' function. The last element contains the number of the following parameter array, 0 indicates end of list		
r0986[0...99]	List of available parameter numbers / Parameter list		
	Access level: 2	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Contains 100 parameter numbers index 600 - 699.		
Index:	[0] = Parameter 1 [1] = Parameter 2 [2] = Parameter 3 [3] = Parameter 4 [4] = Parameter 5 [5] = Parameter 6 [6] = Parameter 7 [7] = Parameter 8 [8] = Parameter 9 [9] = Parameter 10		
Note:	The parameter list array has 2 elements to reduce memory consumption. On each access to an element index 0-99, the individual result is determined dynamically by the 'BeforeAccess' function. The last element contains the number of the following parameter array, 0 indicates end of list		
r0987[0...99]	List of available parameter numbers / Parameter list		
	Access level: 2	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Contains 100 parameter numbers index 700 - 799.		
Index:	[0] = Parameter 1 [1] = Parameter 2 [2] = Parameter 3 [3] = Parameter 4 [4] = Parameter 5 [5] = Parameter 6 [6] = Parameter 7 [7] = Parameter 8 [8] = Parameter 9 [9] = Parameter 10		
Note:	The parameter list array has 2 elements to reduce memory consumption. On each access to an element index 0-99, the individual result is determined dynamically by the 'BeforeAccess' function. The last element contains the number of the following parameter array, 0 indicates end of list		

r0988[0...99]	List of available parameter numbers / Parameter list		
	Access level: 2	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Contains 100 parameter numbers index 800 - 899.		
Index:	[0] = Parameter 1 [1] = Parameter 2 [2] = Parameter 3 [3] = Parameter 4 [4] = Parameter 5 [5] = Parameter 6 [6] = Parameter 7 [7] = Parameter 8 [8] = Parameter 9 [9] = Parameter 10		
Note:	The parameter list array has 2 elements to reduce memory consumption. On each access to an element index 0-99, the individual result is determined dynamically by the 'BeforeAccess' function. The last element contains the number of the following parameter array, 0 indicates end of list		

r0989[0...99]	List of available parameter numbers / Parameter list		
	Access level: 2	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Contains 100 parameter numbers index 900 - 999.		
Index:	[0] = Parameter 1 [1] = Parameter 2 [2] = Parameter 3 [3] = Parameter 4 [4] = Parameter 5 [5] = Parameter 6 [6] = Parameter 7 [7] = Parameter 8 [8] = Parameter 9 [9] = Parameter 10		
Note:	The parameter list array has 2 elements to reduce memory consumption. On each access to an element index 0-99, the individual result is determined dynamically by the 'BeforeAccess' function. The last element contains the number of the following parameter array, 0 indicates end of list		

p1000[0...2] Selection of frequency setpoint / Freq setp. select.			
CU240E	Access level: 1	P-Group: Setpoints	Data type: Unsigned16
CU240S	Quick comm. YES	Active: NO	Data set: CDS
	Can be changed: C(1), T	Calculated: -	
	Min	Max	Factory setting
	0	77	2
Description:	Selects frequency setpoint source. The main setpoint is given by the least significant digit (right-hand position) and the additional setpoint is given by the most significant digit (left-hand position). Single digits denote main setpoints that have no additional setpoint.		
Value:	0: No main setpoint 1: MOP setpoint 2: Analog setpoint 3: Fixed frequency 4: USS on RS232 5: USS on RS485 7: Analog setpoint 2 10: No main setpoint + MOP setpoint 11: MOP setpoint + MOP setpoint 12: Analog setpoint + MOP setpoint 13: Fixed frequency + MOP setpoint 14: USS on RS232 + MOP setpoint 15: USS on RS485 + MOP setpoint 17: Analog setpoint 2 + MOP setpoint 20: No main setpoint + Analog setpoint 21: MOP setpoint + Analog setpoint 22: Analog setpoint + Analog setpoint 23: Fixed frequency + Analog setpoint 24: USS on RS232 + Analog setpoint 25: USS on RS485 + Analog setpoint 27: Analog setpoint 2 + Analog setpoint 30: No main setpoint + Fixed frequency 31: MOP setpoint + Fixed frequency 32: Analog setpoint + Fixed frequency 33: Fixed frequency + Fixed frequency 34: USS on RS232 + Fixed frequency 35: USS on RS485 + Fixed frequency 37: Analog setpoint 2 + Fixed frequency 40: No main setpoint + USS on RS232 41: MOP setpoint + USS on RS232 42: Analog setpoint + USS on RS232 43: Fixed frequency + USS on RS232 44: USS on RS232 + USS on RS232 45: USS on RS485 + USS on RS232 47: Analog setpoint 2 + USS on RS232 50: No main setpoint + USS on RS485 51: MOP setpoint + USS on RS485 52: Analog setpoint + USS on RS485 53: Fixed frequency + USS on RS485 54: USS on RS232 + USS on RS485 55: USS on RS485 + USS on RS485 57: Analog setpoint 2 + USS on RS485 70: No main setpoint + Analog setpoint 2 71: MOP setpoint + Analog setpoint 2 72: Analog setpoint + Analog setpoint 2 73: Fixed frequency + Analog setpoint 2 74: USS on RS232 + Analog setpoint 2 75: USS on RS485 + Analog setpoint 2 77: Analog setpoint 2 + Analog setpoint 2		
Caution:	 Changing this parameter sets (to default) all settings on item selected. These are the following parameters: P1070, P1071, P1075, P1076		

p1000[0...2]	Selection of frequency setpoint / Freq setp. select.		
CU240S DP	Access level: 1	P-Group: Setpoints	Data type: Unsigned16
CU240S DP-F	Quick comm. YES	Active: NO	Data set: CDS
CU240S PN	Can be changed: C(1), T	Calculated: -	
CU240S PN-F			

Min	Max	Factory setting
0	77	6

Description: Selects frequency setpoint source.

The main setpoint is given by the least significant digit (right-hand position) and the additional setpoint is given by the most significant digit (left-hand position). Single digits denote main setpoints that have no additional setpoint.

Value:

0:	No main setpoint
1:	MOP setpoint
2:	Analog setpoint
3:	Fixed frequency
4:	USS on RS232
6:	Fieldbus
7:	Analog setpoint 2
10:	No main setpoint + MOP setpoint
11:	MOP setpoint + MOP setpoint
12:	Analog setpoint + MOP setpoint
13:	Fixed frequency + MOP setpoint
14:	USS on RS232 + MOP setpoint
16:	Fieldbus + MOP setpoint
17:	Analog setpoint 2 + MOP setpoint
20:	No main setpoint + Analog setpoint
21:	MOP setpoint + Analog setpoint
22:	Analog setpoint + Analog setpoint
23:	Fixed frequency + Analog setpoint
24:	USS on RS232 + Analog setpoint
26:	Fieldbus + Analog setpoint
27:	Analog setpoint 2 + Analog setpoint
30:	No main setpoint + Fixed frequency
31:	MOP setpoint + Fixed frequency
32:	Analog setpoint + Fixed frequency
33:	Fixed frequency + Fixed frequency
34:	USS on RS232 + Fixed frequency
36:	Fieldbus + Fixed frequency
37:	Analog setpoint 2 + Fixed frequency
40:	No main setpoint + USS on RS232
41:	MOP setpoint + USS on RS232
42:	Analog setpoint + USS on RS232
43:	Fixed frequency + USS on RS232
44:	USS on RS232 + USS on RS232
46:	Fieldbus + USS on RS232
47:	Analog setpoint 2 + USS on RS232
60:	No main setpoint + Fieldbus
61:	MOP setpoint + Fieldbus
62:	Analog setpoint + Fieldbus
63:	Fixed frequency + Fieldbus
64:	USS on RS232 + Fieldbus
66:	Fieldbus + Fieldbus
67:	Analog setpoint 2 + Fieldbus
70:	No main setpoint + Analog setpoint 2
71:	MOP setpoint + Analog setpoint 2
72:	Analog setpoint + Analog setpoint 2
73:	Fixed frequency + Analog setpoint 2
74:	USS on RS232 + Analog setpoint 2
76:	Fieldbus + Analog setpoint 2
77:	Analog setpoint 2 + Analog setpoint 2

Caution:



Changing this parameter sets (to default) all settings on item selected. These are the following parameters: P1070, P1071, P1075, P1076

p1001[0...2]	Fixed frequency 1 / Fixed frequency 1		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 0.00 [Hz]
Description:	<p>Defines fixed frequency setpoint 1.</p> <p>There are 2 types of fixed frequencies:</p> <ol style="list-style-type: none"> 1. Direct selection (P1016 = 1): <ul style="list-style-type: none"> - In this mode of operation 1 Fixed Frequency selector (P1020...P1023) selects 1 fixed frequency. - If several inputs are active together, the selected frequencies are summed. E.g.: FF1 + FF2 + FF3 + FF4. 2. Binary coded selection (P1016 = 2): <ul style="list-style-type: none"> - Up to 16 different fixed frequency values can be selected using this method. - The fixed frequencies are selected according to FP3210. 		
Dependency:	<p>Select fixed frequency operation (using P1000).</p> <p>Inverter requires ON command to start in the case of direct selection. Therefore r1025 must be connected to P0840 to start.</p>		
Note:	Fixed frequencies can be selected using the digital inputs.		
p1002[0...2]	Fixed frequency 2 / Fixed frequency 2		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 5.00 [Hz]
Description:	Defines fixed frequency setpoint 2.		
Note:	See parameter P1001 (fixed frequency 1).		
p1003[0...2]	Fixed frequency 3 / Fixed frequency 3		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 10.00 [Hz]
Description:	Defines fixed frequency setpoint 3.		
Note:	See parameter P1001 (fixed frequency 1).		
p1004[0...2]	Fixed frequency 4 / Fixed frequency 4		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 15.00 [Hz]
Description:	Defines fixed frequency setpoint 4.		
Note:	See parameter P1001 (fixed frequency 1).		

p1005[0...2]	Fixed frequency 5 / Fixed frequency 5		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 20.00 [Hz]
Description:	Defines fixed frequency setpoint 5.		
Note:	See parameter P1001 (fixed frequency 1).		
p1006[0...2]	Fixed frequency 6 / Fixed frequency 6		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 25.00 [Hz]
Description:	Defines fixed frequency setpoint 6.		
Note:	See parameter P1001 (fixed frequency 1).		
p1007[0...2]	Fixed frequency 7 / Fixed frequency 7		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 30.00 [Hz]
Description:	Defines fixed frequency setpoint 7.		
Note:	See parameter P1001 (fixed frequency 1).		
p1008[0...2]	Fixed frequency 8 / Fixed frequency 8		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 35.00 [Hz]
Description:	Defines fixed frequency setpoint 8.		
Note:	See parameter P1001 (fixed frequency 1).		
p1009[0...2]	Fixed frequency 9 / Fixed frequency 9		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 40.00 [Hz]
Description:	Defines fixed frequency setpoint 9.		
Note:	See parameter P1001 (fixed frequency 1).		

p1010[0...2]	Fixed frequency 10 / Fixed frequency 10		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 45.00 [Hz]
Description:	Defines fixed frequency setpoint 10.		
Note:	See parameter P1001 (fixed frequency 1).		
p1011[0...2]	Fixed frequency 11 / Fixed frequency 11		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 50.00 [Hz]
Description:	Defines fixed frequency setpoint 11.		
Note:	See parameter P1001 (fixed frequency 1).		
p1012[0...2]	Fixed frequency 12 / Fixed frequency 12		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 55.00 [Hz]
Description:	Defines fixed frequency setpoint 12.		
Note:	See parameter P1001 (fixed frequency 1).		
p1013[0...2]	Fixed frequency 13 / Fixed frequency 13		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 60.00 [Hz]
Description:	Defines fixed frequency setpoint 13.		
Note:	See parameter P1001 (fixed frequency 1).		
p1014[0...2]	Fixed frequency 14 / Fixed frequency 14		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 65.00 [Hz]
Description:	Defines fixed frequency setpoint 14.		
Note:	See parameter P1001 (fixed frequency 1).		

p1015[0...2]	Fixed frequency 15 / Fixed frequency 15		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 65.00 [Hz]
Description:	Defines fixed frequency setpoint 15.		
Note:	See parameter P1001 (fixed frequency 1).		
p1016[0...2]	Fixed frequency mode / FF mode		
	Access level: 2	P-Group: Setpoints	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: T	Calculated: -	
	Min 1	Max 2	Factory setting 1
Description:	Fixed frequencies can be selected in two different modes. Parameter P1016 defines the mode.		
Value:	1: Direct selection 2: Binary selection		
Note:	See P1001 (fixed frequency 1) for description of how to use fixed frequencies.		
p1020[0...2]	BI: Fixed freq. selection Bit 0 / FF sel. Bit 0		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 722.3
Description:	Defines origin of fixed frequency selection.		
Dependency:	Accessible only if P0701 - P070x = 99 (function of digital inputs = BICO) When Standard Telegram 350 and PROFIBUS selected (P0700 = 6, P0922 = 350), parameter cannot be changed.		
p1021[0...2]	BI: Fixed freq. selection Bit 1 / FF sel. Bit 1		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 722.4
Description:	Defines origin of fixed frequency selection.		
Dependency:	Accessible only if P0701 - P070x = 99 (function of digital inputs = BICO) When Standard Telegram 350 and PROFIBUS selected (P0700 = 6, P0922 = 350), parameter cannot be changed.		

p1022[0...2]	BI: Fixed freq. selection Bit 2 / FF sel. Bit 2				
	Access level: 3	P-Group: Commands	Data type: U32 / Binary		
	Quick comm. NO	Active: NO	Data set: CDS		
	Can be changed: T	Calculated: -			
	Min	Max	Factory setting		
	-	-	722.5		
Description:	Defines origin of fixed frequency selection.				
Dependency:	Accessible only if P0701 - P070x = 99 (function of digital inputs = BICO) When Standard Telegram 350 and PROFIBUS selected (P0700 = 6, P0922 = 350), parameter cannot be changed.				
p1023[0...2]	BI: Fixed freq. selection Bit 3 / FF sel. Bit 3				
CU240E	Access level: 3	P-Group: Commands	Data type: U32 / Binary		
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS		
CU240S PN-F	Can be changed: T	Calculated: -			
	Min	Max	Factory setting		
	-	-	0		
Description:	Defines origin of fixed frequency selection.				
Dependency:	Accessible only if P0701 - P070x = 99 (function of digital inputs = BICO) When Standard Telegram 350 and PROFIBUS selected (P0700 = 6, P0922 = 350), parameter cannot be changed.				
p1023[0...2]	BI: Fixed freq. selection Bit 3 / FF sel. Bit 3				
CU240S	Access level: 3	P-Group: Commands	Data type: U32 / Binary		
CU240S DP	Quick comm. NO	Active: NO	Data set: CDS		
CU240S PN	Can be changed: T	Calculated: -			
	Min	Max	Factory setting		
	-	-	722.6		
Description:	Defines origin of fixed frequency selection.				
Dependency:	Accessible only if P0701 - P070x = 99 (function of digital inputs = BICO) When Standard Telegram 350 and PROFIBUS selected (P0700 = 6, P0922 = 350), parameter cannot be changed.				
r1024	CO: Act. fixed frequency / Act. FF				
	Access level: 3	P-Group: Setpoints	Data type: FloatingPoint32		
	Unit: [Hz]	Calculated: -	Data set: -		
Description:	Displays sum total of selected fixed frequencies.				
r1025.0	BO: Fixed frequency status / FF Status				
	Access level: 3	P-Group: Commands	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays the status of fixed frequencies.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Status of FF	Yes	No	-

p1031[0...2]	MOP mode / MOP mode			
	Access level: 2	P-Group: Setpoints	Data type: Unsigned16	
	Quick comm. NO	Active: YES	Data set: DDS	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	-	-	0	
Description:	MOP mode specification.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Setpoint store activ	Yes	No
	01	No On-state for MOP necessary	Yes	No
Note:	Defines the operation mode of the motorized potentiometer. See P1040 (setpoint of MOP).			

p1032	Inhibit reverse direction of MOP / Inhib. MOP reverse			
	Access level: 2	P-Group: Setpoints	Data type: Unsigned16	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: T	Calculated: -		
	Min	Max	Factory setting	
	0	1	1	
Description:	Inhibits reverse setpoint selection of the MOP.			
Value:	0: Reverse direction is allowed 1: Reverse direction inhibited			
Note:	It is possible to change motor direction using the motor potentiometer setpoint (increase / decrease frequency either by using digital inputs or OP keypad up / down (e.g. BOP)). The "reversing key" of the OP (e.g. BOP) is not affected by the settings of P1032. Use P1110 to fully prevent change of motor direction. Setting 0 enables a change of motor direction using the motor potentiometer setpoint (increase/decrease frequency).			

p1035[0...2]	BI: Enable MOP (UP-command) / Enable MOP(UP)			
CU240E	Access level: 3	P-Group: Setpoints	Data type: U32 / Binary	
CU240S	Quick comm. NO	Active: NO	Data set: CDS	
	Can be changed: T	Calculated: -		
	Min	Max	Factory setting	
	-	-	19.13	
Description:	Defines source for motor potentiometer setpoint increase frequency.			
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.			
Notice:	If this command is enabled by short pulses of less than 1 second, the frequency is changed in steps of 0.1 Hz. When the signal is enabled longer than 1 second the ramp generator accelerates with the rate of P1047.			

p1035[0...2]	BI: Enable MOP (UP-command) / Enable MOP(UP)			
CU240S DP	Access level: 3	P-Group: Setpoints	Data type: U32 / Binary	
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS	
	Can be changed: T	Calculated: -		
	Min	Max	Factory setting	
	-	-	2090.13	
Description:	Defines source for motor potentiometer setpoint increase frequency.			
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.			
Notice:	If this command is enabled by short pulses of less than 1 second, the frequency is changed in steps of 0.1 Hz. When the signal is enabled longer than 1 second the ramp generator accelerates with the rate of P1047.			

p1035[0...2]	BI: Enable MOP (UP-command) / Enable MOP(UP)		
CU240S PN	Access level: 3	P-Group: Setpoints	Data type: U32 / Binary
CU240S PN-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	8890.13
Description:	Defines source for motor potentiometer setpoint increase frequency.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
Notice:	If this command is enabled by short pulses of less than 1 second, the frequency is changed in steps of 0.1 Hz. When the signal is enabled longer than 1 second the ramp generator accelerates with the rate of P1047.		
p1036[0...2]	BI: Enable MOP (DOWN-command) / Enable MOP(DWN)		
CU240E	Access level: 3	P-Group: Setpoints	Data type: U32 / Binary
CU240S	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	19.14
Description:	Defines source for motor potentiometer setpoint decrease frequency.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
Notice:	If this command is enabled by short pulses of less than 1 second, the frequency is changed in steps of 0.1 Hz. When the signal is enabled longer than 1 second the ramp generator decelerates with the rate of P1048.		
p1036[0...2]	BI: Enable MOP (DOWN-command) / Enable MOP(DWN)		
CU240S DP	Access level: 3	P-Group: Setpoints	Data type: U32 / Binary
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	2090.14
Description:	Defines source for motor potentiometer setpoint decrease frequency.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
Notice:	If this command is enabled by short pulses of less than 1 second, the frequency is changed in steps of 0.1 Hz. When the signal is enabled longer than 1 second the ramp generator decelerates with the rate of P1048.		
p1036[0...2]	BI: Enable MOP (DOWN-command) / Enable MOP(DWN)		
CU240S PN	Access level: 3	P-Group: Setpoints	Data type: U32 / Binary
CU240S PN-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	8890.14
Description:	Defines source for motor potentiometer setpoint decrease frequency.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
Notice:	If this command is enabled by short pulses of less than 1 second, the frequency is changed in steps of 0.1 Hz. When the signal is enabled longer than 1 second the ramp generator decelerates with the rate of P1048.		

p1040[0...2]	Setpoint of the MOP / MOP setpoint		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -650.00 [Hz]	Max 650.00 [Hz]	Factory setting 5.00 [Hz]
Description:	Determines setpoint for motor potentiometer control (P1000 = 1).		
Dependency:	Motor potentiometer (P1040) must be chosen as main setpoint or additional setpoint (using P1000).		
Note:	If motor potentiometer setpoint is selected either as main setpoint or additional setpoint, the reverse direction will be inhibited by default of P1032 (inhibit reverse direction of MOP). To re-enable reverse direction, set P1032 = 0. A short press of the 'up' or 'down' keys (e.g.: BOP) will change the frequency setpoint in steps of 0.1Hz. A longer press will cause an accelerated frequency setpoint change. The start value gets active (for the MOP output) only at the start of the MOP. The parameter P1031 influences the start value behaviour as follows: <ul style="list-style-type: none"> • P1031=0: P1040 gets immediately active in the OFF-state and when changed in the ON-state, it gets active after the next OFF and ON cycle. • P1031=1: The last MOP output before stop is stored as starting value, since storing is selected, so a change of P1040 while in ON-state has no effect. In OFF-state P1040 can be changed. • P1031=2: The MOP is active every time, so the change of P1040 affects after the next power cycle or a change of P1031 to 0. • P1031=3: The last MOP output before power down is stored as starting value, since the MOP is active independent from the ON-command, a change of P1040 has only effect in the case of a change of P1031. 		
p1041[0...2]	BI: MOP select setpoint automatically/manually / Setp. auto/manu		
	Access level: 3	P-Group: Setpoints	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	Sets the signal source to change over from manual to automatic mode. If using the motorized potentiometer in the manual mode the setpoint is changed using two signals for up and down e.g. P1035 and P1036. If using the automatic mode the setpoint must be interconnected via the connector input (P1042). 0 : manually 1 : automatically		
Notice:	Refer to: P1035, P1036, P1042		
p1042[0...2]	CI: MOP auto setpoint / MOP auto setpoint		
	Access level: 3	P-Group: Setpoints	Data type: U32 / Integer32
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the setpoint of the motorized potentiometer if automatic mode P1041 is selected.		
Notice:	Refer to: P1041		

p1043[0...2]	BI: MOP accept rampgenerator setpoint / MOP acc RFG setpo		
	Access level: 3	P-Group: Setpoints	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the setting command to accept the setting value for the motorized potentiometer. The value becomes effective for a 0/1 edge of the setting command.		
Notice:	Refer to: P1044		
p1044[0...2]	CI: MOP rampgenerator setpoint / MOP RFG setpoint		
	Access level: 3	P-Group: Setpoints	Data type: U32 / Integer32
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	Sets the signal source for the setpoint value for the MOP. The value becomes effective for a 0/1 edge of the setting command.		
Notice:	Refer to: P1043		
r1045	CO: MOP input frequency of the RFG / MOP RFG input		
	Access level: 3	P-Group: Setpoints	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays the motorized potentiometer setpoint before it passed the MOP RFG.		
p1047[0...2]	MOP ramp-up time of the RFG / MOP ramp-up time		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [s]	Max 1000.00 [s]	Factory setting 10.00 [s]
Description:	Sets the ramp-up time for the internal MOP ramp-function generator. The setpoint is changed from zero up to limit defined in P1082 within this time.		
Notice:	Refer to: P1048, P1082		
p1048[0...2]	MOP ramp-down time of the RFG / MOP rampdown time		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [s]	Max 1000.00 [s]	Factory setting 10.00 [s]
Description:	Sets the ramp-down time for the internal MOP ramp-function generator. The setpoint is changed from limit defined in P1082 down to zero within this time.		
Notice:	Refer to: P1047, P1082		

r1050	CO: Act. Output freq. of the MOP / MOP outp.freq.		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays output frequency of motor potentiometer setpoint ([Hz]).		
p1055[0...2]	BI: Enable JOG right / Enable JOG ->		
CU240E	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Defines source of JOG right when P0719 = 0 (Auto selection of command/setpoint source).		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
p1055[0...2]	BI: Enable JOG right / Enable JOG ->		
CU240S DP	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	2090.8
Description:	Defines source of JOG right when P0719 = 0 (Auto selection of command/setpoint source).		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
p1055[0...2]	BI: Enable JOG right / Enable JOG ->		
CU240S PN	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S PN-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	8890.8
Description:	Defines source of JOG right when P0719 = 0 (Auto selection of command/setpoint source).		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
p1056[0...2]	BI: Enable JOG left / Enable JOG <-		
CU240E	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Defines source of JOG left when P0719 = 0 (Auto selection of command/setpoint source).		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		

p1056[0...2]	BI: Enable JOG left / Enable JOG <-		
CU240S DP	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	2090.9
Description:	Defines source of JOG left when P0719 = 0 (Auto selection of command/setpoint source).		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
p1056[0...2]	BI: Enable JOG left / Enable JOG <-		
CU240S PN	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S PN-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	8890.9
Description:	Defines source of JOG left when P0719 = 0 (Auto selection of command/setpoint source).		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
p1057	JOG Enable / JOG Enable		
	Access level: 3	P-Group: Commands	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	0000 bin	0001 bin	0001 bin
Description:	While JOG Enable is '0' Jogging (p1056 and p1055) is disabled. When '1' Jogging is enabled.		
p1058[0...2]	JOG frequency / JOG frequency		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	0.00 [Hz]	650.00 [Hz]	5.00 [Hz]
Description:	Jogging increases the motor speed by small amounts. The JOG mode allows the operator to perform a specific number of revolutions and position the rotor manually. The JOG buttons on OP use a non-latching switch on one of the digital inputs to control the motor speed. While the JOG button is pressed, parameter P1058 determines the frequency at which the inverter will run. The motor speed is increased as long as 'JOG left' or 'JOG right' are selected and until the left or right JOG frequency is reached.		
Dependency:	P1060 and P1061 set up and down ramp times respectively for jogging. Rounding times (P1130 - P1133), rounding type (P1134) and P2167 will also have influence on the JOG ramp.		

p1059[0...2]	JOG frequency left / JOG frequency <-		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 5.00 [Hz]
Description:	While JOG left is selected, this parameter determines the frequency at which the inverter will run.		
Dependency:	P1060 and P1061 set up and down ramp times respectively for jogging.		

p1060[0...2]	JOG ramp-up time / JOG ramp-up time		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [s]	Max 650.00 [s]	Factory setting 10.00 [s]
Description:	Sets jog ramp-up time. This is the time used while jogging is active.		
Notice:	Ramp times will be used as follows: <ul style="list-style-type: none"> • P1060 / P1061 : JOG mode is active • P1120 / P1121 : Normal mode (ON/OFF) is active • P1060 / P1061 : Normal mode (ON/OFF) and P1124 is active The rounding of P1130 - P1133 also applies to the JOG ramping.		

p1061[0...2]	JOG ramp-down time / JOG ramp-down time		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [s]	Max 650.00 [s]	Factory setting 10.00 [s]
Description:	Sets ramp-down time. This is the time used while jogging is active.		
Notice:	Ramp times will be used as follows: <ul style="list-style-type: none"> • P1060 / P1061 : JOG mode is active • P1120 / P1121 : Normal mode (ON/OFF) is active • P1060 / P1061 : Normal mode (ON/OFF) and P1124 is active 		

p1070[0...2]	CI: Main setpoint / Main setpoint		
CU240E	Access level: 3	P-Group: Setpoints	Data type: U32 / Integer32
CU240S	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 755[0]
Description:	Defines source of main setpoint.		

p1070[0...2]	CI: Main setpoint / Main setpoint		
CU240S DP	Access level: 3	P-Group: Setpoints	Data type: U32 / Integer32
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
CU240S PN	Can be changed: T	Calculated: -	
CU240S PN-F			
	Min	Max	Factory setting
	-	-	2050[1]
Description:	Defines source of main setpoint.		
p1071[0...2]	CI: Main setpoint scaling / Main setp scal		
	Access level: 3	P-Group: Setpoints	Data type: U32 / Integer16
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	1
Description:	Defines source of the main setpoint scaling.		
p1074[0...2]	BI: Disable additional setpoint / Disab.add.setp		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Disables additional setpoint		
p1075[0...2]	CI: Additional setpoint / Add. setpoint		
	Access level: 3	P-Group: Setpoints	Data type: U32 / Integer32
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Defines source of the additional setpoint (to be added to main setpoint).		
p1076[0...2]	CI: Additional setpoint scaling / Add. setp.scal		
	Access level: 3	P-Group: Setpoints	Data type: U32 / Integer16
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	1
Description:	Defines source of scaling for additional setpoint (to be added to main setpoint).		
r1078	CO: Total frequency setpoint / Tot. freq.setp		
	Access level: 3	P-Group: Setpoints	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays sum of main and additional setpoints in [Hz].		

r1079	CO: Selected frequency setpoint / Sel. freq.setp		
	Access level: 3	P-Group: Setpoints	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays selected frequency setpoint. Following frequency setpoints are displayed: <ul style="list-style-type: none"> • r1078 Total frequency setpoint • P1058 JOG frequency right • P1059 JOG frequency left 		
Dependency:	P1055 (BI: Enable JOG right) or P1056 (BI: Enable JOG left) define command source of JOG right or JOG left respectively.		
Note:	P1055 = 0 and P1056 = 0 ==> Total frequency setpoint is selected.		
p1080[0...2]	Min. frequency / Min. frequency		
	Access level: 1	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. YES	Active: YES	Data set: DDS
	Can be changed: C(1), U, T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 0.00 [Hz]
Description:	Sets minimum motor frequency [Hz] at which motor will run irrespective of frequency setpoint. The minimum frequency P1080 represents a masking frequency of 0 Hz for all frequency target value sources e.g. AI, MOP, FF, USS with the exception of the JOG target value source (analogous to P1091). Thus the frequency band +/-P1080 is run through in optimum time by means of the acceleration/deceleration ramps. Dwelling in the frequency band is not possible. Furthermore, an overshoot of the actual frequency f_{act} upper min. frequency P1080 is output by the signal function $ f_{act} > f_{min}$.		
Note:	Value set here is valid both for clockwise and for anticlockwise rotation. Under certain conditions (e.g. ramping, current limiting), motor can run below minimum frequency.		

p1082[0...2]

Max. frequency / Max. frequency

CU240E
CU240S

Access level: 1
Quick comm. YES
Can be changed: C(1), T

P-Group: Setpoints
Active: NO
Calculated: -

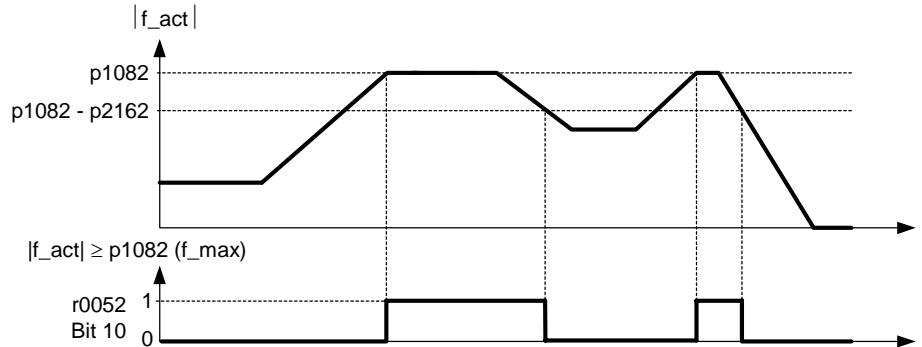
Data type: FloatingPoint32
Data set: DDS

Min 0.00 [Hz] **Max** 650.00 [Hz] **Factory setting** 50.00 [Hz]

Description:

Sets maximum motor frequency [Hz] at which motor will run irrespective of the frequency setpoint. The value set here is valid for both clockwise and anticlockwise rotation. Furthermore, the monitoring function $|f_{act}| \geq P1082$ (r0052 Bit10, see example below) is affected by this parameter.

Example:



Dependency:

The maximum value of P1082 also depends on the nominal frequency: $\text{Max. P1082} = \min(15 \cdot P0310, 650 \text{ Hz})$. As consequence P1082 can be affected if P0310 is changed to a smaller value. The maximum frequency and the pulse frequency depending on each other. The maximum frequency affects the pulse frequency according to the following table.

		p1800			
		2 kHz	4 kHz	6 kHz	8 - 16 kHz
f _{max}	p1082	0 - 133.3 Hz	0 - 266.6 Hz	0 - 400 Hz	0 - 650 Hz

Example:

If P1082 is set to 350 Hz a pulse frequency from at least 6 kHz is necessary. If P1800 is smaller than 6 kHz the parameter is changed P1800 = 6 kHz.

The maximum output frequency of inverter can be exceeded if one of the following is active:

- p1335 ≠ 0 (Slip compensation active) :

$$f_{\max}(p1335) = f_{\max} + f_{\text{slip,max}} = p1082 + \frac{p1336}{100} \cdot \frac{r0330}{100} \cdot p0310$$

- p1200 ≠ 0 (Flying restart active) :

$$f_{\max}(p1200) = f_{\max} + 2 \cdot f_{\text{slip,nom}} = p1082 + 2 \cdot \frac{r0330}{100} \cdot p0310$$

The resultant value is displayed in r1084 (resultant maximum frequency).

Note:

When using the setpoint source

- Analog Input
- USS

the setpoint frequency (in Hz) is cyclically calculated using

- a percentage value (e.g. for the analog input r0754)
- a hexadecimal value (e.g. for the USS r2018[1])
- and the reference frequency P2000.

If for example P1082 = 80 Hz, P2000 = 50 Hz and the analog input is parameterised with P0757 = 0 V, P0758 = 0 %, P0759 = 10 V, P0760 = 100 %, a setpoint frequency of 50 Hz will be applied at 10 V of the analog input.

Regeneration at rated frequency is only possible, when the maximum frequency (p1082) is higher than the rated frequency of the motor. When Quick Commissioning is carried out P2031 is changed as follows: P2000 = P1082.

p1082[0...2]**Max. frequency / Max. frequency**

CU240S DP
CU240S DP-F
CU240S PN
CU240S PN-F

Access level: 1**P-Group:** Setpoints**Data type:** FloatingPoint32**Quick comm. YES****Active:** NO**Data set:** DDS**Can be changed:** C(1), T**Calculated:** -**Min**

0.00 [Hz]

Max

650.00 [Hz]

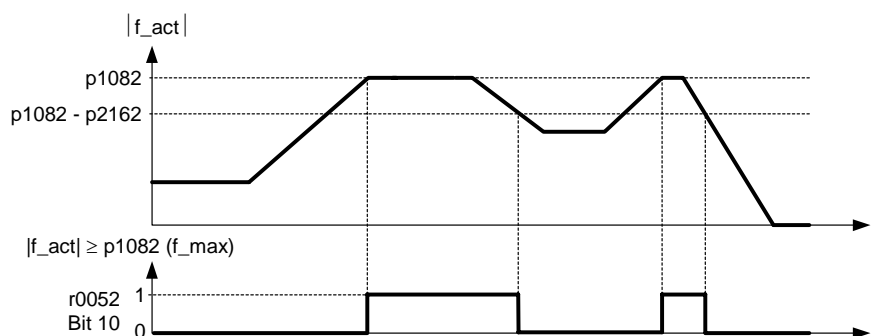
Factory setting

50.00 [Hz]

Description:

Sets maximum motor frequency [Hz] at which motor will run irrespective of the frequency setpoint.

The value set here is valid for both clockwise and anticlockwise rotation. Furthermore, the monitoring function [f_act] \geq P1082 (r0052 Bit10, see example below) is affected by this parameter.

Example:**Dependency:**

The maximum value of P1082 also depends on the nominal frequency: Max. P1082 = min(15*P0310, 650 Hz).

As consequence P1082 can be affected if P0310 is changed to a smaller value. The maximum frequency and the pulse frequency depending on each other. The maximum frequency affects the pulse frequency according to the following table.

		p1800			
		2 kHz	4 kHz	6 kHz	8 - 16 kHz
f _{max}	p1082	0 - 133.3 Hz	0 - 266.6 Hz	0 - 400 Hz	0 - 650 Hz

Example:

If P1082 is set to 350 Hz a pulse frequency from at least 6 kHz is necessary. If P1800 is smaller than 6 kHz the parameter is changed P1800 = 6 kHz. The maximum output frequency of inverter can be exceeded if one of the following is active:

- p1335 \neq 0 (Slip compensation active) :

$$f_{\max}(p1335) = f_{\max} + f_{\text{slip,max}} = p1082 + \frac{p1336}{100} \cdot \frac{r0330}{100} \cdot p0310$$

- p1200 \neq 0 (Flying restart active) :

$$f_{\max}(p1200) = f_{\max} + 2 \cdot f_{\text{slip,nom}} = p1082 + 2 \cdot \frac{r0330}{100} \cdot p0310$$

The resultant value is displayed in r1084 (resultant maximum frequency).

Note:

When using the setpoint source

- Analog Input
- USS
- Fieldbus

the setpoint frequency (in Hz) is cyclically calculated using

- a percentage value (e.g. for the analog input r0754)
- a hexadecimal value (e.g. for the USS r2018[1])
- and the reference frequency P2000.

If for example P1082 = 80 Hz, P2000 = 50 Hz and the analog input is parameterised with P0757 = 0 V, P0758 = 0 %, P0759 = 10 V, P0760 = 100 %, a setpoint frequency of 50 Hz will be applied at 10 V of the analog input.

Regeneration at rated frequency is only possible, when the maximum frequency (p1082) is higher than the rated frequency of the motor. When Quick Commissioning is carried out P2000 is changed as follows: P2000 = P1082.

r1084	Resultant max. frequency / Resultant max freq		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays resultant maximum frequency. p1300 < 20 : p1800 <= 6 kHz --> r1084 = min(p1082, p1800/15, 650.00) p1800 >= 8 kHz --> r1084 = min(p1082, 650.00) p1300 >= 20: r1084 = min(p1082, 5 * p0310, 200.00)		
p1091[0...2]	Skip frequency / Skip frequency		
	Access level: 3	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 0.00 [Hz]
Description:	Defines skip frequency 1 which avoids effects of mechanical resonance and suppresses frequencies within +/- P1101 (skip frequency bandwidth).		
Notice:	Stationary operation is not possible within the suppressed frequency range; the range is merely passed through (on the ramp). For example, if P1091 = 10 Hz and P1101 = 2 Hz, it is not possible to operate continuously between 10 Hz +/- 2 Hz (i.e. between 8 and 12 Hz).		
Note:	The function is disabled if P1091 = 0.		
p1092[0...2]	Skip frequency 2 / Skip frequency 2		
	Access level: 3	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 0.00 [Hz]
Description:	Defines skip frequency 2 which avoids effects of mechanical resonance and suppresses frequencies within +/- P1101 (skip frequency bandwidth).		
Note:	See P1091 (skip frequency 1).		
p1093[0...2]	Skip frequency 3 / Skip frequency 3		
	Access level: 3	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 0.00 [Hz]
Description:	Defines skip frequency 3 which avoids effects of mechanical resonance and suppresses frequencies within +/- P1101 (skip frequency bandwidth).		
Note:	See P1091 (skip frequency 1).		

p1094[0...2]	Skip frequency 4 / Skip frequency 4		
	Access level: 3	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 0.00 [Hz]
Description:	Defines skip frequency 4 which avoids effects of mechanical resonance and suppresses frequencies within +/- P1101 (skip frequency bandwidth).		
Note:	See P1091 (skip frequency 1).		
p1101[0...2]	Skip frequency bandwidth / Skipfreq bandwidth		
	Access level: 3	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 10.00 [Hz]	Factory setting 2.00 [Hz]
Description:	Delivers frequency bandwidth to be applied to skip frequencies (in [Hz]).		
Note:	See P1091 (skip frequency 1).		
p1110[0...2]	BI: Inhibit neg. freq. setpoint / Inh. neg. setp		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	This parameter suppresses negative setpoints. Therefore, modification of the motor direction is inhibited to the setpoint channel. If a min. frequency (P1080) and a negative setpoint are given, the motor is accelerated by a positive value in relationship to the min. frequency.		
p1113[0...2]	BI: Reverse / Reverse		
CU240E	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 722.1
Description:	Defines source of reverse command used when P0719 = 0 (Auto selection of command/setpoint source).		
p1113[0...2]	BI: Reverse / Reverse		
CU240S DP	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 2090.11
Description:	Defines source of reverse command used when P0719 = 0 (Auto selection of command/setpoint source).		

p1113[0...2]	BI: Reverse / Reverse		
CU240S PN	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S PN-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	8890.11
Description:	Defines source of reverse command used when P0719 = 0 (Auto selection of command/setpoint source).		
r1114	CO: Freq. setp. after dir. ctrl. / Setp<-dir.ctrl.		
	Access level: 3	P-Group: Setpoints	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays setpoint frequency after change of direction.		
r1119	CO: Freq. setpoint before RFG / Setp before RFG		
	Access level: 3	P-Group: Setpoints	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	<p>Displays frequency setpoint at the input to the ramp function generator after modification by other functions, e.g.:</p> <ul style="list-style-type: none"> • P1110 BI: Inhibit neg. freq. setpoint, • P1091 - P1094 skip frequencies, • P1080 min. frequency, • P1082 max. frequency, <p>This value is available filtered (r0020) and unfiltered (r1119).</p>		
p1120[0...2]	Ramp-up time / Ramp-up time		
	Access level: 1	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1), U, T	Calculated: -	
	Min	Max	Factory setting
	0.00 [s]	650.00 [s]	10.00 [s]
Description:	<p>Time taken for motor to accelerate from standstill up to maximum motor frequency (P1082) when no rounding is used.</p> <p>Setting the ramp-up time too short can cause the inverter to trip (overcurrent F0001).</p>		
Dependency:	Rounding times (P1130 - P1133) and rounding type (P1134) will also have influence on the ramp.		
Notice:	<p>Ramp times will be used as follows:</p> <ul style="list-style-type: none"> • P1060 / P1061 : JOG mode is active • P1120 / P1121 : Normal mode (ON/OFF) is active • P1060 / P1061 : Normal mode (ON/OFF) and P1124 is active 		
Note:	<p>If an external frequency setpoint with set ramp rates is used (e.g. from a PLC), the best way to achieve optimum drive performance is to set ramp times in P1120 and P1121 slightly shorter than those of the PLC.</p> <p>Changes to P1120 will be immediately effective.</p>		

p1121[0...2]	Ramp-down time / Ramp-down time		
	Access level: 1	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1), U, T	Calculated: -	
	Min 0.00 [s]	Max 650.00 [s]	Factory setting 10.00 [s]
Description:	Time taken for motor to decelerate from maximum motor frequency (P1082) down to standstill when no rounding is used.		
Notice:	Setting the ramp-down time too short can cause the inverter to trip (overcurrent F0001 / overvoltage F0002). Ramp times will be used as follows: <ul style="list-style-type: none"> • P1060 / P1061 : JOG mode is active • P1120 / P1121 : Normal mode (ON/OFF) is active • P1060 / P1061 : Normal mode (ON/OFF) and P1124 is active 		
Note:	Changes to P1121 will be immediately effective.		
p1124[0...2]	BI: Enable JOG ramp times / Enable JOG ramp		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	Defines source for switching between jog ramp times (P1060, P1061) and normal ramp times (P1120, P1121) as applied to the RFG. This parameter is valid for normal mode (ON/OFF) only.		
Notice:	P1124 does not have any impact when JOG mode is selected. In this case, jog ramp times (P1060, P1061) will be used all the time. Ramp times will be used as follows: <ul style="list-style-type: none"> • P1060 / P1061 : JOG mode is active • P1120 / P1121 : Normal mode (ON/OFF) is active • P1060 / P1061 : Normal mode (ON/OFF) and P1124 is active 		
p1130[0...2]	Ramp-up initial rounding time / Ramp-up ini. Trnd		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [s]	Max 40.00 [s]	Factory setting 0.00 [s]
Description:	Defines rounding time in seconds at start of ramp-up.		
Notice:	Rounding times are recommended, since they prevent an abrupt response, thus avoiding detrimental effects on the mechanics. Rounding times are not recommended when analog inputs are used, since they would result in overshoot/undershoot in the inverter response.		
Note:	If short or zero ramp times (P1120, P1121 < P1130, P1131, P1132, P1133) are set, the total ramp up time (t _{up}) or ramp down time (t _{down}) will not depend on P1130.		

p1131[0...2]	Ramp-up final rounding time / Ramp-up final Trnd		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [s]	Max 40.00 [s]	Factory setting 0.00 [s]
Description:	Defines rounding time at end of ramp-up.		
Notice:	Rounding times are not recommended when analog inputs are used, since they would result in overshoot/undershoot in the inverter response.		
Note:	Rounding times are recommended, since they prevent an abrupt response, thus avoiding detrimental effects on the mechanics.		
p1132[0...2]	Ramp-down initial rounding time / Ramp-dwn ini. Trnd		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [s]	Max 40.00 [s]	Factory setting 0.00 [s]
Description:	Defines rounding time at start of ramp-down.		
Notice:	Rounding times are not recommended when analog inputs are used, since they would result in overshoot/undershoot in the inverter response.		
Note:	Rounding times are recommended, since they prevent an abrupt response, thus avoiding detrimental effects on the mechanics.		
p1133[0...2]	Ramp-down final rounding time / Ramp-dwn fin. Trnd		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [s]	Max 40.00 [s]	Factory setting 0.00 [s]
Description:	Defines rounding time at end of ramp-down.		
Notice:	Rounding times are not recommended when analog inputs are used, since they would result in overshoot/undershoot in the inverter response.		
Note:	Rounding times are recommended, since they prevent an abrupt response, thus avoiding detrimental effects on the mechanics.		
p1134[0...2]	Rounding type / Rounding type		
	Access level: 2	P-Group: Setpoints	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0	Max 1	Factory setting 0
Description:	Defines the smoothing which is active by setpoint modifications during acceleration or deceleration (e.g. new setpoint, OFF1, OFF3, REV). This smoothing is applied, if the motor is ramped-up or ramped-down and <ul style="list-style-type: none"> • P1134 = 0, • P1132 > 0, P1133 > 0 and • the setpoint is not yet reached. 		
Value:	0: Continuous smoothing 1: Discontinuous smoothing		
Dependency:	Effect only when P1130 (Ramp-up initial rounding time) or P1131 (Ramp-up final rounding time) or P1132 (Ramp-down initial rounding time) or P1133 (Ramp-down final rounding time) > 0 s.		

p1135[0...2]	OFF3 ramp-down time / OFF3 ramp-dwn time		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1), U, T	Calculated: -	
	Min 0.00 [s]	Max 650.00 [s]	Factory setting 5.00 [s]
Description:	Defines ramp-down time from maximum frequency to standstill for OFF3 command. Settings in P1130 and P1134 will have no effect on OFF3 ramp-down characteristic. An initial ramp-down rounding time of approximately 10% of P1135 is however included. For the total OFF3 ramp-down time: $t_{down,OFF3} = f(p1134) = 1.1 * p1135 * (f_{2} / p1082)$		
Note:	This time may be exceeded if the VDC_max. level is reached.		
p1140[0...2]	BI: RFG enable / RFG enable		
CU240E	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 1
Description:	Defines command source of RFG enable command (RFG: ramp function generator). If binary input is equal to zero then the RFG output will be set immediately to 0.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
p1140[0...2]	BI: RFG enable / RFG enable		
CU240S DP	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 2090.4
Description:	Defines command source of RFG enable command (RFG: ramp function generator). If binary input is equal to zero then the RFG output will be set immediately to 0.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
p1140[0...2]	BI: RFG enable / RFG enable		
CU240S PN	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S PN-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 8890.4
Description:	Defines command source of RFG enable command (RFG: ramp function generator). If binary input is equal to zero then the RFG output will be set immediately to 0.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		

p1141[0...2]	BI: RFG start / RFG start		
CU240E	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	1
Description:	Defines command source of RFG start command (RFG: ramp function generator). If binary input is equal to zero then the RFG output is held at its present value.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
p1141[0...2]	BI: RFG start / RFG start		
CU240S DP	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	2090.5
Description:	Defines command source of RFG start command (RFG: ramp function generator). If binary input is equal to zero then the RFG output is held at its present value.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
p1141[0...2]	BI: RFG start / RFG start		
CU240S PN	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S PN-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	8890.5
Description:	Defines command source of RFG start command (RFG: ramp function generator). If binary input is equal to zero then the RFG output is held at its present value.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
p1142[0...2]	BI: RFG enable setpoint / RFG enable setp		
CU240E	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	1
Description:	Defines command source of RFG enable setpoint command (RFG: ramp function generator). If binary input is equal to zero then the RFG input will be set to zero and the RFG output will ramp-down to zero.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
p1142[0...2]	BI: RFG enable setpoint / RFG enable setp		
CU240S DP	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	2090.6
Description:	Defines command source of RFG enable setpoint command (RFG: ramp function generator). If binary input is equal to zero then the RFG input will be set to zero and the RFG output will ramp-down to zero.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		

p1142[0...2]	BI: RFG enable setpoint / RFG enable setp		
CU240S PN	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S PN-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	8890.6
Description:	Defines command source of RFG enable setpoint command (RFG: ramp function generator). If binary input is equal to zero then the RFG input will be set to zero and the RFG output will ramp-down to zero.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
r1170	CO: Frequency setpoint after RFG / Setp. after RFG		
	Access level: 3	P-Group: Setpoints	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays overall frequency setpoint after ramp generator.		
p1200	Flying start / Flying start		
	Access level: 2	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: C, U, T	Calculated: -	
	Min	Max	Factory setting
	0	6	0
Description:	Starts inverter onto a spinning motor by rapidly changing the output frequency of the inverter until the actual motor speed has been found. Then, the motor runs up to setpoint using the normal ramp time.		
Value:	0: Flying start disabled 1: Flying start always active, start --> setpoint 2: Flying start active if power on, fault, OFF2, start --> setp. 3: Flying start active if fault, OFF2, start --> setpoint 4: Flying start always active, only --> setpoint 5: Flying start active if power on, fault, OFF2, only --> setp. 6: Flying start active if fault, OFF2, only --> setpoint		
Notice:	Flying start must be used in cases where the motor may still be turning (e.g. after a short mains break) or can be driven by the load. Otherwise, overcurrent trips will occur.		
Note:	Useful for motors with high inertia loads. Settings 1 to 3 search in both directions. Settings 4 to 6 search only in direction of setpoint.		
p1202[0...2]	Motor-current: Flying start / Mot. cur: Flystart		
	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: C, U, T	Calculated: -	
	Min	Max	Factory setting
	10 [%]	200 [%]	100 [%]
Description:	Defines search current used for flying start. Value is in [%] based on rated motor current (P0305).		
Note:	Reducing the search current may improve performance for flying start if the inertia of the system is not very high.		

p1203[0...2]	Search rate: Flying start / SrchRate: Flystart		
	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: C, U, T	Calculated: -	
	Min 10 [%]	Max 200 [%]	Factory setting 100 [%]
Description:	Sets factor (in V/f mode only) by which the output frequency changes during flying start to synchronize with turning motor. This value is entered in [%]. It defines the reciprocal initial gradient in the search sequence. Parameter P1203 influences the time taken to search for the motor frequency.		
Example:	For a motor with 50 Hz, 1350 rpm, 100 % would produce a maximum search time of 600 ms.		
Note:	A higher value produces a flatter gradient and thus a longer search time. A lower value has the opposite effect.		

r1204	Status word: Flying start V/f / Stat: Flystart V/f				
	Access level: 4	P-Group: -	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Bit parameter for checking and monitoring states during search, if V/f control mode is selected (P1300 < 20).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Current applied	Yes	No	-
	01	Current could not be applied	Yes	No	-
	02	Voltage reduced	Yes	No	-
	03	Slope-filter started	Yes	No	-
	04	Current less threshold	Yes	No	-
	05	Current-minimum	Yes	No	-
	07	Speed could not be found	Yes	No	-

r1205	Status word: Flying start SLVC / Stat Flystart SLVC				
	Access level: 3	P-Group: -	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Bit parameter for checking status of flying start performed with n-adaption of observer. Parameter is only valid, if sensorless vector control (SLVC) is selected (P1300 = 20, 22).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Transformation active	Yes	No	-
	01	Initialize n-adaption	Yes	No	-
	02	Current applying	Yes	No	-
	03	n-controller closed	Yes	No	-
	04	Isd-controller open	Yes	No	-
	05	RFG hold	Yes	No	-
	06	n-adaption set to zero	Yes	No	-
	07	reserved	Yes	No	-
	08	reserved	Yes	No	-
	09	reserved	Yes	No	-
	10	Direction Positive	Yes	No	-
	11	Search is started	Yes	No	-
	12	Current is applied	Yes	No	-
	13	Search is aborted	Yes	No	-
	14	Deviation is zero	Yes	No	-
	15	n-controller is active	Yes	No	-

p1210	Automatic restart / Automatic restart		
	Access level: 2	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: C, U, T	Calculated: -	
	Min 0	Max 6	Factory setting 1

Description: Configures automatic restart function

Value:

0:	Disabled	
1:	Trip reset after power on,	P1211 disabled
2:	Restart after mains blackout,	P1211 disabled
3:	Restart after mains brownout or fault,	P1211 enabled
4:	Restart after mains brownout,	P1211 enabled
5:	Restart after mains blackout and fault,	P1211 disabled
6:	Restart after mains brown- /blackout or fault,	P1211 enabled

Dependency: Automatic restart requires constant ON command via a digital input wire link.

Caution: P1210 > 2 can cause the motor to restart automatically without toggling the ON command !



Notice:

A "mains brownout" is where the power is interrupted and re-applied before the display on the BOP (if one is fitted to the inverter) has gone dark (a very short mains break where the DC link has not fully collapsed).

A "mains blackout" is a long mains break, where the DC link has fully collapsed before the power is re-applied.

"Delay Time" is the time between attempts of quitting fault. The "Delay Time" of first attempt is 1 second, then it will be doubled every next attempt.

The "Number of Restart Attempts" can be set in P1211. This is the number of restarts the inverter will try to quit fault.

When faults are quit and after 4 seconds of no fault condition, "Number of Restart Attempts" will be reset to P1211 and "Delay Time" will be reset to 1 second.

P1210 = 0:

Automatic restart is disabled.

P1210 = 1:

The inverter will acknowledge (reset) faults i.e. it will reset a fault when the is re-applied. This means the inverter must be fully powered down, a brownout is not sufficed. The inverter will not run until the ON command has been toggled.

P1210 = 2:

The inverter will acknowledge the fault F0003 at power on after blackout and restarts the drive. It is necessary that the ON command is wired via a digital input (DI).

P1210 = 3:

For these settings it is fundamental that the drive only restarts if it has been in a RUN state at the time of the faults (F0003, etc.). The inverter will acknowledge the fault and restarts the drive after a blackout or brownout. It is necessary that the ON command is wired via a digital input (DI).

P1210 = 4:

For these settings it is fundamental that the drive only restarts if it has been in a RUN state at the time of the fault (F0003). The inverter will acknowledge the fault and restarts the drive after a blackout or brownout. It is necessary that the ON command is wired via a digital input (DI).



P1210 = 5:

The inverter will acknowledge the faults F0003 etc. at power on after blackout and restarts the drive. It is necessary that the ON command is wired via a digital input (DI).



P1210 = 6:

The inverter will acknowledge the faults (F0003 etc.) at power on after blackout or brownout and restarts the drive. It is necessary that the ON command is wired via a digital input (DI). Setting 6 causes the motor to restart immediately.

Flying start must be used in cases where the motor may still be turning (e.g. after a short mains break) or can be driven by the load (P1200).

p1211	Number of restart attempts / Restart attempts		
	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: C, U, T	Calculated: -	
	Min 0	Max 10	Factory setting 3
Description:	Specifies number of times inverter will attempt to restart if automatic restart P1210 is activated.		
p1215	Holding brake enable / MHB enable		
CU240E	Access level: 2	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: C, T	Calculated: -	
	Min 0	Max 1	Factory setting 0
Description:	Enables/disables holding brake function. The motor holding brake (MHB) is controlled via status word 1 r0052 Bit12. This signal can be issued via: <ul style="list-style-type: none"> status word of the serial interface (e.g. USS) digital outputs (e.g. DO0: ==> P0731 = 52.C (r0052 Bit12)) 		
Value:	0: Motor holding brake disabled 1: Motor holding brake enabled		
Caution:	It is not permissible to use the motor holding brake as working brake, as it is generally only designed for a limited number of emergency braking operations.		
			
Note:	In sensorless vector control mode (P1300 = 20) the following should be valid: <ul style="list-style-type: none"> The value of the min. Frequency P1080 should be zero. 		
p1215	Holding brake enable / MHB enable		
CU240S	Access level: 2	P-Group: -	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: NO	Data set: -
CU240S DP-F	Can be changed: C, T	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min 0	Max 1	Factory setting 0
Description:	Enables/disables holding brake function. The motor holding brake (MHB) is controlled via status word 1 r0052 Bit12. This signal can be issued via: <ul style="list-style-type: none"> status word of the serial interface (e.g. USS) digital outputs (e.g. DO0: ==> P0731 = 52.C (r0052 Bit12)) 		
Value:	0: Motor holding brake disabled 1: Motor holding brake enabled		
Caution:	It is not permissible to use the motor holding brake as working brake, as it is generally only designed for a limited number of emergency braking operations.		
			
Note:	In a vector control mode (P1300 = 20 or P1300 = 21) the following should be valid: <ul style="list-style-type: none"> The value of the min. Frequency P1080 should be zero. The delay speed loss reaction should be > brake holding times (i.e. P0494 > P1216 and P0494 > P1217) The delay time for motor pulled out should be > brake holding times (i.e. P2178 > P1216 and P2178 > P1217) Otherwise there may be encoder loss trips (F0090) when the brake is applied and pulses are enabled.		

p1216	Holding brake release delay / MHB release delay		
	Access level: 2	P-Group: -	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: C, T	Calculated: -	
	Min 0.0 [s]	Max 20.0 [s]	Factory setting 1.0 [s]
Description:	Defines period during which inverter runs at min. frequency P1080 before ramping up.		
p1217	Holding time after ramp down / Thold. <- ramp-dwn		
	Access level: 2	P-Group: -	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: C, T	Calculated: -	
	Min 0.0 [s]	Max 20.0 [s]	Factory setting 1.0 [s]
Description:	Defines time for which inverter runs at minimum frequency (P1080) after ramping down.		
Note:	If P1217 > P1227, parameter P1227 will take precedence.		
p1218[0...2]	BI: MHB override / MHB override		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: U, T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	Enables the MHB output to be overridden, allowing the brake to be opened under separate control.		
p1227[0...2]	Zero speed detection monitoring time / Zero speed time		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [s]	Max 300.0 [s]	Factory setting 4.0 [s]
Description:	Sets the monitoring time for the standstill identification. When braking with OFF1 or OFF3, standstill is identified after this time has expired, after the setpoint speed has fallen below P2167. After this, the braking signal is started, the system waits for the closing time and then the pulses are cancelled.		
Note:	P1227 = 300.0 : function is deactivated P1227 = 0.0 : pulses are locked immediately If P1217 > P1227, parameter P1227 will take precedence.		

p1230[0...2] BI: Enable DC braking / Enable DC brk.			
CU240E	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S	Quick comm. NO	Active: NO	Data set: CDS
CU240S DP	Can be changed: U, T	Calculated: -	
CU240S DP-F			
CU240S PN			
CU240S PN-F			
PM240			
	Min	Max	Factory setting
	-	-	0
Description:	<p>Enables DC braking via a signal applied from an external source. Function remains active while external input signal is active. DC braking causes the motor to stop rapidly by applying a DC braking current (current applied also holds shaft stationary). When the DC braking signal is applied, the inverter output pulses are blocked and the DC current is not applied until the motor has been sufficiently demagnetized. This delay time is set in P0347 (demagnetization time). If this delay is too short, overcurrent trips can occur. The level of DC braking is set in P1232 (DC braking current - relative to the rated motor current) which is set to 100 % by default.</p>		
Dependency:	When Standard Telegram 350 and PROFIBUS selected (p0700 = 6, p0922 = 350), parameter cannot be changed.		
Caution:	<p>With the DC braking, the kinetic energy of the motor is converted into heat in the motor. The drive could overheat if it remains in this status for an excessive period of time ! DC braking is not possible when using a synchronous motor (i.e. P0300 = 2).</p>		
			
p1232[0...2] DC braking current / DC braking current			
PM240	Access level: 2	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: C, U, T	Calculated: -	
	Min	Max	Factory setting
	0 [%]	250 [%]	100 [%]
Description:	<p>Defines level of DC current in [%] relative to rated motor current (P0305). The DC braking can be issued observing the following dependencies:</p> <ul style="list-style-type: none"> • OFF1 / OFF3 ==> see P1233 • BICO ==> see P1230 		
p1233[0...2] Duration of DC braking / DC brak. duration			
PM240	Access level: 2	P-Group: -	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: C, U, T	Calculated: -	
	Min	Max	Factory setting
	0.00 [s]	250.00 [s]	0.00 [s]
Description:	<p>Defines duration for which DC braking is active following an OFF1 or OFF3 command. When an OFF1 or OFF3 command is received by the drive, the output frequency starts to ramp to 0 Hz. When the output frequency reaches the value set in P1234, the drive injects a DC braking current P1232 for the time duration set in P1233.</p>		
Caution:	<p>With the DC braking, the kinetic energy of the motor is converted into heat in the motor. The drive could overheat if it remains in this status for an excessive period of time ! DC braking is not possible when using a synchronous motor (i.e. P0300 = 2).</p>		
			
Notice:	<p>The DC braking function causes the motor to stop rapidly by applying a DC braking current. When the DC braking signal is applied, the inverter output pulses are blocked and the DC current not applied until the motor has been sufficiently demagnetized (demagnetization time is calculated automatically from motor data).</p>		
Note:	P1233 = 0 means that DC braking is not activated.		

p1234[0...2]		DC braking start frequency / DC brk. start freq	
PM240	Access level: 2	P-Group: -	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: C, U, T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 650.00 [Hz]
Description:	Sets start frequency for DC braking. When an OFF1 or OFF3 command is received by the drive, the output frequency starts to ramp to 0 Hz. When the output frequency reaches the value set in start frequency of DC braking P1234, the drive injects a DC braking current P1232 for the time duration set in P1233.		
p1236[0...2]		Compound braking current / Compound brk. cur.	
PM240	Access level: 2	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: C, U, T	Calculated: -	
	Min 0 [%]	Max 250 [%]	Factory setting 0 [%]
Description:	Defines DC level superimposed on AC waveform after exceeding DC-link voltage threshold of compound braking. The value is entered in [%] relative to rated motor current (P0305). Compound braking switch-on level (V_DC,Comp) : If p1254 = 0 --> V_DC,Comp = 1.13 * sqrt(2) * V_mains = 1.13 * sqrt(2) * p0210 otherwise V_DC,Comp = 0.98 * r1242 The Compound Brake is an overlay of the DC brake function with regenerative braking (effective braking at the ramp) after OFF1 or OFF3. This enables braking with controlled motor frequency and a minimum of energy returned to the motor. Through optimization of the ramp-down time and the compound braking an efficient braking without additional HW components is possible.		
Dependency:	Compound braking depends on the DC link voltage only (see threshold above). This will happen on OFF1, OFF3 and any regenerative condition. It is disabled, when: <ul style="list-style-type: none"> • DC braking is active • Flying start is active • Vector mode (SLVC, VC) is selected 		
Notice:	Increasing the value will generally improve braking performance; however, if you set the value too high, an overcurrent trip may result. If used with dynamic braking enabled as well compound braking will take priority. If used with the Vdc max controller enabled the drive behaviour whilst braking may be worsened particularly with high values of compound braking. Compound braking does not work when the drive is in vector control.		
Note:	P1236 = 0 means that compound braking is not activated.		

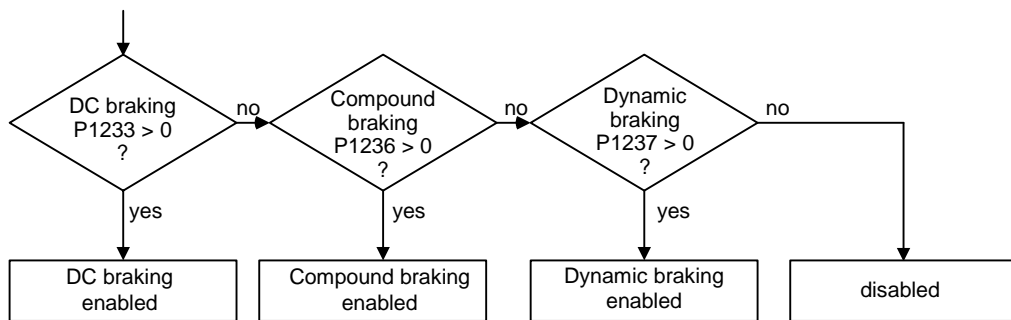
p1237 Dynamic braking / Dynamic braking
 PM240 **Access level:** 2 **P-Group:** - **Data type:** Unsigned16
Quick comm. NO **Active:** YES **Data set:** -
Can be changed: C, U, T **Calculated:** -

Min 0 **Max** 5 **Factory setting** 0

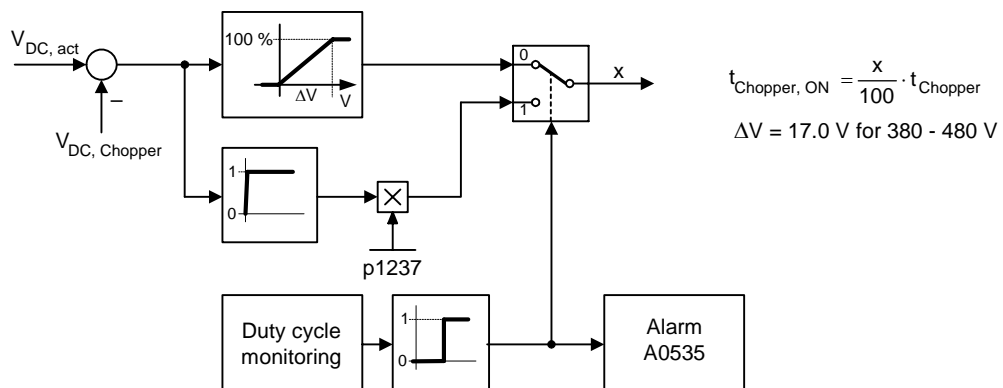
Description: Dynamic braking absorbs the braking energy in a chopper resistor.
 This parameter defines the rated duty cycle of the braking resistor (chopper resistor).
 Dynamic braking is active when the function is enabled and DC-link voltage exceeds the dynamic braking switch-on level.
 Dynamic braking switch-on level ($V_{DC,Chopper}$):
 If $p1254 = 0 \rightarrow V_{DC,Chopper} = 1.13 \cdot \sqrt{2} \cdot V_{mains} = 1.13 \cdot \sqrt{2} \cdot p0210$
 otherwise $V_{DC,Chopper} = 0.98 \cdot r1242$

Value:
 0: Disabled
 1: 5 % duty cycle
 2: 10 % duty cycle
 3: 20 % duty cycle
 4: 50 % duty cycle
 5: 100 % duty cycle


Dependency: If dynamic braking is used with DC braking enabled as well as compound braking, DC braking and compound braking will take priority.



Notice: Initially the brake will operate at a high duty cycle dependant on the DC link level until the thermal limit is approached.
 The duty cycle specified by this parameter will then be imposed.
 The resistor should be able to operate at this level indefinitely without overheating.




The threshold for the warning A0535 is equivalent to 10 seconds running at 95 % duty cycle.
 The duty cycle will be limited when it was running 12 seconds at 95 % duty cycle.

p1240[0...2] Configuration of Vdc controller / Vdc controller			
PM240	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: C, T	Calculated: -	
	Min 0	Max 3	Factory setting 1
Description:	Enables / disables Vdc controller. The Vdc controller dynamically controls the DC link voltage to prevent overvoltage trips on high inertia systems.		
Value:	0: Vdc controller disabled 1: Vdc-max controller enabled 2: Kinetic buffering (Vdc-min controller) enabled 3: Vdc-max controller and kinetic buffering (KIB) enabled		
Caution:	If P1245 increased too much, it may interfere with the drive normal operation.		
			
Note:	<ul style="list-style-type: none"> Vdc-max controller: Vdc-max controller automatically increases ramp-down times to keep the DC-link voltage (r0026) within limits (r1242). Vdc-min controller: Vdc-min is activated if DC-link voltage falls below the switch on level P1245. The kinetic energy of the motor is then used to buffer the DC-link voltage, thus causing deceleration of the drive. If the drive trips with F0003 immediately, try increasing the dynamic factor P1247 first. If still tripping with F0003 try then increasing the switch on level P1245. 		

r1242 CO: Switch-on level of Vdc-max / Vdc-max ON lev			
PM240	Access level: 3	P-Group: -	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays switch-on level of Vdc max controller. Following equation is only valid, if p1254 = 0 : $r1242 = 1.15 * \sqrt{2} * V_mains = 1.15 * \sqrt{2} * p0210$ otherwise r1242 is internally calculated.		

p1243[0...2] Dynamic factor of Vdc-max / Vdc-max dyn. fact.			
PM240	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: C, U, T	Calculated: -	
	Min 10 [%]	Max 200 [%]	Factory setting 100 [%]
Description:	Defines dynamic factor for DC link controller in [%].		
Dependency:	P1243 = 100 % means parameters P1250, P1251 and P1252 (gain, integration time and differential time) are used as set. Otherwise, these are multiplied by P1243 (dynamic factor of Vdc-max).		
Note:	Vdc controller adjustment is calculated automatically from motor and inverter data.		

p1245[0...2]	Switch on level kin. buffering / KIB ON level		
PM240	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: C, U, T	Calculated: -	
	Min 65 [%]	Max 115 [%]	Factory setting 76 [%]
Description:	Enter switch-on level for kinetic buffering (KIB) in [%] relative to supply voltage (P0210). $r1246[V] = (p1245[\%] / 100) * \sqrt{2} * p0210$		
Warning:	Increasing the value too much, may interfere with the drive normal operation.		
			
Note:	P1254 has no effect on the switch-on-level for KIB.		
r1246[0...2]	CO: Switch-on level kin buffering / KIB ON level		
PM240	Access level: 3	P-Group: -	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: DDS
Description:	Displays switch-on level of kinetic buffering (KIB, Vdc min controller). If the dc-link voltage drops below the value in r1246, kinetic buffering will be activated. That means the motor frequency will be reduced in order to keep Vdc within the valid range. If there is not enough regenerative energy, the converter trips with undervoltage.		
p1247[0...2]	Dyn. factor of kinetic buffering / Dyn. factor of KIB		
PM240	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: C, U, T	Calculated: -	
	Min 10 [%]	Max 200 [%]	Factory setting 100 [%]
Description:	Enters dynamic factor for kinetic buffering (KIB, Vdc-min controller). P1247 = 100 % means parameters P1250, P1251 and P1252 (gain, integration time and differential time) are used as set. Otherwise, these are multiplied by P1247 (dynamic factor of Vdc-min).		
Note:	Vdc controller adjustment is calculated automatically from motor and inverter data.		
p1250[0...2]	Gain of Vdc-controller / Gain of Vdc ctrl.		
PM240	Access level: 3	P-Group: -	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: C, U, T	Calculated: -	
	Min 0.00	Max 10.00	Factory setting 1.00
Description:	Enters gain for Vdc controller.		
p1251[0...2]	Integration time Vdc-controller / Int. time Vdc ctrl		
PM240	Access level: 3	P-Group: -	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: C, U, T	Calculated: -	
	Min 0.1 [ms]	Max 1000.0 [ms]	Factory setting 40.0 [ms]
Description:	Enters integral time constant for Vdc controller.		

p1252[0...2]	Differential time Vdc-controller / Diff.time Vdc ctrl		
PM240	Access level: 3	P-Group: -	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: C, U, T	Calculated: -	
	Min 0.0 [ms]	Max 1000.0 [ms]	Factory setting 1.0 [ms]
Description:	Enters differential time constant for Vdc controller.		
p1253[0...2]	Vdc-controller output limitation / Vdc ctrl outp. lim		
	Access level: 3	P-Group: -	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: C, U, T	Calculated: CALC_MOD_REG	
	Min 0.00 [Hz]	Max 600.00 [Hz]	Factory setting 10.00 [Hz]
Description:	Limits maximum effect of Vdc max controller.		
Note:	The Factory setting depends on inverter power.		
p1254	Auto detect Vdc switch-on levels / Autodet Vdc ON lev		
PM240	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: C, T	Calculated: -	
	Min 0	Max 1	Factory setting 1
Description:	Enables/disables auto-detection of switch-on levels for Vdc max controller.		
Value:	0: Disabled 1: Enabled		
p1256[0...2]	Reaction of kinetic buffering / Reaction of KIB		
PM240	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: C, T	Calculated: -	
	Min 0	Max 2	Factory setting 0
Description:	Enters reaction for kinetic buffering controller (Vdc-min controller). Depending on the setting selected, the frequency limit defined in P1257 is used to either hold the speed or disable pulses. If not enough regeneration is produced, drive may trip with undervoltage.		
Value:	0: Maintain DC-link until trip 1: Maintain DC-link until trip / stop 2: Control stop		
Note:	P1256 = 0: Maintain DC-link voltage until mains is returned or drive is tripped with undervoltage. The frequency is kept above the frequency limit provided in P1257. P1256 = 1: Maintain DC-link voltage until mains is returned or drive is tripped with undervoltage or pulses are disabled when frequency falls below the limit in P1257. P1256 = 2: This option ramps down the frequency to standstill even when mains return. If mains does not return, frequency brought down under the control of vdc-min controller until P1257 limit. Then pulses are disabled or undervoltage has occurred. If mains return, then an OFF1 is active until P1257 limit. Then pulses are disabled.		

p1257[0...2]	Freq limit for kinetic buffering / Freq limit for KIB		
PM240	Access level: 3	P-Group: Setpoints	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 600.00 [Hz]	Factory setting 2.50 [Hz]
Description:	Frequency which kinetic buffering (KIB) either hold speed or disable pulses depending on P1256.		

p1300[0...2]	Control mode / Control mode		
CU240E	Access level: 2	P-Group: Closed-loop control	Data type: Unsigned16
	Quick comm. YES	Active: NO	Data set: DDS
	Can be changed: C(1), T	Calculated: -	
	Min 0	Max 22	Factory setting 0

Description: Parameter to select the control method.
Controls relationship between speed of motor and voltage supplied by inverter.

Value:

- 0: V/f with linear characteristic
- 1: V/f with FCC
- 2: V/f with quadratic characteristic
- 3: V/f with programmable characteristic
- 4: reserved
- 5: V/f for textile applications
- 6: V/f with FCC for textile applications
- 19: V/f control with independent voltage setpoint
- 20: Sensorless vector control
- 22: Sensorless vector torque-control

Dependency: See parameter P0205, P0500

Note:

P1300 = 1 : V/f with FCC (flux current control)

- Maintains motor flux current for improved efficiency.
- If FCC is chosen, linear V/f is active at low frequencies.

P1300 = 2 : V/f with a quadratic characteristic

- Suitable for centrifugal fans / pumps

P1300 = 3 : V/f with a programmable characteristic

- User defined characteristic (see P1320)
- For synchronous motors (e.g. SIEMOSYN motors)

P1300 = 5,6 : V/f for textile applications

- Slip compensation disabled.
- I_{max} controller modifies the output voltage only.
- I_{max} controller does not influence the output frequency.

P1300 = 19 : V/f control with independent voltage setpoint

The following table presents an overview of control parameters (V/f) that can be modified in relationship to P1300 dependencies:

ParNo.	Parameter name	Level	V/f							SLVC	VC		
			p1300 =										
			0	1	2	3	5	6	19	20	22	21	23
p1300[3]	Control mode	2	x	x	x	x	x	x	x	x	x	x	x
p1310[3]	Continuous boost	2	x	x	x	x	x	x	x	-	-	-	-
p1311[3]	Acceleration boost	2	x	x	x	x	x	x	x	-	-	-	-
p1312[3]	Starting boost	2	x	x	x	x	x	x	x	-	-	-	-
p1316[3]	Boost end frequency	3	x	x	x	x	x	x	x	-	-	-	-
p1320[3]	Programmable V/f freq. coord. 1	3	-	-	-	x	-	-	-	-	-	-	-
p1321[3]	Programmable V/f volt. coord. 1	3	-	-	-	x	-	-	-	-	-	-	-
p1322[3]	Programmable V/f freq. coord. 2	3	-	-	-	x	-	-	-	-	-	-	-
p1323[3]	Programmable V/f volt. coord. 2	3	-	-	-	x	-	-	-	-	-	-	-
p1324[3]	Programmable V/f freq. coord. 3	3	-	-	-	x	-	-	-	-	-	-	-
p1325[3]	Programmable V/f volt. coord. 3	3	-	-	-	x	-	-	-	-	-	-	-
p1330[3]	Cl: Voltage setpoint	3	-	-	-	-	-	-	x	-	-	-	-
p1333[3]	Start frequency for FCC	3	-	x	-	-	-	x	-	-	-	-	-
p1335[3]	Slip compensation	2	x	x	x	x	-	-	-	-	-	-	-
p1336[3]	CO: U/f Slip limit	2	x	x	x	x	-	-	-	-	-	-	-
p1338[3]	Resonance damping gain V/f	3	x	x	x	x	-	-	-	-	-	-	-
p1340[3]	I _{max} freq. controller prop. gain	3	x	x	x	x	x	x	x	-	-	-	-
p1341[3]	I _{max} controller integral time	3	x	x	x	x	x	x	x	-	-	-	-
p1345[3]	I _{max} controller prop. gain	3	x	x	x	x	x	x	x	-	-	-	-
p1346[3]	I _{max} voltage ctrl. integral time	3	x	x	x	x	x	x	x	-	-	-	-
p1350[3]	Voltage soft start	3	x	x	x	x	x	x	x	-	-	-	-

Sensorless vector control (SLVC, P1300 = 20,22):

SLVC can provide excellent performance for the following types of application:

- Applications which require high torque performance
- Applications which require fast respond to shock loading
- Applications which require torque holding while passing through 0 Hz
- Applications which require very accurate speed holding
- Applications which require motor pull out protection

Restrictions:

SLVC is dependent on the accuracy of the motor model being used and the measurements being performed by the inverter.

There are therefore certain restrictions on the use of SLVC:

- $f_{max} = \min(200 \text{ Hz}, 5 * p0310)$ (max. frequency)
- $(1 / 4) \leq (p0305 / r0207) \leq (r0209 / r0207)$ (ratio of rated motor current to rated inverter current)
- no synchronous motor

Recommended means of commissioning:

For correct operation under SLVC control it is imperative that the name plate data of the motor (P0304 - P0310) is correctly entered and that the motor data identification (P1900) must be carried out on a cold motor.

It is also necessary to ensure that the motor ambient temperature is correctly entered in P0625 if this is significantly different from the default value of 20°C.

This must be done after the quick commissioning has been completed (P3900) but before the motor data identification measurements are carried out.

Optimisation:

The following parameters can be adjusted by the user to improve performance.

- P0003 = 3
- P0342: Total / motor inertia ratio

Sensorless Vector Control (SLVC):

- P1470: P gain (SLVC)
- P1472: I term (SLVC)
- P1610: Continuous torque boost (SLVC, open loop boost)
- P1750: Control word of motor model

The following table presents an overview of control parameters (SLVC) that can be modified in relationship to P1300 dependencies:

ParNo.	Parameter name	Level	V/f							SLVC		VC	
			P1300 =							20	22	21	23
			0	1	2	3	5	6	19				
P1400[3]	Configuration of speed control	3	-	-	-	-	-	-	-	-	-	x	-
P1442[3]	Filter time for act. speed	3	-	-	-	-	-	-	-	-	-	x	-
P1452[3]	Filter time for act.speed (SLVC)	3	-	-	-	-	-	-	-	x	-	-	-
P1460[3]	Gain speed controller	2	-	-	-	-	-	-	-	-	-	x	-
P1462[3]	Integral time speed controller	2	-	-	-	-	-	-	-	-	-	x	-
P1470[3]	Gain speed controller (SLVC)	2	-	-	-	-	-	-	-	x	-	-	-
P1472[3]	Integral time n-ctrl. (SLVC)	2	-	-	-	-	-	-	-	x	-	-	-
P1477[3]	BI: Set integrator of n-ctrl.	3	-	-	-	-	-	-	-	x	-	x	-
P1478[3]	CI: Set integrator value n-ctrl.	3	-	-	-	-	-	-	-	x	-	x	-
P1488[3]	Droop input source	3	-	-	-	-	-	-	-	x	-	x	-
P1489[3]	Droop scaling	3	-	-	-	-	-	-	-	x	-	x	-
P1492[3]	Enable droop	3	-	-	-	-	-	-	-	x	-	x	-
P1496[3]	Scaling accel. precontrol	3	-	-	-	-	-	-	-	x	-	x	-
P1499[3]	Scaling accel. torque control	3	-	-	-	-	-	-	-	-	x	-	-
P1500[3]	Selection of torque setpoint	2	-	-	-	-	-	-	-	x	x	x	x
P1501[3]	BI: Change to torque control	3	-	-	-	-	-	-	-	x	x	x	x
P1503[3]	CI: Torque setpoint	3	-	-	-	-	-	-	-	-	x	-	x
P1511[3]	CI: Additional torque setpoint	3	-	-	-	-	-	-	-	x	x	x	x
P1520[3]	CO: Upper torque limit	2	-	-	-	-	-	-	-	x	x	x	x
P1521[3]	CO: Lower torque limit	2	-	-	-	-	-	-	-	x	x	x	x
P1522[3]	CI: Upper torque limit	3	-	-	-	-	-	-	-	x	x	x	x
P1523[3]	CI: Lower torque limit	3	-	-	-	-	-	-	-	x	x	x	x
P1525[3]	Scaling lower torque limit	3	-	-	-	-	-	-	-	x	x	x	x
P1530[3]	Motoring power limitation	2	-	-	-	-	-	-	-	x	x	x	x
P1531[3]	Regenerative power limitation	2	-	-	-	-	-	-	-	x	x	x	x
P1570[3]	CO: Fixed value flux setpoint	2	-	-	-	-	-	-	-	x	x	x	x
P1574[3]	Dynamic voltage headroom	3	-	-	-	-	-	-	-	x	x	x	x
P1580[3]	Efficiency optimization	2	-	-	-	-	-	-	-	x	x	x	x
P1582[3]	Smooth time for flux setpoint	3	-	-	-	-	-	-	-	x	x	x	x
P1596[3]	Int. time field weak. controller	3	-	-	-	-	-	-	-	x	x	x	x
P1610[3]	Continuous torque boost (SLVC)	2	-	-	-	-	-	-	-	x	x	-	-
P1611[3]	Acc. torque boost (SLVC)	2	-	-	-	-	-	-	-	x	x	-	-
P1740	Gain for oscillation damping	3	-	-	-	-	-	-	-	x	x	-	-
P1750[3]	Control word of motor model	3	-	-	-	-	-	-	-	x	x	x	x
P1755[3]	Start-freq. motor model (SLVC)	3	-	-	-	-	-	-	-	x	x	-	-
P1756[3]	Hyst.-freq. motor model (SLVC)	3	-	-	-	-	-	-	-	x	x	-	-
P1758[3]	T(wait) transit to feed-fwd-mode	3	-	-	-	-	-	-	-	x	x	-	-
P1759[3]	T(wait) for n-adaption to settle	3	-	-	-	-	-	-	-	x	x	-	-
P1764[3]	Kp of n-adaption (SLVC)	3	-	-	-	-	-	-	-	x	x	-	-
P1780[3]	Control word of Rs/Rr-adaption	3	-	-	-	-	-	-	-	x	x	-	-
P0400[3]	Select encoder type	2	-	-	-	-	-	-	-	-	-	x	x
P0408[3]	Encoder pulses per revolution	2	-	-	-	-	-	-	-	-	-	x	x
P0491[3]	Reaction on speed signal loss	2	-	-	-	-	-	-	-	-	-	x	x
P0492[3]	Allowed speed difference	2	-	-	-	-	-	-	-	-	-	x	x
P0494[3]	Delay speed loss reaction	2	-	-	-	-	-	-	-	-	-	x	x

1) If the speed control (main setpoint) is selected a torque setpoint is available via the additional setpoint channel.

p1300[0...2]	Control mode / Control mode		
CU240S	Access level: 2	P-Group: Closed-loop control	Data type: Unsigned16
CU240S DP	Quick comm. YES	Active: NO	Data set: DDS
CU240S DP-F	Can be changed: C(1), T	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min	Max	Factory setting
	0	23	0
Description:	Parameter to select the control method. Controls relationship between speed of motor and voltage supplied by inverter.		
Value:	0: V/f with linear characteristic 1: V/f with FCC 2: V/f with quadratic characteristic 3: V/f with programmable characteristic 4: reserved 5: V/f for textile applications 6: V/f with FCC for textile applications 19: V/f control with independent voltage setpoint 20: Sensorless vector control 21: Vector control with sensor 22: Sensorless vector torque-control 23: Vector torque-control with sensor		
Dependency:	See parameter P0205, P0500		
Caution:	When commissioning Vector Control with encoder-feedback (VC), the drive should be configured for V/f mode (see P1300) first. Run the drive and compare r0061 with r0021 that should agree in <ul style="list-style-type: none"> • sign and • magnitude (with a deviation of only a few percent). Only if both criteria are fulfilled, change P1300 and select VC (P1300 = 21 or 23).		
	P0400 = 1 (single channel encoder) will only allow operation in one direction. If operation in both directions is required, connect an encoder with 2 channels (A and B) and select setting 2. See the Operating Instructions of the encoder module for more information.		
Note:	P1300 = 1 : V/f with FCC (flux current control) <ul style="list-style-type: none"> • Maintains motor flux current for improved efficiency. • If FCC is chosen, linear V/f is active at low frequencies. P1300 = 2 : V/f with a quadratic characteristic <ul style="list-style-type: none"> • Suitable for centrifugal fans / pumps P1300 = 3 : V/f with a programmable characteristic <ul style="list-style-type: none"> • User defined characteristic (see P1320) • For synchronous motors (e.g. SIEMOSYN motors) P1300 = 5,6 : V/f for textile applications <ul style="list-style-type: none"> • Slip compensation disabled. • I_{max} controller modifies the output voltage only. • I_{max} controller does not influence the output frequency. P1300 = 19 : V/f control with independent voltage setpoint		
	The following table presents an overview of control parameters (V/f) that can be modified in relationship to P1300 dependencies:		

ParNo.	Parameter name	Level	V/f							SLVC		VC	
			p1300 =										
			0	1	2	3	5	6	19	20	22	21	23
p1300[3]	Control mode	2	x	x	x	x	x	x	x	x	x	x	x
p1310[3]	Continuous boost	2	x	x	x	x	x	x	x	-	-	-	-
p1311[3]	Acceleration boost	2	x	x	x	x	x	x	x	-	-	-	-
p1312[3]	Starting boost	2	x	x	x	x	x	x	x	-	-	-	-
p1316[3]	Boost end frequency	3	x	x	x	x	x	x	x	-	-	-	-
p1320[3]	Programmable V/f freq. coord. 1	3	-	-	-	x	-	-	-	-	-	-	-
p1321[3]	Programmable V/f volt. coord. 1	3	-	-	-	x	-	-	-	-	-	-	-
p1322[3]	Programmable V/f freq. coord. 2	3	-	-	-	x	-	-	-	-	-	-	-
p1323[3]	Programmable V/f volt. coord. 2	3	-	-	-	x	-	-	-	-	-	-	-
p1324[3]	Programmable V/f freq. coord. 3	3	-	-	-	x	-	-	-	-	-	-	-
p1325[3]	Programmable V/f volt. coord. 3	3	-	-	-	x	-	-	-	-	-	-	-
p1330[3]	Cl: Voltage setpoint	3	-	-	-	-	-	-	x	-	-	-	-
p1333[3]	Start frequency for FCC	3	-	x	-	-	-	x	-	-	-	-	-
p1335[3]	Slip compensation	2	x	x	x	x	-	-	-	-	-	-	-
p1336[3]	CO: U/f Slip limit	2	x	x	x	x	-	-	-	-	-	-	-
p1338[3]	Resonance damping gain V/f	3	x	x	x	x	-	-	-	-	-	-	-
p1340[3]	I _{max} freq. controller prop. gain	3	x	x	x	x	x	x	x	-	-	-	-
p1341[3]	I _{max} controller integral time	3	x	x	x	x	x	x	x	-	-	-	-
p1345[3]	I _{max} controller prop. gain	3	x	x	x	x	x	x	x	-	-	-	-
p1346[3]	I _{max} voltage ctrl. integral time	3	x	x	x	x	x	x	x	-	-	-	-
p1350[3]	Voltage soft start	3	x	x	x	x	x	x	x	-	-	-	-

Sensorless vector control (SLVC, P1300 = 20,22) and vector control (VC, P1300 = 21,23):

SLVC can provide excellent performance for the following types of application:

- Applications which require high torque performance
- Applications which require fast respond to shock loading
- Applications which require torque holding while passing through 0 Hz
- Applications which require very accurate speed holding
- Applications which require motor pull out protection

Restrictions:

SLVC /VC is dependent on the accuracy of the motor model being used and the measurements being performed by the inverter.

There are therefore certain restrictions on the use of SLVC / VC:

- $f_{max} = \min(200 \text{ Hz}, 5 * p0310)$ (max. frequency)
- $(1 / 4) \leq (p0305 / r0207) \leq (r0209 / r0207)$ (ratio of rated motor current to rated inverter current)
- no synchronuos motor

Recommended means of commissioning:

For correct operation under SLVC / VC control it is imperative that the name plate data of the motor (P0304 - P0310) is correctly entered and that the motor data identification (P1900) must be carried out on a cold motor.

It is also necessary to ensure that the motor ambient temperature is correctly entered in P0625 if this is significantly different from the default value of 20°C.

This must be done after the quick commissioning has been completed (P3900) but before the motor data identification measurements are carried out.

Optimisation:

The following parameters can be adjusted by the user to improve performance.

- P0003 = 3
- P0342: Total / motor inertia ratio

Sensorless Vector Control (SLVC):

- P1470: P gain (SLVC)
- P1472: I term (SLVC)
- P1610: Continuous torque boost (SLVC, open loop boost)
- P1750: Control word of motor model

Vector Control (VC):

- P1460: P gain
- P1462: I term

The following table presents an overview of control parameters (SLVC, VC) that can be modified in relationship to P1300 dependencies:

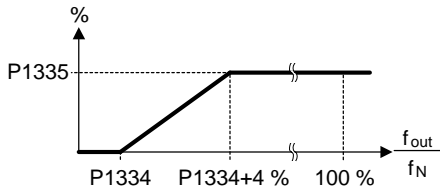
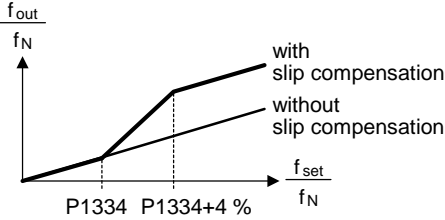
ParNo.	Parameter name	Level	V/f							SLVC		VC	
			P1300 =										
			0	1	2	3	5	6	19	20	22	21	23
P1400[3]	Configuration of speed control	3	-	-	-	-	-	-	-	-	-	x	-
P1442[3]	Filter time for act. speed	3	-	-	-	-	-	-	-	-	-	x	-
P1452[3]	Filter time for act.speed (SLVC)	3	-	-	-	-	-	-	-	x	-	-	-
P1460[3]	Gain speed controller	2	-	-	-	-	-	-	-	-	-	x	-
P1462[3]	Integral time speed controller	2	-	-	-	-	-	-	-	-	-	x	-
P1470[3]	Gain speed controller (SLVC)	2	-	-	-	-	-	-	-	x	-	-	-
P1472[3]	Integral time n-ctrl. (SLVC)	2	-	-	-	-	-	-	-	x	-	-	-
P1477[3]	Bl: Set integrator of n-ctrl.	3	-	-	-	-	-	-	-	x	-	x	-
P1478[3]	Cl: Set integrator value n-ctrl.	3	-	-	-	-	-	-	-	x	-	x	-
P1488[3]	Droop input source	3	-	-	-	-	-	-	-	x	-	x	-
P1489[3]	Droop scaling	3	-	-	-	-	-	-	-	x	-	x	-
P1492[3]	Enable droop	3	-	-	-	-	-	-	-	x	-	x	-
P1496[3]	Scaling accel. precontrol	3	-	-	-	-	-	-	-	x	-	x	-
P1499[3]	Scaling accel. torque control	3	-	-	-	-	-	-	-	-	x	-	-
P1500[3]	Selection of torque setpoint	2	-	-	-	-	-	-	-	x	x	x	x
P1501[3]	Bl: Change to torque control	3	-	-	-	-	-	-	-	x	x	x	x
P1503[3]	Cl: Torque setpoint	3	-	-	-	-	-	-	-	-	x	-	x
P1511[3]	Cl: Additional torque setpoint	3	-	-	-	-	-	-	-	x	x	x	x
P1520[3]	CO: Upper torque limit	2	-	-	-	-	-	-	-	x	x	x	x
P1521[3]	CO: Lower torque limit	2	-	-	-	-	-	-	-	x	x	x	x
P1522[3]	Cl: Upper torque limit	3	-	-	-	-	-	-	-	x	x	x	x
P1523[3]	Cl: Lower torque limit	3	-	-	-	-	-	-	-	x	x	x	x
P1525[3]	Scaling lower torque limit	3	-	-	-	-	-	-	-	x	x	x	x
P1530[3]	Motoring power limitation	2	-	-	-	-	-	-	-	x	x	x	x
P1531[3]	Regenerative power limitation	2	-	-	-	-	-	-	-	x	x	x	x
P1570[3]	CO: Fixed value flux setpoint	2	-	-	-	-	-	-	-	x	x	x	x
P1574[3]	Dynamic voltage headroom	3	-	-	-	-	-	-	-	x	x	x	x
P1580[3]	Efficiency optimization	2	-	-	-	-	-	-	-	x	x	x	x
P1582[3]	Smooth time for flux setpoint	3	-	-	-	-	-	-	-	x	x	x	x
P1596[3]	Int. time field weak. controller	3	-	-	-	-	-	-	-	x	x	x	x
P1610[3]	Continuous torque boost (SLVC)	2	-	-	-	-	-	-	-	x	x	-	-
P1611[3]	Acc. torque boost (SLVC)	2	-	-	-	-	-	-	-	x	x	-	-
P1740	Gain for oscillation damping	3	-	-	-	-	-	-	-	x	x	-	-
P1750[3]	Control word of motor model	3	-	-	-	-	-	-	-	x	x	x	x
P1755[3]	Start-freq. motor model (SLVC)	3	-	-	-	-	-	-	-	x	x	-	-
P1756[3]	Hyst.-freq. motor model (SLVC)	3	-	-	-	-	-	-	-	x	x	-	-
P1758[3]	T(wait) transit to feed-fwd-mode	3	-	-	-	-	-	-	-	x	x	-	-
P1759[3]	T(wait) for n-adaption to settle	3	-	-	-	-	-	-	-	x	x	-	-
P1764[3]	Kp of n-adaption (SLVC)	3	-	-	-	-	-	-	-	x	x	-	-
P1780[3]	Control word of Rs/Rr-adaption	3	-	-	-	-	-	-	-	x	x	-	-
P0400[3]	Select encoder type	2	-	-	-	-	-	-	-	-	-	x	x
P0408[3]	Encoder pulses per revolution	2	-	-	-	-	-	-	-	-	-	x	x
P0491[3]	Reaction on speed signal loss	2	-	-	-	-	-	-	-	-	-	x	x
P0492[3]	Allowed speed difference	2	-	-	-	-	-	-	-	-	-	x	x
P0494[3]	Delay speed loss reaction	2	-	-	-	-	-	-	-	-	-	x	x

1) If the speed control (main setpoint) is selected a torque setpoint is available via the additional setpoint channel.

p1310[0...2]	Continuous boost / Continuous boost		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [%]	Max 250.0 [%]	Factory setting 50.0 [%]
Description:	Defines boost level in [%] relative to P0305 (rated motor current) applicable to both linear and quadratic V/f curves. At low output frequencies the output voltage is low to keep the flux level constant. However, the output voltage may be too low for the following:		
	<ul style="list-style-type: none"> • magnetisation the asynchronous motor • hold the load • overcome losses in the system. 		
	The inverter output voltage can be increased via P1310 for the compensation of losses, hold loads at 0 Hz or maintain the magnetization.		
	The magnitude of the boost in Volt at a frequency of zero is defined as follows:		
	$V_ConBoost,100 = p0305 * p0350 * (p1310 / 100)$		
Dependency:	Continous boost P1310 has no effect during vector operation.		
Note:	Increasing the boost levels increases motor heating (especially at standstill).		
	Setting in P0640 (motor overload factor [%]) limits the boost:		
	$sum(V_Boost) / (p0305 * p0350) \leq p1310 / 100$		
	The boost values are combined when continuous boost (P1310) used in conjunction with other boost parameters (acceleration boost P1311 and starting boost P1312). However priorities are allocated to these parameters as follows:		
	$P1310 > P1311 > P1312$		
	The total boost is limited by following equation:		
	$sum(V_Boost) \leq 3 * R_S * I_Mot = 3 * p0305 * p0350$		
p1311[0...2]	Acceleration boost / Acceleration boost		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
Description:	Min 0.0 [%]	Max 250.0 [%]	Factory setting 0.0 [%]
	Applies boost in [%] relative to P0305 (rated motor current) following a positive setpoint change and drops back out once the setpoint is reached.		
	P1311 will only produce boost during ramping, and is therefore useful for additional torque during acceleration and deceleration.		
	As opposed to parameter P1312, which is only active on the first acceleration issued after the ON command, parameter P1311 is always effect during an acceleration and deceleration when issued.		
	The magnitude of the boost in Volt at a frequency of zero is defined as follows:		
	$V_AccBoost,100 = p0305 * p0350 * (p1311 / 100)$		
Dependency:	Acceleration boost P1311 has no effect during vector operation.		
Note:	See parameter P1310.		

p1312[0...2]	Starting boost / Starting boost		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [%]	Max 250.0 [%]	Factory setting 0.0 [%]
Description:	<p>Applies a constant linear offset (in [%] relative to P0305 (rated motor current)) to active V/f curve (either linear or quadratic) after an ON command and is active until:</p> <ol style="list-style-type: none"> 1. ramp output reaches setpoint for the first time respectively 2. setpoint is reduced to less than present ramp output <p>This is useful for starting loads with high inertia. Setting the starting boost (P1312) too high will cause the inverter to limit the current, which will in turn restrict the output frequency to below the setpoint frequency.</p> <p>The magnitude of the boost in Volt at a frequency of zero is defined as follows: $V_StartBoost,100 = p0305 * p0350 * (p1312 / 100)$</p>		
Dependency:	Starting boost P1312 has no effect during vector operation.		
Note:	See parameter P1310.		
r1315	CO: Total boost voltage / Total boost V		
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays total value of voltage boost (in volts).		
p1316[0...2]	Boost end frequency / Boost end freq.		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_REG	
	Min 0.0 [%]	Max 100.0 [%]	Factory setting 20.0 [%]
Description:	<p>Defines point at which programmed boost reaches 50 % of its value.</p> <p>This value is expressed in [%] relative to P0310 (rated motor frequency).</p> <p>The default frequency is defined as follows: $V_Boost,min = 2 * (3 + (153 / \sqrt{P_Motor}))$</p>		
Note:	<p>The expert user may change this value to alter the shape of the curve, e.g. to increase torque at a particular frequency.</p> <p>Default value is depending on inverter type and its rating data.</p>		

p1320[0...2]	Programmable V/f freq. coord. 1 / V/f freq. coord. 1		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 0.00 [Hz]
Description:	Sets the frequency of the first point of V/f coordinates (P1320/1321 to P1324/1325) to define V/f characteristic. These parameter pairs can be used to provide correct torque at correct frequency and is useful when used with synchronous motors.		
Dependency:	To set parameter, select P1300 = 3 (V/f with programmable characteristic). The acceleration boost and starting boost defined in P1311 and P1312 are applied to V/f with programmable characteristic.		
Note:	Linear interpolation will be applied between the individual data points. V/f with programmable characteristic (P1300 = 3) has 3 programmable points and 2 non-programmable points. The 2 non-programmable points are: <ul style="list-style-type: none"> • Continuous boost P1310 at 0 Hz • Rated motor voltage P0304 at rated motor frequency P0310 		
p1321[0...2]	Programmable V/f volt. coord. 1 / V/f volt. coord. 1		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [V]	Max 3000.0 [V]	Factory setting 0.0 [V]
Description:	See P1320 (programmable V/f freq. coord. 1).		
p1322[0...2]	Programmable V/f freq. coord. 2 / V/f freq. coord. 2		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 0.00 [Hz]
Description:	See P1320 (programmable V/f freq. coord. 1).		
p1323[0...2]	Programmable V/f volt. coord. 2 / V/f volt. coord. 2		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [V]	Max 3000.0 [V]	Factory setting 0.0 [V]
Description:	See P1320 (programmable V/f freq. coord. 1).		
p1324[0...2]	Programmable V/f freq. coord. 3 / V/f freq. coord. 3		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 0.00 [Hz]
Description:	See P1320 (programmable V/f freq. coord. 1).		

p1325[0...2]	Programmable V/f volt. coord. 3 / V/f volt. coord. 3		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm.: NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [V]	Max 3000.0 [V]	Factory setting 0.0 [V]
Description:	See P1320 (programmable V/f freq. coord. 1).		
p1330[0...2]	Cl: Voltage setpoint / Voltage setp.		
	Access level: 3	P-Group: Closed-loop control	Data type: U32 / FloatingPoint32
	Quick comm.: NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	BICO parameter for selecting source of voltage setpoint for independent V/f control (P1300 = 19).		
p1333[0...2]	Start frequency for FCC / Start freq for FCC		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm.: NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [%]	Max 100.0 [%]	Factory setting 10.0 [%]
Description:	Defines start frequency at which FCC (flux current control) is enabled as [%] of rated motor frequency (P0310).		
Notice:	If this value is too low, the system may become unstable.		
p1334[0...2]	Slip compensation activation range / Slip c. act. range		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm.: NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 1.0 [%]	Max 20.0 [%]	Factory setting 6.0 [%]
Description:	To set the frequency activation range for slip compensation. The percentage value of P1334 refers to the motor rated frequency P0310. The upper threshold will always stay 4 % above P1334.		
	Range of slip compensation :		
			
Dependency:	Slip compensation (P1335) active.		
Note:	See parameter P1335. The starting frequency of the slip compensation is P1334 * P0310.		

p1335[0...2]	Slip compensation / Slip compensation		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [%]	Max 600.0 [%]	Factory setting 0.0 [%]
Description:	Parameter dynamically adjusts inverter output frequency so that motor speed is kept constant independent of motor load. In the V/f-control, the motor frequency will always be less than the inverter output frequency due to the slip frequency. For a given output frequency, the motor frequency will drop as load is increased. This behavior, typical for induction motors, can be compensated using slip compensation. P1335 can be used to enable and fine-tune the slip compensation.		
Dependency:	Gain adjustment enables fine-tuning of the actual motor speed (see P1460 - gain speed control).		
Notice:	The applied value of the slip compensation (scaled by P1335) is limited by following equation: $f_{\text{Slip_comp,max}} = r0330 * (p1336 / 100)$		
Note:	P1335 = 0 % : Slip compensation disabled. P1335 = 50 % - 70 % : Full slip compensation at cold motor (partial load). P1335 = 100 % (standard setting for warm stator) : Full slip compensation at warm motor (full load).		
p1336[0...2]	Slip limit / Slip limit		
	Access level: 2	P-Group: Closed-loop control	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [%]	Max 600 [%]	Factory setting 250 [%]
Description:	Compensation slip limit in [%] relative to r0330 (rated motor slip), which is added to frequency setpoint.		
Dependency:	Slip compensation (P1335) active.		
r1337	CO: V/f slip frequency / V/f slip freq.		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays actual compensated motor slip as [%]. $f_{\text{slip}} [\text{Hz}] = r1337 [\%] * P2000 / 100$		
Dependency:	Slip compensation (P1335) active.		
p1338[0...2]	Resonance damping gain V/f / Res.damp. gain V/f		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_CON	
	Min 0.00	Max 10.00	Factory setting 0.00
Description:	Defines resonance damping gain for V/f. The di/dt of the active current will be scaled by P1338. If di/dt increases the resonance damping circuit decreases the inverter output frequency.		
Note:	The resonance circuit damps oscillations of the active current which frequently occur during no-load operation. In V/f modes (see P1300), the resonance damping circuit is active in a range from approx. 6 % to 80 % of rated motor frequency (P0310). If the value of P1338 is too high, this will cause instability (forward control effect).		

p1340[0...2]	I_{max} controller prop. gain / I_{max} ctrl prp gain		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.000	Max 0.499	Factory setting 0.000
Description:	<p>Proportional gain of the I_{max} controller.</p> <p>The I_{max} controller reduces inverter current if the output current exceeds the maximum motor current (r0067). In linear V/f, parabolic V/f, FCC, and programmable V/f modes the I_{max} controller uses both a frequency controller (see parameters P1340 and P1341) and a voltage controller (see parameters P1345 and P1346). The frequency controller seeks to reduce current by limiting the inverter output frequency (to a minimum of the two times nominal slip frequency).</p> <p>If this action does not successfully remove the overcurrent condition, the inverter output voltage is reduced using the I_{max} voltage controller.</p> <p>When the overcurrent condition has been removed successfully, frequency limiting is removed using the ramp-up time set in P1120.</p> <p>In linear V/f for textiles, FCC for textiles, or external V/f modes only the I_{max} voltage controller is used to reduce current (see parameters P1345 and P1346).</p>		
Note:	<p>The I_{max} controller can be disabled by setting the frequency controller integral time P1341 to zero. This disables both the frequency and voltage controllers.</p> <p>Note that when disabled, the I_{max} controller will take no action to reduce current but overcurrent warnings will still be generated, and the drive will trip in excessive overcurrent or overload conditions.</p>		
p1341[0...2]	I_{max} controller integral time / I_{max} ctrl int time		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_CON	
	Min 0.000 [s]	Max 50.000 [s]	Factory setting 0.300 [s]
Description:	<p>Integral time constant of the I_{max} controller.</p> <ul style="list-style-type: none"> • P1341 = 0 : I_{max} controller disabled • P1340 = 0 and P1341 > 0 : frequency controller enhanced integral • P1340 > 0 and P1341 > 0 : frequency controller normal PI control 		
Note:	<p>See parameter P1340 for further information.</p> <p>The Factory setting depends on inverter power.</p>		
r1343	CO: I_{max} controller freq. output / I_{max} ctrl Foutp		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays effective frequency limitation.		
Dependency:	If I _{max} controller not in operation, parameter normally shows max. frequency P1082.		
r1344	CO: I_{max} controller volt. output / I_{max} ctrl Voutp		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays amount by which the I _{max} controller is reducing the inverter output voltage.		

p1345[0...2]	I_{max} voltage ctrl. prop. gain / I_{max} volt prp gain		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_CON	
	Min 0.000	Max 5.499	Factory setting 0.250
Description:	If the output current (r0068) exceeds the maximum current (r0067), the frequency inverter is dynamically controlled by reducing the output voltage. This parameter sets the proportional gain of this controller.		
Note:	See parameter P1340 for further information. The Factory setting depends on inverter power.		
p1346[0...2]	I_{max} voltage ctrl. integral time / I_{max} volt int time		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_CON	
	Min 0.000 [s]	Max 50.000 [s]	Factory setting 0.300 [s]
Description:	Integral time constant of the I _{max} voltage controller. <ul style="list-style-type: none"> • P1341 = 0 : I_{max} controller disabled • P1345 = 0 and P1346 > 0 : I_{max} voltage controller enhanced integral • P1345 > 0 and P1346 > 0 : I_{max} voltage controller normal PI control 		
Note:	See parameter P1340 for further information. The Factory setting depends on inverter power.		
p1350[0...2]	Voltage soft start / Voltage soft start		
	Access level: 3	P-Group: Closed-loop control	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0	Max 1	Factory setting 0
Description:	Sets whether voltage is built up smoothly during magnetization time (ON) or whether it simply jumps to boost voltage (OFF).		
Value:	0: OFF 1: ON		
Note:	The settings for this parameter bring benefits and drawbacks: <ul style="list-style-type: none"> • P1350 = 0: OFF (jump to boost voltage) Benefit: flux is built up quickly Drawback: motor may move • P1350 = 1: ON (smooth voltage build-up) Benefit: motor less likely to move Drawback: flux build-up takes longer 		


p1400[0...2]	Configuration of speed control / Config. of n-ctrl.			
	Access level: 3	P-Group: Closed-loop control	Data type: Unsigned16	
	Quick comm. NO	Active: YES	Data set: DDS	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	-	-	0001 bin	
Description:	Configuration for speed control.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Automatic Kp adaption	Yes	No
	01	Integral freeze (SLVC)	Yes	No
Note:	P1400 Bit 00 = 1: Automatic gain adaption of speed controller (P1460 resp. P1470) is enabled. In the area of field weakening the gain is reduced in dependence on flux. P1400 Bit01 = 1: The integrator of the speed controller is frozen if Sensorless Vector Control (SLVC) is selected and the control is switched from closed-loop to open-loop operation. Advantage: The correct amount of slip compensation is calculated and applied to the open-loop function for a motor under load.			
r1407.0...15	CO/BO: Status 2 of motor control / Stat 2 ctrl			
	Access level: 3	P-Group: Closed-loop control	Data type: Unsigned16	
	Unit: -	Calculated: -	Data set: -	
Description:	Displays status of motor control, which can be used to diagnose inverter status.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	V/f control enabled	Yes	No
	01	SLVC enabled	Yes	No
	02	Torque control enabled	Yes	No
	05	Stop I-comp. speed control	Yes	No
	06	Set I-comp. speed controller	Yes	No
	08	Upper torque limit active	Yes	No
	09	Lower torque limit active	Yes	No
	10	Droop active	Yes	No
	15	DDS change active	Yes	No
Note:	See P0052 (CO/BO: Status word 1)			
r1438	CO: Freq. setpoint to controller / Freq. setp ctl			
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32	
	Unit: [Hz]	Calculated: -	Data set: -	
Description:	Displays setpoint of speed controller.			
p1442[0...2]	Filter time for act. speed / Filter time n_act.			
CU240S	Access level: 2	P-Group: Closed-loop control	Data type: Unsigned16	
CU240S DP	Quick comm. NO	Active: YES	Data set: DDS	
CU240S DP-F	Can be changed: U, T	Calculated: -		
CU240S PN				
CU240S PN-F				
	Min	Max	Factory setting	
	2 [ms]	32000 [ms]	2 [ms]	
Description:	Sets time constant of PT1 filter to smooth actual speed of speed controller.			

r1445	CO: Act. filtered frequency / Act. filt freq		
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays filtered actual speed at speed controller input.		
p1452[0...2]	Filter time for act.speed (SLVC) / Act.spd.filt. SLVC		
	Access level: 2	P-Group: Closed-loop control	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 2 [ms]	Max 32000 [ms]	Factory setting 2 [ms]
Description:	Sets time constant of PT1 filter to filter the speed deviation of speed controller in operation mode SLVC (sensorless vector control).		
p1460[0...2]	Gain speed controller / Gain of n-ctrl.		
CU240S	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
CU240S DP	Quick comm. NO	Active: YES	Data set: DDS
CU240S DP-F	Can be changed: U, T	Calculated: CALC_MOD_CON	
CU240S PN			
CU240S PN-F			
	Min 0.0	Max 2000.0	Factory setting 3.0
Description:	Enters gain of speed controller.		
p1462[0...2]	Integral time speed controller / Tn of n-ctrl.		
CU240S	Access level: 2	P-Group: Closed-loop control	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: YES	Data set: DDS
CU240S DP-F	Can be changed: U, T	Calculated: CALC_MOD_CON	
CU240S PN			
CU240S PN-F			
	Min 25 [ms]	Max 32001 [ms]	Factory setting 400 [ms]
Description:	Enters integral time of speed controller.		
p1470[0...2]	Gain speed controller (SLVC) / Gain n-ctrl (SLVC)		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_CON	
	Min 0.0	Max 2000.0	Factory setting 3.0
Description:	Enters gain of speed controller for sensorless vector control (SLVC).		
p1472[0...2]	Integral time n-ctrl. (SLVC) / Tn of n-ctrl. SLVC		
	Access level: 2	P-Group: Closed-loop control	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_CON	
	Min 25 [ms]	Max 32001 [ms]	Factory setting 400 [ms]
Description:	Enters integral time of speed controller for sensorless vector control (SLVC).		

p1477[0...2]	BI: Set integrator of n-ctrl. / Set integrator		
	Access level: 3	P-Group: Closed-loop control	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Selects command source for enabling of integrator setting.		
p1478[0...2]	CI: Set integrator value n-ctrl. / Set int. value		
	Access level: 3	P-Group: Closed-loop control	Data type: U32 / FloatingPoint32
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Selects source for integral part of speed controller.		
Notice:	Neither function works after flying start.		
Note:	If the P1482 (integral component of speed controller) is connected and the setting command is not connected (P1477=0), upon pulse enable the integral component of the controller is set once to the last value prior the pulse inhibit.		
r1482	CO: Integral output of n-ctrl. / Int.outp n-ctrl		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Nm]	Calculated: -	Data set: -
Description:	Displays integral part of speed controller output.		
p1488[0...2]	Droop input source / Droop input source		
	Access level: 3	P-Group: Closed-loop control	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	0	3	0
Description:	Selects source of droop input signal.		
	With mechanically coupled motors it is very important that an even load distribution is applied to each motor. The load sharing can be achieved by enabling the droop function on both inverters.		
	<ol style="list-style-type: none"> 1. Droop is applied as a frequency setpoint on each inverter. The droop increases the slip via the negative feedback of the torque setpoint to the frequency setpoint. In a steady-state an even load distribution can be achieved if the slip characteristics are identical. <ul style="list-style-type: none"> - P1488 > 0 - P1489 > 0 - P1492 = 1 2. Droop can act as a setpoint or limitation for a group of inverters (i.e. master-slave inverters). By use of the master-slave inverter technique an even load distribution is achieved across the whole application. This is accomplished by setting the torque setpoint (r1490) on the master inverter which then controls the speed of the master inverter and all connected slave inverters. <ul style="list-style-type: none"> - P1488 > 0 - P1489 > 0 - P1492 = 0 		
Value:	0: Droop input disabled 1: Torque setpoint 2: Speed controller output 3: Speed controller integral output		
Dependency:	Droop scaling (P1489) must be > 0 for droop to be effective.		

p1489[0...2]	Droop scaling / Droop scaling		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00	Max 0.50	Factory setting 0.05
Description:	Defines amount of droop in per unit at full load in [%].		
Note:	If 0 is entered as value, no droop is applied. The Factory setting depends on inverter power.		
r1490	CO: Droop frequency / Droop freq.		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Displays output signal of droop function. This result of droop calculation is subtracted from the speed controller setpoint.		
p1492[0...2]	BI: Enable droop / Enable droop		
	Access level: 3	P-Group: Closed-loop control	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: U, T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	Enables droop.		
Dependency:	Effective only if droop scaling P1489 > 0.		
p1496[0...2]	Scaling accel. precontrol / Scal acc. prectrl.		
CU240E	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [%]	Max 400.0 [%]	Factory setting 0.0 [%]
Description:	Enters scaling of acceleration in [%]. The response of setpoint changes for the speed control loop can be improved using the precontrol function (P1496). Precontrol is derived from the differential frequency setpoint multiplied by the mass inertia P0341; P0342 is then supplied as a torque setpoint to the current controller. If the filter (SLVC: P1452) is applied in the correct manner, the derived speed controller is only required to control a small deviation in the value of the corrected variable.		
Note:	P1496 = 0: ==> Precontrol disabled P1496 > 0: ==> Precontrol enabled P1496 = 100: ==> Standard setting for precontrol		

p1496[0...2] Scaling accel. precontrol / Scal acc. prectrl.			
CU240S	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
CU240S DP	Quick comm. NO	Active: YES	Data set: DDS
CU240S PN	Can be changed: U, T	Calculated: -	
	Min 0.0 [%]	Max 400.0 [%]	Factory setting 0.0 [%]
Description:	<p>Enters scaling of acceleration in [%].</p> <p>The response of setpoint changes for the speed control loop can be improved using the precontrol function (P1496).</p> <p>Precontrol is derived from the differential frequency setpoint multiplied by the mass inertia P0341; P0342 is then supplied as a torque setpoint to the current controller.</p> <p>If the filter (VC: P1442, SLVC: P1452) is applied in the correct manner, the derived speed controller is only required to control a small deviation in the value of the corrected variable.</p>		
Note:	<p>P1496 = 0: ==> Precontrol disabled</p> <p>P1496 > 0: ==> Precontrol enabled</p> <p>P1496 = 100: ==> Standard setting for precontrol</p>		
p1496[0...2] Scaling accel. precontrol / Scal acc. prectrl.			
CU240S DP-F	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
CU240S PN-F	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [%]	Max 400.0 [%]	Factory setting 0.0 [%]
Description:	<p>Enters scaling of acceleration in [%].</p> <p>The response of setpoint changes for the speed control loop can be improved using the precontrol function (P1496).</p> <p>Precontrol is derived from the differential frequency setpoint multiplied by the mass inertia P0341; P0342 is then supplied as a torque setpoint to the current controller.</p> <p>If the filter (VC: P1442, SLVC: P1452) is applied in the correct manner, the derived speed controller is only required to control a small deviation in the value of the corrected variable.</p>		
Note:	<p>P1496 = 0: ==> Precontrol disabled (necessary for robustness of safety applications with SS1 and SLS)</p> <p>P1496 > 0: ==> Precontrol enabled</p> <p>P1496 = 100: ==> Standard setting for precontrol</p>		
p1499[0...2] Scaling accel. torque control / Scal acc. trq ctrl			
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [%]	Max 400.0 [%]	Factory setting 100.0 [%]
Description:	<p>Enters scaling of acceleration in [%] for sensorless torque control (SLVC) at low frequencies.</p>		


p1500[0...2] Selection of torque setpoint / Torque setp. sel.			
CU240E	Access level: 2	P-Group: Closed-loop control	Data type: Unsigned16
CU240S	Quick comm. YES	Active: NO	Data set: CDS
	Can be changed: C(1), T	Calculated: -	
	Min 0	Max 77	Factory setting 0
Description:	Selects torque setpoint source. The main setpoint is given by the least significant digit (right-hand position) and the additional setpoint is given by the most significant digit (left-hand position). Single digits denote main setpoints that have no additional setpoint.		
Value:	0: No main setpoint 2: Analog setpoint 4: USS on RS232 5: USS on RS485 7: Analog setpoint 2 20: No main setpoint + Analog setpoint 22: Analog setpoint + Analog setpoint 24: USS on RS232 + Analog setpoint 25: USS on RS485 + Analog setpoint 27: Analog setpoint 2 + Analog setpoint 40: No main setpoint + USS on RS232 42: Analog setpoint + USS on RS232 44: USS on RS232 + USS on RS232 45: USS on RS485 + USS on RS232 47: Analog setpoint 2 + USS on RS232 50: No main setpoint + USS on RS485 52: Analog setpoint + USS on RS485 54: USS on RS232 + USS on RS485 55: USS on RS485 + USS on RS485 57: Analog setpoint 2 + USS on RS485 70: No main setpoint + Analog setpoint 2 72: Analog setpoint + Analog setpoint 2 74: USS on RS232 + Analog setpoint 2 75: USS on RS485 + Analog setpoint 2 77: Analog setpoint 2 + Analog setpoint 2		
Caution:	 Changing this parameter sets (to default) all settings on item selected. These are the following parameters: P1503, P1511		

p1500[0...2] Selection of torque setpoint / Torque setp. sel.			
CU240S DP	Access level: 2	P-Group: Closed-loop control	Data type: Unsigned16
CU240S DP-F	Quick comm. YES	Active: NO	Data set: CDS
CU240S PN	Can be changed: C(1), T	Calculated: -	
CU240S PN-F			
	Min 0	Max 77	Factory setting 0
Description:	Selects torque setpoint source. The main setpoint is given by the least significant digit (right-hand position) and the additional setpoint is given by the most significant digit (left-hand position). Single digits denote main setpoints that have no additional setpoint.		
Value:	0: No main setpoint 2: Analog setpoint 4: USS on RS232 6: Fieldbus 7: Analog setpoint 2 20: No main setpoint + Analog setpoint 22: Analog setpoint + Analog setpoint 24: USS on RS232 + Analog setpoint 26: Fieldbus + Analog setpoint 27: Analog setpoint 2 + Analog setpoint 40: No main setpoint + USS on RS232 42: Analog setpoint + USS on RS232 44: USS on RS232 + USS on RS232 46: Fieldbus + USS on RS232 47: Analog setpoint 2 + USS on RS232 60: No main setpoint + Fieldbus 62: Analog setpoint + Fieldbus 64: USS on RS232 + Fieldbus 66: Fieldbus + Fieldbus 67: Analog setpoint 2 + Fieldbus 70: No main setpoint + Analog setpoint 2 72: Analog setpoint + Analog setpoint 2 74: USS on RS232 + Analog setpoint 2 76: Fieldbus + Analog setpoint 2 77: Analog setpoint 2 + Analog setpoint 2		
Caution:	Changing this parameter sets (to default) all settings on item selected. These are the following parameters: P1503, P1511		



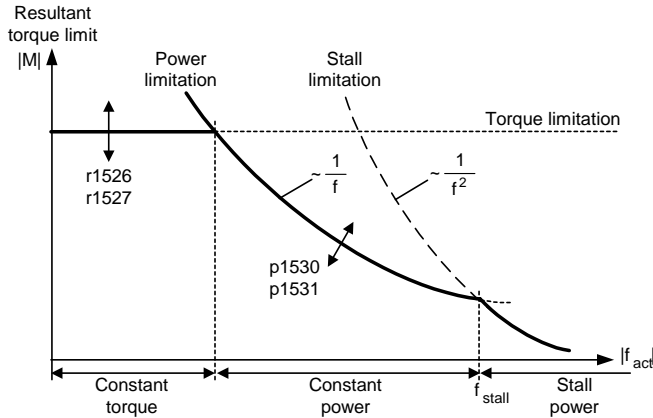
p1501[0...2] BI: Change to torque control / Change > torq ctrl			
CU240E	Access level: 3	P-Group: Closed-loop control	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	Selects command source from which it is possible to change between master (speed control) and slave (torque control).		
Caution:	The OFF1 command is not recognized when torque control is selected indirectly (P1300 = 20 and P1501 = 1). However, if direct selection of torque control is used (P1300 = 22) the OFF1 command is recognized as OFF2. If indirect selection of torque control is used, it is recommended to program an OFF2 command using, for example a digital input or create a circuit using the Free Function Blocks (FFB):		
Note:	Speed control without encoder feedback see P1470.		



p1501[0...2]	BI: Change to torque control / Change > torq ctrl		
CU240S	Access level: 3	P-Group: Closed-loop control	Data type: U32 / Binary
CU240S DP	Quick comm. NO	Active: NO	Data set: CDS
CU240S DP-F	Can be changed: T	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min	Max	Factory setting
	-	-	0
Description:	Selects command source from which it is possible to change between master (speed control) and slave (torque control).		
Caution:	The OFF1 command is not recognized when torque control is selected indirectly (P1300 = 20, 21 and P1501 = 1). However, if direct selection of torque control is used (P1300 = 22, 23) the OFF1 command is recognized as OFF2. If indirect selection of torque control is used, it is recommended to program an OFF2 command using, for example a digital input or create a circuit using the Free Function Blocks (FFB):		
			
Note:	Speed control with encoder feedback see P1460. Speed control without encoder feedback see P1470.		
p1503[0...2]	CI: Torque setpoint / Torque setp.		
	Access level: 3	P-Group: Closed-loop control	Data type: U32 / FloatingPoint32
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Selects source of torque setpoint for torque control.		
r1508	CO: Torque setpoint / Torque setp.		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Nm]	Calculated: -	Data set: -
Description:	Displays torque setpoint before limitation.		
p1511[0...2]	CI: Additional torque setpoint / Add. trq. setp		
	Access level: 3	P-Group: Closed-loop control	Data type: U32 / FloatingPoint32
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Selects source of additional torque setpoint for torque and speed control.		
r1515	CO: Additional torque setpoint / Add. trq. setp		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Nm]	Calculated: -	Data set: -
Description:	Displays additional torque setpoint.		
r1518	CO: Acceleration torque / Accel. torque		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Nm]	Calculated: -	Data set: -
Description:	Displays acceleration torque.		

p1520[0...2]	CO: Upper torque limit / Upper trq. lim		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_ALL	
	Min -99999.00 [Nm]	Max 99999.00 [Nm]	Factory setting 5.13 [Nm]
Description:	Specifies fixed value for upper torque limitation. $p1520_def = r0333 * (p0640 / 100\%)$ $p1520_max = +/-4 * r0333$		
Note:	The factory setting depends on rating data of Power Module and Motor.		
p1521[0...2]	CO: Lower torque limit / Lower trq. lim		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_ALL	
	Min -99999.00 [Nm]	Max 99999.00 [Nm]	Factory setting -5.13 [Nm]
Description:	Specifies fixed value of lower torque limitation. $p1521_def = -r0333 * (p0640 / 100\%)$ $p1521_max = +/-4 * r0333$		
Note:	The factory setting depends on rating data of Power Module and Motor.		
p1522[0...2]	CI: Upper torque limit / Upper trq. lim		
	Access level: 3	P-Group: Closed-loop control	Data type: U32 / FloatingPoint32
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 1520[0]
Description:	Selects source of upper torque limitation.		
p1523[0...2]	CI: Lower torque limit / Lower trq. lim		
	Access level: 3	P-Group: Closed-loop control	Data type: U32 / FloatingPoint32
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 1521[0]
Description:	Selects source of lower torque limitation.		
p1525[0...2]	Scaling lower torque limit / Scal. low trq. lim		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -400.0 [%]	Max 400.0 [%]	Factory setting 100.0 [%]
Description:	Specifies scaling of lower torque limitation in [%].		
Note:	P1525 = 100 % = standard setting		

r1526 **CO: Upper torque limitation / Upper trq. lim**
Access level: 3 **P-Group:** Closed-loop control **Data type:** FloatingPoint32
Unit: [Nm] **Calculated:** - **Data set:** -
Description: Displays actual upper torque limitation.



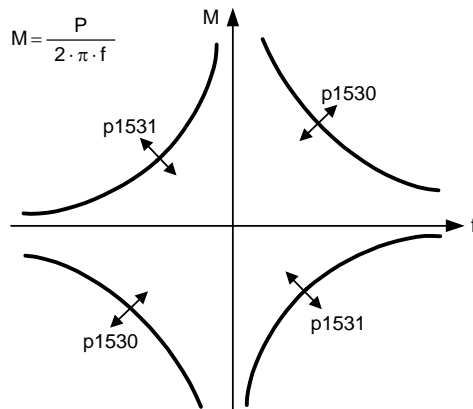
Dependency: The parameters r1526 and r1527 depend on P1520, P1521, P1522, P1523 and P1525.

r1527 **CO: Lower torque limitation / Lower trq. lim**
Access level: 3 **P-Group:** Closed-loop control **Data type:** FloatingPoint32
Unit: [Nm] **Calculated:** - **Data set:** -
Description: Displays actual lower torque limitation.
Note: See parameter r1526.

p1530[0...2] **Motoring power limitation / Motoring power lim**
Access level: 2 **P-Group:** Closed-loop control **Data type:** FloatingPoint32
Quick comm. NO **Active:** YES **Data set:** DDS
Can be changed: U, T **Calculated:** CALC_MOD_ALL
Min **Max** **Factory setting**
 0.0 8000.0 0.75

Description: Defines fixed value for the max. permissible motoring active power (motoring power limitation).
 $p1530_def = 2.5 * p0307$
 $p1530_max = 3 * p0307$
 Parameter P1530 limits the torque in addition to the act. frequency.

Note: Power limitation (motoring, regenerative)

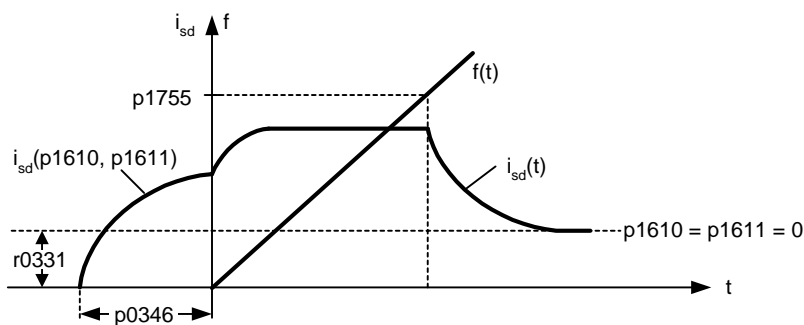


p1531[0...2]	Regenerative power limitation / Regener. power lim		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_ALL	
	Min -8000.0	Max 0.0	Factory setting -0.75
Description:	Enters fixed value for the max. permissible regenerative active power (regenerative power limitation). p1531_def = -1 * p0307 p1531_max = -1 * p0307		
Note:	See parameter P1530.		
r1536	CO: Max. trq. motoring current / Max trq mot cur		
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [A]	Calculated: -	Data set: -
Description:	Displays maximum torque motoring current component.		
r1537	CO: Max trq regenerative current / Max trq reg cur		
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [A]	Calculated: -	Data set: -
Description:	Displays maximum torque of the regenerative current component.		
r1538	CO: Upper torque limit (total) / Total up TrqLim		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Nm]	Calculated: -	Data set: -
Description:	Displays total upper torque limitation.		
r1539	CO: Lower torque limit (total) / Total lw TrqLim		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [Nm]	Calculated: -	Data set: -
Description:	Displays total lower torque limitation.		
p1570[0...2]	CO: Fixed value flux setpoint / Fval flux setp		
	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 50.0 [%]	Max 200.0 [%]	Factory setting 100.0 [%]
Description:	Defines fixed value of flux setpoint in [%] relative to rated motor flux.		
Note:	If P1570 > 100 %, the flux setpoint rises according to the load from 100 % to the value of P1570 between idling and nominal load.		
p1574[0...2]	Dynamic voltage headroom / Dyn. volt headroom		
	Access level: 3	P-Group: Closed-loop control	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [V]	Max 150 [V]	Factory setting 10 [V]
Description:	Sets dynamic voltage headroom for vector control.		

p1580[0...2]	Efficiency optimization / Efficiency optimiz		
	Access level: 2	P-Group: Closed-loop control	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [%]	Max 100 [%]	Factory setting 0 [%]
Description:	Sets the efficiency optimization for closed-loop vector control in [%]. When optimizing the efficiency, the flux setpoint is adapted as a function of the load.		
Note:	If P1580 > 0, the dynamics for speed control (P1470, P1472) are restricted to prevent vibration. When no load is applied, a value of 100 % produces full flux reduction (i.e. to 50 % of rated motor flux). When using optimization, it is necessary to increase the smoothing time of the flux setpoint (P1582).		
p1582[0...2]	Smooth time for flux setpoint / Flux setp. Tsmooth		
	Access level: 3	P-Group: Closed-loop control	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 4 [ms]	Max 500 [ms]	Factory setting 15 [ms]
Description:	Sets time constant of PT1 filter to smooth flux setpoint.		
r1583	CO: Flux setpoint (smoothed) / Smoothed setp.		
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays smoothed flux setpoint in [%] relative to rated motor flux.		
p1596[0...2]	Int. time field weak. controller / Int.time weak.ctrl		
	Access level: 3	P-Group: Closed-loop control	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 20 [ms]	Max 32001 [ms]	Factory setting 50 [ms]
Description:	Sets the integral time of the field weakening controller.		
r1597	CO: Outp. field weak. controller / Outp.weak. ctrl		
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays output signal of field weakening controller in [%] relative to rated motor flux.		
r1598	CO: Flux setpoint (total) / Total flux setp		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays total flux setpoint in [%] relative to the rated motor flux.		

p1610[0...2]	Continuous torque boost (SLVC) / Cont. torque boost		
Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32	
Quick comm. NO	Active: YES	Data set: DDS	
Can be changed: U, T	Calculated: -		
Min 0.0 [%]	Max 200.0 [%]	Factory setting 50.0 [%]	

Description: Sets continuous torque boost in lower speed range of SLVC (sensorless vector control). Value is entered in [%] relative to rated motor torque r0333.



Note: P1610 = 100 % corresponds to rated motor torque.

p1611[0...2]	Acc. torque boost (SLVC) / Acc trq boost SLVC		
Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32	
Quick comm. NO	Active: YES	Data set: DDS	
Can be changed: U, T	Calculated: -		
Min 0.0 [%]	Max 200.0 [%]	Factory setting 0.0 [%]	

Description: Sets acceleration torque boost in lower speed range of SLVC (sensorless vector control). Value is entered in [%] relative to rated motor torque r0333.

Note: P1611 = 100 % corresponds to rated motor torque.

p1654[0...2]	Smooth time for Isq setpoint / Isq setp. Tsmooth		
Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32	
Quick comm. NO	Active: YES	Data set: DDS	
Can be changed: U, T	Calculated: -		
Min 2.0 [ms]	Max 20.0 [ms]	Factory setting 6.0 [ms]	

Description: Sets time constant of PT1 filter to filter setpoint of torque generating current component in field weakening range.

p1715[0...2]	Gain current controller / Gain current ctrl.		
Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32	
Quick comm. NO	Active: YES	Data set: DDS	
Can be changed: U, T	Calculated: CALC_MOD_CON		
Min 0.00	Max 5.00	Factory setting 0.25	

Description: Enters gain of current controller.

p1717[0...2]	Integral time current controller / Int.time cur. ctrl		
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_CON	
	Min 1.0 [ms]	Max 50.0 [ms]	Factory setting 4.1 [ms]
Description:	Enters integral time of current controller.		
r1718	CO: Output of Isq controller / Outp. Isq ctrl		
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays actual output of Isq current (torque current) controller (PI controller). It contains the proportional and integral part of the PI controller.		
r1719	CO: Integral output of Isq ctrl. / Int. outp. Isq		
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays integral output of Isq current (torque current) controller (PI controller).		
r1723	CO: Output of Isd controller / Outp. Isd ctrl		
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays actual output of Isd current (flux current) controller (PI controller). It contains the proportional and integral part of the PI controller.		
r1724	CO: Integral output of Isd ctrl. / Int. outp. Isd		
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays integral output of Isd current (flux current) controller (PI controller).		
r1725	CO: Integral limit of Isd ctrl. / Int. limit Isd		
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays limit of integral output voltage setpoint of Isd current controller.		
r1728	CO: Decoupling voltage / Decoupl. volt		
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays actual output voltage setpoint of cross channel decoupling.		
p1740	Gain for oscillation damping / Oscill. damp. gain		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0.000	Max 10.000	Factory setting 0.000
Description:	Sets oscillation damping gain for sensorless vector control at low frequencies. The oscillation damping subtracts the result of a delayed differential (DT1) from the setpoint frequency.		

p1745[0...2]	Flux variance limit in stall / Flux var.lim.stall				
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32		
	Quick comm. NO	Active: YES	Data set: DDS		
	Can be changed: U, T	Calculated: CALC_MOD_CON			
	Min 0.0 [%]	Max 1000.0 [%]	Factory setting 5.0 [%]		
Description:	Sets the flux variance limit. With SLVC the variance between the flux setpoint and the actual flux is used to detect motor stall conditions.				
Note:	The function is active, with SLVC (P1300 = 20 or 22) and control in open loop mode (output frequency > P1755).				
r1746	CO: Actual flux variance / Act. flux variance				
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32		
	Unit: [%]	Calculated: -	Data set: -		
Description:	Displays the present percentage of flux variance. See P1745.				
p1750[0...2]	Control word of motor model / Motor model CtrlWd				
	Access level: 3	P-Group: Closed-loop control	Data type: Unsigned16		
	Quick comm. NO	Active: NO	Data set: DDS		
	Can be changed: U, T	Calculated: -			
	Min -	Max -	Factory setting 0000 bin		
Description:	Control word of motor model. This parameter controls the operation of the sensorless vector control (SLVC) at very low frequencies. This therefore includes the following conditions: <ul style="list-style-type: none"> • Operation directly after an ON command • zero crossing. SLVC open loop means that the speed controller does not get any speed feedback from the observer model.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Start SLVC open loop	Yes	No	-
	01	Zero crossing SLVC open loop	Yes	No	-
r1751.0...15	CO/BO: Status word of motor model / Motor model StatWd				
	Access level: 3	P-Group: Closed-loop control	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays status of transition from feed-forward to observer-control and vice versa.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Open loop operation	Yes	No	-
	01	RFG set by transition control	Yes	No	-
	02	Rs/Lh adaption stopped	Yes	No	-
	03	Observer feedback enabled	Yes	No	-
	04	Angle hold active	Yes	No	-
	05	Accelertation check enabled	Yes	No	-
	06	Sensor mode active	Yes	No	-
	14	Rs adapted	Yes	No	-
	15	Xh adapted	Yes	No	-

p1752[0...2]	Start-freq. speed adaption (VC with encoder) / Start-freq. (VC)		
CU240S	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
CU240S DP	Quick comm. NO	Active: YES	Data set: DDS
CU240S DP-F	Can be changed: U, T	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min 0.1 [Hz]	Max 250.0 [Hz]	Factory setting 5.0 [Hz]
Description:	Enters start frequency of the n adaption in vector control with encoder (VC, hysteresis like P1755). The feature of speed-adaptation is an essential function to correct the torque (i.e. slip) in VC-mode. However, at low frequencies the activated n-adaptation may cause some troubles. Therefore, below the limit of $P1752 * P1756 / 100$ % this feature is switched off.		
p1755[0...2]	Start-freq. motor model (SLVC) / Start-freq. (SLVC)		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.2 [Hz]	Max 250.0 [Hz]	Factory setting 5.0 [Hz]
Description:	Assigns in SLVC the frequency limit for switch over from closed-loop operation to open-loop operation and vice versa.		
Note:	For detailed information see "Function manual", Section "Vector Control without Speed Encoder".		
p1756[0...2]	Hyst.-freq. motor model (SLVC) / Hyst. freq. (SLVC)		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 10.0 [%]	Max 100.0 [%]	Factory setting 50.0 [%]
Description:	Hysteresis value for open-/closed-loop control (SLVC) and activation/deactivation of speed adaption (VC).		
Note:	For detailed information see "Function manual", Section "Vector Control without Speed Encoder".		
p1758[0...2]	T(wait) transit to open-loop / T(wait) trans.->OL		
	Access level: 3	P-Group: Closed-loop control	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 100 [ms]	Max 2000 [ms]	Factory setting 1000 [ms]
Description:	Sets waiting time for change from closed-loop to open-loop control mode.		
Note:	For detailed information see "Function manual", Section "Vector Control without Speed Encoder".		
p1759[0...2]	T(wait) transit to closed-loop / T(wait) trans.->CL		
	Access level: 3	P-Group: Closed-loop control	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [ms]	Max 2000 [ms]	Factory setting 0 [ms]
Description:	Sets waiting time for change from open-loop to closed-loop control mode.		
Note:	For detailed information see "Function manual", Section "Vector Control without Speed Encoder".		

p1764[0...2]	Kp of n-adaption (SLVC) / Kp n-adapt. (SLVC)				
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32		
	Quick comm. NO	Active: YES	Data set: DDS		
	Can be changed: U, T	Calculated: CALC_MOD_CON			
	Min 0.0	Max 2.5	Factory setting 0.2		
Description:	Enters gain of speed adaptation controller for sensorless vector control.				
p1767[0...2]	Tn of n-adaption (SLVC) / Tn n-adapt. (SLVC)				
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32		
	Quick comm. NO	Active: YES	Data set: DDS		
	Can be changed: U, T	Calculated: CALC_MOD_CON			
	Min 1.0 [ms]	Max 200.0 [ms]	Factory setting 4.0 [ms]		
Description:	Enters speed adaptation controller integral time.				
r1770	CO: Prop. output of n-adaption / Prop outp n-ad				
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32		
	Unit: [Hz]	Calculated: -	Data set: -		
Description:	Displays proportional part of speed adaptation controller.				
r1771	CO: Int. output of n-adaption / Int. outp n-ad				
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32		
	Unit: [Hz]	Calculated: -	Data set: -		
Description:	Displays integral part of speed adaptation controller.				
r1778	CO: Flux angle difference / Flux angle diff				
	Access level: 4	P-Group: Closed-loop control	Data type: FloatingPoint32		
	Unit: [°]	Calculated: -	Data set: -		
Description:	Displays flux angle difference between motor model and current transformation before motor model is active.				
p1780[0...2]	Control word of Rs/Rr-adaption / CtrlWd Rs/Rr adapt				
	Access level: 3	P-Group: Closed-loop control	Data type: Unsigned16		
	Quick comm. NO	Active: NO	Data set: DDS		
	Can be changed: U, T	Calculated: -			
	Min -	Max -	Factory setting 0111 bin		
Description:	Enables thermal adaptation of stator and rotor resistance to reduce torque errors in speed/torque regulation with speed sensor, or speed errors in speed/torque regulation without speed sensor.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Enable thermal Rs/Rr-adapt.	Yes	No	-
	01	Enable observer Rs-adapt.	Yes	No	-
	02	Enable observer Xm-adapt.	Yes	No	-
Note:	Only stator resistance adaptation is carried out for synchronous motors.				

p1781[0...2]	Tn of Rs-adaption / Tn of Rs-adaption		
	Access level: 4	P-Group: Closed-loop control	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 10 [ms]	Max 2000 [ms]	Factory setting 100 [ms]
Description:	Enters Rs-adaptation controller integral time.		
r1782	CO: Output of Rs-adaptation / Output Rs-adaption		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays stator resistance adaptation from controller in [%] relative to rated motor resistance.		
p1786[0...2]	Tn of Xm-adaption / Tn of Xm-adaption		
	Access level: 4	P-Group: Closed-loop control	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 10 [ms]	Max 2000 [ms]	Factory setting 100 [ms]
Description:	Enters Xm-adaptation controller integral time.		
r1787	CO: Output of Xm-adaption / Outp. Xm-adaption		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays main reactance adaptation from controller in [%] relative to rated impedance.		
p1800[0...2]	Pulse frequency / Pulse frequency		
	Access level: 2	P-Group: Converter	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 2 [kHz]	Max 16 [kHz]	Factory setting 4 [kHz]
Description:	Sets pulse frequency of power switches in inverter. The frequency can be changed in steps of 2 kHz.		
Dependency:	The minimum/maximum/default values of the pulse frequency are determined by the used power module. Furthermore the minimum pulse frequency depends on the parametrization of P1082 (maximum frequency) and P0310 (rated motor frequency).		
Note:	If the pulse frequency is increased, max. inverter current r0209 can be reduced (derating). The derating characteristic depends on the type and power of the inverter. If silent operation is not absolutely necessary, lower pulse frequencies may be selected to reduce inverter losses and radio-frequency emissions. Under certain circumstances, the inverter may reduce the pulse frequency to provide protection against overtemperature (see P0290 and P0291 Bit00).		

r1801[0...1]	CO: Pulse frequency / Pulse frequency		
	Access level: 3	P-Group: Converter	Data type: Unsigned16
	Unit: [kHz]	Calculated: -	Data set: -
Description:	Displays informations about pulse frequency of power switches in inverter. r1801[0] Displays the actual inverter pulse frequency. r1801[1] Displays the minimum inverter pulse frequency which can be reached when the functions "motor identification" or "inverter overload reaction" are active. If no PM is plugged this parameter is set to 0 kHz.		
Index:	[0] = Actual pulse frequency [1] = Minimum pulse frequency		
Notice:	Under certain conditions (inverter overtemperature, see P0290), this can differ from the values selected in P1800 (pulse frequency).		
p1802	Modulator mode / Modulator mode		
	Access level: 3	P-Group: Converter	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 1	Max 3	Factory setting 3
Description:	Selects inverter modulator mode.		
Value:	1: Asymmetric SVM 2: Space vector modulation 3: SVM/ASVM controlled mode		
Notice:	<ul style="list-style-type: none"> Asymmetric space vector modulation (ASVM) produces lower switching losses than space vector modulation (SVM), but may cause irregular rotation at very low speeds. Space vector modulation (SVM) with over-modulation may produce current waveform distortion at high output voltages. Space vector modulation (SVM) without over-modulation will reduce maximum output voltage available to motor. 		
Note:	If a LC-filter is selected (P0230 = 3 or (P0230 = 4 and P0234 > 0)), modulation is set to SVM (P1802 = 2) . If an internal output filter is installed the modulation is forced to SVM (P0230 = 3 and P1802 = 2).		
p1803[0...2]	Max. modulation / Max. modulation		
	Access level: 3	P-Group: Converter	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 20.0 [%]	Max 150.0 [%]	Factory setting 106.0 [%]
Description:	Sets maximum modulation index.		
Note:	P1803 = 100 % : Limit for over-control (for ideal inverter without switching delay). For vector control the modulation limit will be reduced automatically with 4 %. If a LC-filter is selected (P0230 = 3 or (P0230 = 4 and P234 > 0)), the max. modulation index is set to 100 % if it is greater than 100 %. If an internal output filter is installed the modulation depth is limited to 100 % (p0230 = 3 and p1803 <= 100 %).		


p1810	Control word Vdc control / Control word vdc c				
	Access level: 3	P-Group: Converter	Data type: Unsigned16		
	Quick comm. NO	Active: NO	Data set: -		
	Can be changed: U, T	Calculated: -			
	Min	Max	Factory setting		
	-	-	0010 bin		
Description:	Configures Vdc filtering and compensation.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	enable Vdc average filter	Yes	No	-
	01	enable Vdc compensation	Yes	No	-
p1820[0...2]	Reverse output phase sequence / Rev.outp.phase seq				
	Access level: 2	P-Group: Modulation	Data type: Unsigned16		
	Quick comm. NO	Active: NO	Data set: DDS		
	Can be changed: T	Calculated: -			
	Min	Max	Factory setting		
	0	1	0		
Description:	Changes sequence of phases without changing setpoint polarity.				
Value:	0: Forward 1: Reverse the Motor				
Note:	See P1000 (select frequency setpoint)				
p1825	On-state voltage of IGBT / On-state voltage				
	Access level: 4	P-Group: Modulation	Data type: FloatingPoint32		
	Quick comm. NO	Active: YES	Data set: -		
	Can be changed: U, T	Calculated: -			
	Min	Max	Factory setting		
	0.0 [V]	20.0 [V]	0.9 [V]		
Description:	Corrects on-state voltage of the IGBTs.				
p1828	Gating unit dead time / Gating dead time				
	Access level: 4	P-Group: Modulation	Data type: FloatingPoint32		
	Quick comm. NO	Active: NO	Data set: -		
	Can be changed: U, T	Calculated: -			
	Min	Max	Factory setting		
	0.00 [µs]	3.98 [µs]	0.01 [µs]		
Description:	Sets compensation time of gating unit interlock.				
p1860	Filter control word / Filter control wor				
	Access level: 3	P-Group: Commands	Data type: Unsigned16		
	Quick comm. NO	Active: YES	Data set: -		
	Can be changed: U, T	Calculated: -			
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	To control the Voltage-/current correction. Voltage- and current correction can be enabled/disabled separately (output filter).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Filter correction on/off	Yes	No	-
	01	Voltage correction on/off	Yes	No	-
	02	Current correction on/off	Yes	No	-


r1861	Filter correction voltage (alpha-component) / Filter correction	
Access level: 2	P-Group: -	Data type: FloatingPoint32
Unit: [V]	Calculated: -	Data set: -
Description:	Alpha component of the voltage correction value (output filter installed and vector control active).	

r1862	Filter correction voltage (beta-component) / Filter correction	
Access level: 2	P-Group: -	Data type: FloatingPoint32
Unit: [V]	Calculated: -	Data set: -
Description:	Beta component of the voltage correction value (output filter installed and vector control active).	

r1863	Filter correction current (alpha-component) / Filter correction	
Access level: 2	P-Group: -	Data type: FloatingPoint32
Unit: [A]	Calculated: -	Data set: -
Description:	Alpha component of the current correction (output filter installed and vector control active).	

r1864	Filter correction current (beta-component) / Filter correction	
Access level: 2	P-Group: -	Data type: FloatingPoint32
Unit: [A]	Calculated: -	Data set: -
Description:	Beta component of the current correction (output filter installed and vector control active).	

p1900 Select motor data identification / Sel.mot.data ident			
CU240E	Access level: 2	P-Group: Motor identification	Data type: Unsigned16
	Quick comm. YES	Active: NO	Data set: -
	Can be changed: C(1), T	Calculated: -	
	Min 0	Max 3	Factory setting 0
Description:	Performs a motor data identification.		
Value:	0: Disabled 2: Identification of all parameters in standstill 3: Ident. of all param. in standstill incl. the saturation curve		
Caution:	Motor identification should be performed on a cold motor. However, the identification of the motor data should only be performed if the motor temperature is within 5 °C of the measured ambient temperature stored in P0625. If the motor identification is not within the 5 °C limit then the correct functioning of Vector Control (SLVC) cannot be guaranteed. The motor rating plate information with respect to the connection of the motor windings (star or delta connection) must be correct in order to establish the correct equivalent circuit data. The motor identification calculates this data based on a phase of a star equivalent circuit P0350 - P0360, irrespective of whether the motor is connected star or delta. This must be considered when the motor data is inputted directly.		
			
Notice:	P1910 can't be changed while the motoridentification is active (P1900 = 2 or 3). When the identification is finished P1900 and P1910 are set to 0.		
Note:	Before selecting motor data identification, "Quick commissioning" has to be performed in advance. Since the cable length of the applications differ in a wide range the preset resistor P0352 is only a rough estimation. Better results of the motor identification can be achieved by specifying the cable resistor before the start of the motor identification by measuring/calculating. Once enabled (P1900 > 0), A0541 generates a warning that the next ON command will initiate measurement of motor parameters. Communications - both via USS as well as via the Fieldbus - are interrupted for the time that it takes to make internal calculations. This can result in the following error messages at the connected SIMATIC S7 control (communications via fieldbus):		
	<ul style="list-style-type: none"> • Parameter fault 30 • Drive fault 70 • Drive fault 75 		
	When using STARTER (USS) to commission the drive system, data cannot be entered while these calculations are being made. The faults can be acknowledged as soon as the calculations have been completed in the frequency inverter. These calculations can take up to one minute to complete.		

p1900			
Select motor data identification / Sel.mot.data ident			
CU240S	Access level: 2	P-Group: Motor identification	Data type: Unsigned16
CU240S DP	Quick comm. YES	Active: NO	Data set: -
CU240S DP-F	Can be changed: C(1), T	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min	Max	Factory setting
	0	3	0
Description:	Performs a motor data identification.		
Value:	0: Disabled 2: Identification of all parameters in standstill 3: Ident. of all param. in standstill incl. the saturation curve		
Caution:	 <p>Motor identification should be performed on a cold motor. However, the identification of the motor data should only be performed if the motor temperature is within 5 °C of the measured ambient temperature stored in P0625. If the motor identification is not within the 5 °C limit then the correct functioning of Vector Control (VC, SLVC) cannot be guaranteed. The motor rating plate information with respect to the connection of the motor windings (star or delta connection) must be correct in order to establish the correct equivalent circuit data. The motor identification calculates this data based on a phase of a star equivalent circuit P0350 - P0360, irrespective of whether the motor is connected star or delta. This must be considered when the motor data is inputted directly.</p>		
Notice:	P1910 can't be changed while the motoridentification is active (P1900 = 2 or 3). When the identification is finished P1900 and P1910 are set to 0.		
Note:	<p>Before selecting motor data identification, "Quick commissioning" has to be performed in advance. Since the cable length of the applications differ in a wide range the preset resistor P0352 is only a rough estimation. Better results of the motor identification can be achieved by specifying the cable resistor before the start of the motor identification by measuring/calculating. Once enabled (P1900 > 0), A0541 generates a warning that the next ON command will initiate measurement of motor parameters. Communications - both via USS as well as via the Fieldbus - are interrupted for the time that it takes to make internal calculations. This can result in the following error messages at the connected SIMATIC S7 control (communications via fieldbus):</p> <ul style="list-style-type: none"> • Parameter fault 30 • Drive fault 70 • Drive fault 75 <p>When using STARTER (USS) to commission the drive system, data cannot be entered while these calculations are being made. The faults can be acknowledged as soon as the calculations have been completed in the frequency inverter. These calculations can take up to one minute to complete.</p>		

p1909[0...2]		Ctrl. word of motor data ident. / Ctrl.mot.data id.			
	Access level: 4	P-Group: Motor identification	Data type: Unsigned16		
	Quick comm. NO	Active: NO	Data set: DDS		
	Can be changed: U, T	Calculated: -			
	Min	Max	Factory setting		
	-	-	0101 1100 0000 0000 bin		
Description:	Control word of motor data identification.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Estimation of Xs	Yes	No	-
	01	Motor ID at 2KHz	Yes	No	-
	02	Estimation of Tr	Yes	No	-
	03	Estimation of Lsigma	Yes	No	-
	05	Det. Tr meas. with 2 freq.	Yes	No	-
	06	Measurement of on voltage	Yes	No	-
	07	Deadtime detection from Rs measurement	Yes	No	-
	08	MotID with hw deadtime comp activ	Yes	No	-
	09	No deadtime detection with 2 freq	Yes	No	-
	10	Detect Ls with LsBlock method	Yes	No	-
	11	MotID adaption of magnetizing current	Yes	No	-
	12	MotID adaption of main reactance	Yes	No	-
	13	MotID switch off saturation curve optim.	Yes	No	-
	14	MotID saturation curve optim. all framesizes	Yes	No	-
	15	MotID saturation curve optim. big frame-sizes	Yes	No	-

p1910		Select motor data identification extended / Sel.mot.data ident		
CU240E	Access level: 2	P-Group: Motor identification	Data type: Unsigned16	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: T	Calculated: -		
	Min	Max	Factory setting	
	0	23	0	
Description:	Performs a motor data identification with extended figures.			
Value:	0: Disabled 1: Identification of all parameters with parameter change 2: Identification of all parameters without parameter change 3: Identification of saturation curve with parameter change 4: Identification of saturation curve without parameter change 5: Identification of XsigDyn (r1920) without parameter change 6: Identification of Tdead (r1926) without parameter change 7: Identification of Rs (r1912) without parameter change 8: Identification of Xs (r1915) without parameter change 9: Identification of Tr (r1913) without parameter change 10: Identification of Xsigma (r1914) without parameter change 20: Set voltage vector 21: Set voltage vector without filtering in P69 22: Set voltage vector rectangle signal 23: Set voltage vector triangle signal			

Caution:

Motor identification should be performed on a cold motor.

However, the identification of the motor data should only be performed if the motor temperature is within 5°C of the measured ambient temperature stored in P0625.

If the motor identification is not within the 5°C limit then the correct functioning of Vector Control (SLVC) cannot be guaranteed.

The motor rating plate information with respect to the connection of the motor windings (Star or delta connection) must be correct in order to establish the correct equivalent circuit data.

The motor identification calculates this data based on a Phase of a Star equivalent circuit P0350 - P0360, irrespective of whether the motor is connected star or delta.

This must be considered when the motor data is inputted directly.

Notice:

P1910 can't be changed while the motor identification with P1900 is active (P1900 = 2 or 3).

When the identification is finished P1910 is set to 0.

When choosing the setting for measurement, observe the following:

1. "with parameter change" means that the values are actually adopted as Pxxxx parameter settings (see common settings above) and applied to the controller as well as being shown in the read-only parameters below.
2. "without parameter change" means that the values are only displayed, i.e. shown for checking purposes in the read-only parameters r1912 (identified stator resistance), r1913 (identified rotor time constant), r1914 (ident. total leakage reactance), r1915/r1916/r1917/r1918/r1919 (identified nominal stator reactance/identified stator reactance 1 to 4), r1925 (IG-BT on-state voltage) and r1926 (identified gating unit dead time). The values are not applied to the controller.

Note:

Before selecting motor data identification, "Quick commissioning" has to be performed in advance.

Since the cable length of the applications differ in a wide range the preset resistor P0352 is only a rough estimation. Better results of the motor identification can be achieved by specifying the cable resistor before the start of the motor identification by measuring/calculating.

Once enabled (P1910 > 0), A0541 generates a warning that the next ON command will initiate measurement of motor parameters.

Communications - both via USS as well as via the Fieldbus - are interrupted for the time that it takes to make internal calculations.

This can result in the following error messages at the connected SIMATIC S7 control (communications via fieldbus):

- Parameter fault 30
- Drive fault 70
- Drive fault 75

When using STARTER (USS) to commission the drive system, data cannot be entered while these calculations are being made.

The faults can be acknowledged as soon as the calculations have been completed in the frequency inverter. These calculations can take up to one minute to complete.

p1910**Select motor data identification extended / Sel.mot.data ident**

CU240S	Access level: 2	P-Group: Motor identification	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: NO	Data set: -
CU240S DP-F	Can be changed: T	Calculated: -	
CU240S PN			
CU240S PN-F			

Min	Max	Factory setting
0	23	0

Description:

Performs a motor data identification with extended figures.

Value:	0:	Disabled
	1:	Identification of all parameters with parameter change
	2:	Identification of all parameters without parameter change
	3:	Identification of saturation curve with parameter change
	4:	Identification of saturation curve without parameter change
	5:	Identification of XsigDyn (r1920) without parameter change
	6:	Identification of Tdead (r1926) without parameter change
	7:	Identification of Rs (r1912) without parameter change
	8:	Identification of Xs (r1915) without parameter change
	9:	Identification of Tr (r1913) without parameter change
	10:	Identification of Xsigma (r1914) without parameter change
	20:	Set voltage vector
	21:	Set voltage vector without filtering in P69
	22:	Set voltage vector rectangle signal
	23:	Set voltage vector triangle signal

Caution:

Motor identification should be performed on a cold motor.

However, the identification of the motor data should only be performed if the motor temperature is within 5°C of the measured ambient temperature stored in P0625.

If the motor identification is not within the 5°C limit then the correct functioning of Vector Control (VC, SLVC) cannot be guaranteed.

The motor rating plate information with respect to the connection of the motor windings (Star or delta connection) must be correct in order to establish the correct equivalent circuit data.

The motor identification calculates this data based on a Phase of a Star equivalent circuit P0350 - P0360, irrespective of whether the motor is connected star or delta.

This must be considered when the motor data is inputted directly.

Notice:

P1910 can't be changed while the motoridentification with P1900 is active (P1900 = 2 or 3).

When the identification is finished P1910 is set to 0.

When choosing the setting for measurement, observe the following:

1. "with parameter change"
means that the values are actually adopted as Pxxxx parameter settings (see common settings above) and applied to the controller as well as being shown in the read-only parameters below.
2. "without parameter change"
means that the values are only displayed, i.e. shown for checking purposes in the read-only parameters r1912 (identified stator resistance), r1913 (identified rotor time constant), r1914 (ident. total leakage reactance), r1915/r1916/r1917/r1918/r1919 (identified nominal stator reactance/identified stator reactance 1 to 4), r1925 (IG-BT on-state voltage) and r1926 (identified gating unit dead time). The values are not applied to the controller.

Note:

Before selecting motor data identification, "Quick commissioning" has to be performed in advance.

Since the cable length of the applications differ in a wide range the preset resistor P0352 is only a rough estimation. Better results of the motor identification can be achieved by specifying the cable resistor before the start of the motor identification by measuring/calculating.

Once enabled (P1910 > 0), A0541 generates a warning that the next ON command will initiate measurement of motor parameters.

Communications - both via USS as well as via the Fieldbus - are interrupted for the time that it takes to make internal calculations.

This can result in the following error messages at the connected SIMATIC S7 control (communications via fieldbus):

- Parameter fault 30
- Drive fault 70
- Drive fault 75

When using STARTER (USS) to commission the drive system, data cannot be entered while these calculations are being made.

The faults can be acknowledged as soon as the calculations have been completed in the frequency inverter. These calculations can take up to one minute to complete.

p1911	No. of phase to be identified / No.of phase for id		
	Access level: 2	P-Group: Motor identification	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min 1	Max 3	Factory setting 1
Description:	Selects maximum number of motor phases to be identified.		
Note:	Because of averaging (measurement inprecisseness and variations in the phase) a measurement with 3 phases delivers better results than a one phase measurement, but needs significant longer measurement time.		
r1912[0...2]	Identified stator resistance / Identif. stat. res		
	Access level: 2	P-Group: Motor identification	Data type: FloatingPoint32
	Unit: [Ohm]	Calculated: -	Data set: -
Description:	Displays measured stator resistance value (line-to-line) in [Ohms]. This value also includes the cable resistances.		
Index:	[0] = U_phase [1] = V_phase [2] = W_phase		
Notice:	If the value identified (Rs = stator resistance) does not lie within the range 0.1 % < Rs [p. u.] < 100 % fault message 41 (motor data identification failure) is issued. P0949 provides further information (fault value = 2 in this case).		
Note:	This value is measured using P1900 = 2 or 3 (P1910 = 1 or 2) , i.e., identification of all parameters with/without change.		
r1913[0...2]	Identified rotor time constant / Identif.rot.Tconst		
	Access level: 2	P-Group: Motor identification	Data type: FloatingPoint32
	Unit: [ms]	Calculated: -	Data set: -
Description:	Displays identified rotor time constant. [msec]		
Index:	[0] = U_phase [1] = V_phase [2] = W_phase		
Notice:	If the value identified (Tr = rotor time constant) does not lie within the range 10ms < Tr < 5s fault message 41 (motor data identification failure) is issued. P0949 provides further information (fault value = 6 in this case).		
r1914[0...2]	Ident. total leakage inductance / Tot.leak.induct.		
	Access level: 2	P-Group: Motor identification	Data type: FloatingPoint32
	Unit: -	Calculated: -	Data set: -
Description:	Displays identified total leakage inductance. [mH]		
Index:	[0] = U_phase [1] = V_phase [2] = W_phase		
Notice:	If the value identified (Lsigma = leakage inductance) does not lie within the range 5 % < Xsigma [p. u.] < 50 % fault message 41 (motor data identification failure) is issued. P0949 provides further information (fault value = 7 in this case).		

r1915[0...2]	Ident. nom. stator inductance / Nom.stat.induct.		
	Access level: 2	P-Group: Motor identification	Data type: FloatingPoint32
	Unit: -	Calculated: -	Data set: -
Description:	Displays identified stator inductance. [mH]		
Index:	[0] = U_phase [1] = V_phase [2] = W_phase		
Notice:	If the value identified (Ls = stator inductance) does not lie within the range 50 % < Xs [p. u.] < 500 % fault message 41 (motor data identification failure) is issued. P0949 provides further information (fault value = 4 in this case).		
r1916[0...2]	Identified stator inductance 1 / Stator induct. 1		
	Access level: 2	P-Group: Motor identification	Data type: FloatingPoint32
	Unit: -	Calculated: -	Data set: -
Description:	Displays identified stator inductance. [mH]		
Index:	[0] = U_phase [1] = V_phase [2] = W_phase		
Note:	See P1915 (identified nominal stator inductance).		
r1917[0...2]	Identified stator inductance 2 / Stator induct. 2		
	Access level: 2	P-Group: Motor identification	Data type: FloatingPoint32
	Unit: -	Calculated: -	Data set: -
Description:	Displays identified stator inductance. [mH]		
Index:	[0] = U_phase [1] = V_phase [2] = W_phase		
Note:	See P1915 (identified nominal stator inductance)		
r1918[0...2]	Identified stator inductance 3 / Stator induct. 3		
	Access level: 2	P-Group: Motor identification	Data type: FloatingPoint32
	Unit: -	Calculated: -	Data set: -
Description:	Displays identified stator inductance. [mH]		
Index:	[0] = U_phase [1] = V_phase [2] = W_phase		
Note:	See P1915 (identified nominal stator reactance)		
r1919[0...2]	Identified stator inductance 4 / Stator induct. 4		
	Access level: 2	P-Group: Motor identification	Data type: FloatingPoint32
	Unit: -	Calculated: -	Data set: -
Description:	Displays identified stator inductance. [mH]		
Index:	[0] = U_phase [1] = V_phase [2] = W_phase		
Note:	See P1915 (identified nominal stator inductance)		

r1920[0...2]	Identified dyn. leak. inductance / Dyn. leak. induct.		
	Access level: 2	P-Group: Motor identification	Data type: FloatingPoint32
	Unit: -	Calculated: -	Data set: -
Description:	Displays identified total dynamic leakage inductance.		
Index:	[0] = U_phase [1] = V_phase [2] = W_phase		
r1925[0...2]	Identified on-state voltage / Id. on-state V.		
	Access level: 2	P-Group: Motor identification	Data type: FloatingPoint32
	Unit: [V]	Calculated: -	Data set: -
Description:	Displays identified on-state voltage of IGBT. [V]		
Index:	[0] = U_phase [1] = V_phase [2] = W_phase		
Notice:	If the identified on-state voltage does not lie within the range 0.0V < 10V fault message 41 (motor data identification failure) is issued. P0949 provides further information (fault value = 20 in this case).		
r1926	Ident. gating unit dead time / Id.gating deadtime		
	Access level: 2	P-Group: Motor identification	Data type: FloatingPoint32
	Unit: [µs]	Calculated: -	Data set: -
Description:	Displays identified dead time of gating unit interlock. [usec]		
p1930	Voltage setpoint for calibration / Volt setp. calibr.		
	Access level: 4	P-Group: Motor identification	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0 [V]	Max 1000 [V]	Factory setting 0 [V]
Description:	Specifies reference voltage for generation of a test voltage vector (e.g. used for shunt calibration). [V]		
p1931	Phase / Phase		
	Access level: 4	P-Group: Motor identification	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 1	Max 12	Factory setting 1
Description:	Defines phase of voltage vector: 1: u-axis 2: v-axis 3: w-axis 4: -u-axis 5: -v-axis 6: -w-axis 7: uv-axis (30°) 8: wu-axis (150°) 9: vw-axis (270°) 10: -uv-axis (210°) 11: -wu-axi (330°) 12: -vw-axis (90°)		

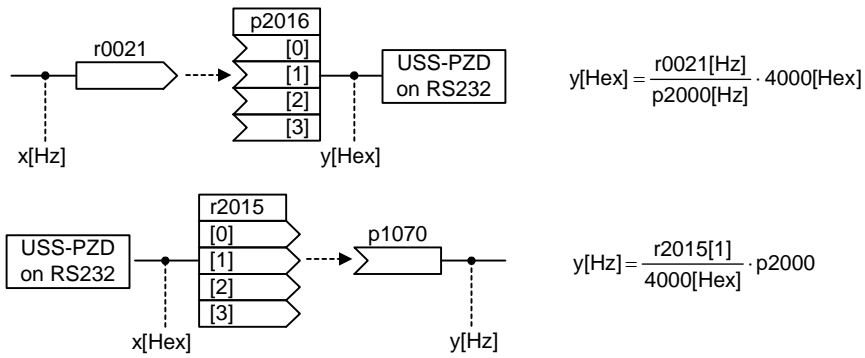
p1960 Speed control optimisation / Speed control opt.			
CU240E	Access level: 3	P-Group: Motor	Data type: Unsigned16
PM240	Quick comm. YES	Active: NO	Data set: -
	Can be changed: C(1), T	Calculated: -	
	Min 0	Max 1	Factory setting 0
Description:	<p>The drive should be set into a vector mode (P1300 = 20) to carry out speed controller optimisation. When speed controller optimisation is enabled (P1960 = 1) the warning A0542 will become active. When the drive is next started it will do the optimisation tests.</p> <p>The drive will accelerate the motor to 20 % of P0310 (rated motor frequency) using the ramp up time P1120 and then under torque control go to 50 % of P0310 (rated motor frequency). The drive will then ramp back down to 20 % using the ramp down time P1121. This procedure is repeated several times and then average time taken.</p> <p>From this an estimation of the inertia of the load on the motor can be derived.</p> <p>From this the inertia ratio parameter (P0342) and the Kp gains for SLVC (P1470) are modified to give a response suitable for the measured inertia.</p>		
Value:	0: Disable 1: Enable		
Notice:	<p>If there is a problem due to instability the drive may trip with an F0042 fault if a stable value has not been obtained on the ramp up within a reasonable time.</p> <p>It should be noted that the DC link controller should be enabled whilst doing the test as otherwise overvoltage trips may be experienced. This will however depend on the ramp down time and the system inertia.</p> <p>The speed loop optimisation may not be suitable for some applications due to the nature of the test i.e. accelerating under torque control from 20 % to 50 %.</p>		
Note:	<p>The speed-controller optimisation can only be carried out if:</p> <ul style="list-style-type: none"> • inverter is in vector control mode • no torque control is active • no flying start function active (P1200 = 0) • without a load on the motor <p>The speed-controller optimisation changes always both parameters P1460 and P1470 undepending what mode (P1300 = 20 or 21) is active. When the test is complete P1960 will be cleared to zero.</p> <p>In SLVC (P1300 = 20) the drive will set the motor model to start in open loop (P1750.0 = 1) when the speed control optimisation is selected (P1960 = 1) and will be set to its old state after the end of the optimisation (P1960 = 0).</p>		

p1960	Speed control optimisation / Speed control opt.		
CU240E	Access level: 3	P-Group: Motor	Data type: Unsigned16
PM250, PM260	Quick comm. YES	Active: NO	Data set: -
	Can be changed: C(1), T	Calculated: -	
	Min	Max	Factory setting
	0	1	0
Description:	<p>The drive should be set into a vector mode (P1300 = 20) to carry out speed controller optimisation. When speed controller optimisation is enabled (P1960 = 1) the warning A0542 will become active. When the drive is next started it will do the optimisation tests.</p> <p>The drive will accelerate the motor to 20 % of P0310 (rated motor frequency) using the ramp up time P1120 and then under torque control go to 50 % of P0310 (rated motor frequency). The drive will then ramp back down to 20 % using the ramp down time P1121. This procedure is repeated several times and then average time taken.</p> <p>From this an estimation of the inertia of the load on the motor can be derived.</p> <p>From this the inertia ratio parameter (P0342) and the Kp gains for SLVC (P1470) are modified to give a response suitable for the measured inertia.</p>		
Value:	0: Disable 1: Enable		
Notice:	<p>If there is a problem due to instability the drive may trip with an F0042 fault if a stable value has not been obtained on the ramp up within a reasonable time.</p> <p>The speed loop optimisation may not be suitable for some applications due to the nature of the test i.e. accelerating under torque control from 20 % to 50 %.</p>		
Note:	<p>The speed-controller optimisation can only be carried out if:</p> <ul style="list-style-type: none"> • inverter is in vector control mode • no torque control is active • no flying start function active (P1200 = 0) • without a load on the motor <p>The speed-controller optimisation changes always both parameters P1460 and P1470 undepending what mode (P1300 = 20 or 21) is active. When the test is complete P1960 will be cleared to zero.</p> <p>In SLVC (P1300 = 20) the drive will set the motor model to start in open loop (P1750.0 = 1) when the speed control optimisation is selected (P1960 = 1) and will be set to its old state after the end of the optimisation (P1960 = 0).</p>		

p1960 Speed control optimisation / Speed control opt.			
CU240S	Access level: 3	P-Group: Motor	Data type: Unsigned16
CU240S DP	Quick comm. YES	Active: NO	Data set: -
CU240S DP-F	Can be changed: C(1), T	Calculated: -	
CU240S PN			
CU240S PN-F			
PM240			
	Min 0	Max 1	Factory setting 0
Description:	<p>The drive should be set into a vector mode (P1300 = 20 or 21) to carry out speed controller optimisation. When speed controller optimisation is enabled (P1960 = 1) the warning A0542 will become active. When the drive is next started it will do the optimisation tests.</p> <p>The drive will accelerate the motor to 20 % of P0310 (rated motor frequency) using the ramp up time P1120 and then under torque control go to 50 % of P0310 (rated motor frequency). The drive will then ramp back down to 20 % using the ramp down time P1121. This procedure is repeated several times and then average time taken. From this an estimation of the inertia of the load on the motor can be derived.</p> <p>From this the inertia ratio parameter (P0342) and the Kp gains for VC (P1460) and SLVC (P1470) are modified to give a response suitable for the measured inertia.</p>		
Value:	0: Disable 1: Enable		
Notice:	<p>If there is a problem due to instability the drive may trip with an F0042 fault if a stable value has not been obtained on the ramp up within a reasonable time.</p> <p>It should be noted that the DC link controller should be enabled whilst doing the test as otherwise overvoltage trips may be experienced. This will however depend on the ramp down time and the system inertia.</p> <p>The speed loop optimisation may not be suitable for some applications due to the nature of the test i.e. accelerating under torque control from 20 % to 50 %.</p>		
Note:	<p>The speed-controller optimisation can only be carried out if:</p> <ul style="list-style-type: none"> • inverter is in vector control mode • no torque control is active • no flying start function active (P1200 = 0) • without a load on the motor <p>The speed-controller optimisation changes always both parameters P1460 and P1470 undepending what mode (P1300 = 20 or 21) is active. When the test is complete P1960 will be cleared to zero.</p> <p>In SLVC (P1300 = 20) the drive will set the motor model to start in open loop (P1750.0 = 1) when the speed control optimisation is selected (P1960 = 1) and will be set to its old state after the end of the optimisation (P1960 = 0).</p>		

p1960 Speed control optimisation / Speed control opt.			
CU240S	Access level: 3	P-Group: Motor	Data type: Unsigned16
CU240S DP	Quick comm. YES	Active: NO	Data set: -
CU240S DP-F	Can be changed: C(1), T	Calculated: -	
CU240S PN			
CU240S PN-F			
PM250, PM260			
	Min 0	Max 1	Factory setting 0
Description:	<p>The drive should be set into a vector mode (P1300 = 20 or 21) to carry out speed controller optimisation. When speed controller optimisation is enabled (P1960 = 1) the warning A0542 will become active. When the drive is next started it will do the optimisation tests.</p> <p>The drive will accelerate the motor to 20 % of P0310 (rated motor frequency) using the ramp up time P1120 and then under torque control go to 50 % of P0310 (rated motor frequency). The drive will then ramp back down to 20 % using the ramp down time P1121. This procedure is repeated several times and then average time taken. From this an estimation of the inertia of the load on the motor can be derived.</p> <p>From this the inertia ratio parameter (P0342) and the Kp gains for VC (P1460) and SLVC (P1470) are modified to give a response suitable for the measured inertia.</p>		
Value:	0: Disable 1: Enable		
Notice:	<p>If there is a problem due to instability the drive may trip with an F0042 fault if a stable value has not been obtained on the ramp up within a reasonable time.</p> <p>The speed loop optimisation may not be suitable for some applications due to the nature of the test i.e. accelerating under torque control from 20 % to 50 %.</p>		
Note:	<p>The speed-controller optimisation can only be carried out if:</p> <ul style="list-style-type: none"> • inverter is in vector control mode • no torque control is active • no flying start function active (P1200 = 0) • without a load on the motor <p>The speed-controller optimisation changes always both parameters P1460 and P1470 undepending what mode (P1300 = 20 or 21) is active. When the test is complete P1960 will be cleared to zero.</p> <p>In SLVC (P1300 = 20) the drive will set the motor model to start in open loop (P1750.0 = 1) when the speed control optimisation is selected (P1960 = 1) and will be set to its old state after the end of the optimisation (P1960 = 0).</p>		

p2000[0...2] Reference frequency / Reference freq.			
	Access level: 2	P-Group: Communications	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: T	Calculated: -	
	Min 1.00 [Hz]	Max 650.00 [Hz]	Factory setting 50.00 [Hz]
Description:	<p>Parameter P2000 represents the reference frequency for frequency values which are displayed/transferred as a percentage or a hexadecimal value.</p> <p>Where:</p> <ul style="list-style-type: none"> • hexadecimal 4000 H ==> P2000 (e.g.: USS-PZD) • percentage 100 % ==> P2000 (e.g.: AI) 		
Example:	<p>If a BICO connection is made between two parameters or alternatively using P0719 or P1000, the 'unit' of the parameters (standardized (Hex) or physical (i.e. Hz) values) may differ. SINAMICS implicitly makes an automatic conversion to the target value.</p>		



Dependency:

Caution:



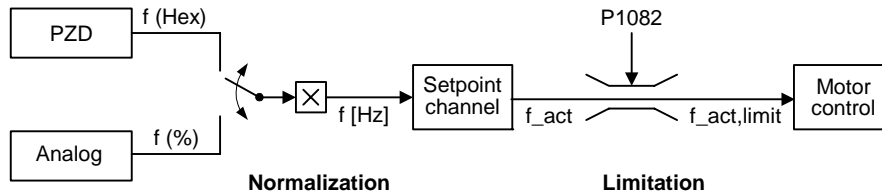
When Quick Commissioning is carried out P2000 is changed as follows: P2000 = P1082.

Parameter P2000 represents the reference frequency of the above mentioned interfaces.

A maximum frequency setpoint of 2*P2000 can be applied via the corresponding interface.

Unlike parameter P1082 (Max. Frequency) this limits the inverter frequency internally independent of the reference frequency.

By modification of P2000 it will also adapt the parameter to the new settings.



$$f[\text{Hz}] = \frac{f(\text{Hex})}{4000(\text{Hex})} \cdot p2000 = \frac{f(\%)}{100\%} \cdot P2000$$

$$f_{\text{act,limit}} = \min(p1082, f_{\text{act}})$$

Notice:

Reference parameters are intended as an aid to presenting setpoint and actual value signals in a uniform manner. This also applies to fixed settings entered as a percentage.

A value of 100 % corresponds to a process data value of 4000H, or 4000 0000H in the case of double values.

In this respect, the following parameters are available:

p2000	Reference frequency	Hz	
p2001	Reference voltage	V	
p2002	Reference current	A	
p2003	Reference torque	Nm	
p2004	Reference power	kW hp	f(p0100)

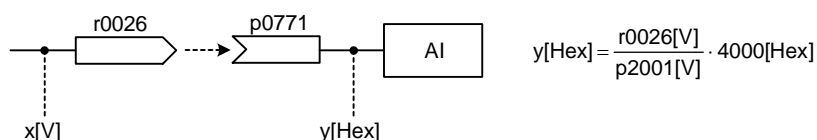
Note:

Changes to P2000 result in a new calculation of P2004.

p2001[0...2]	Reference voltage / Reference voltage		
Access level: 3	P-Group: Communications	Data type: Unsigned16	
Quick comm. NO	Active: NO	Data set: DDS	
Can be changed: T	Calculated: -		
Min 10 [V]	Max 2000 [V]	Factory setting 1000 [V]	

Description: Full-scale output voltage (i.e. 100 %) used over serial link (corresponds to 4000H).

Example:

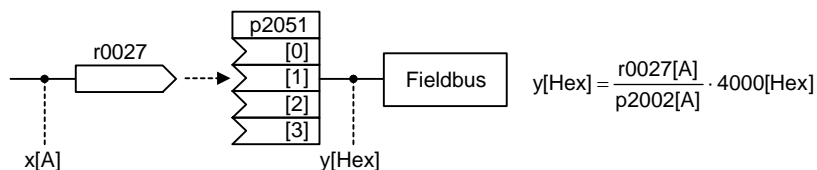


Note: Changes to P2001 result in a new calculation of P2004.

p2002[0...2]	Reference current / Reference current		
Access level: 3	P-Group: Communications	Data type: FloatingPoint32	
Quick comm. NO	Active: NO	Data set: DDS	
Can be changed: T	Calculated: CALC_MOD_ALL		
Min 0.10 [A]	Max 10000.00 [A]	Factory setting 0.10 [A]	

Description: Full-scale output current used over serial link (corresponds to 4000H).

Example: If a BICO connection is made between two parameters, the 'unit' of the parameters (standardized (Hex) or physical (i.e. A) values) may differ. In this case an automatic conversion to the target value is made.

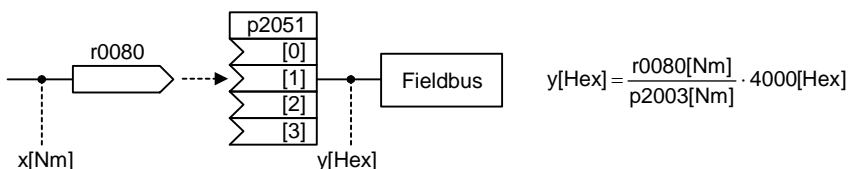


Note: Changes to P2002 result in a new calculation of P2004.

p2003[0...2]	Reference torque / Reference torque		
Access level: 3	P-Group: Communications	Data type: FloatingPoint32	
Quick comm. NO	Active: NO	Data set: DDS	
Can be changed: T	Calculated: CALC_MOD_ALL		
Min 0.10 [Nm]	Max 99999.00 [Nm]	Factory setting 0.75 [Nm]	

Description: Full-scale reference torque used over the serial link (corresponds to 4000H).

Example: If a BICO connection is made between two parameters or alternatively using P1500, the 'unit' of the parameters (standardized (Hex) or physical (i.e. Nm) values) may differ. In this case an automatic conversion to the target value is made.



Note: Changes to P2003 result in a new calculation of P2004.

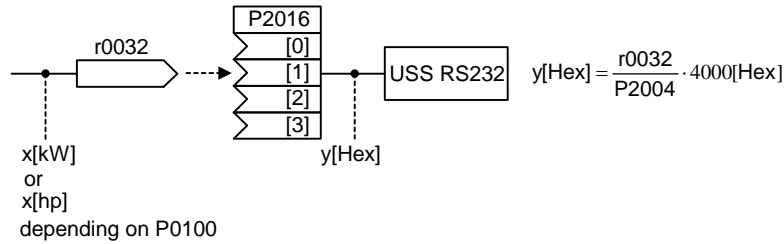
p2004[0...2] Reference power / Reference power

CU240E	Access level: 3	P-Group: Communications	Data type: FloatingPoint32
CU240S	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: T	Calculated: CALC_MOD_ALL	

Min	Max	Factory setting
0.01	2000.00	0.75

Description: Full-scale reference power used over the serial link (corresponds to 4000H).

Example: If a BICO connection is made between two parameters, the 'unit' of the parameters (standardized (Hex) or physical (i.e. kW / hp) values) may differ. In this case an automatic conversion to the target value is made.



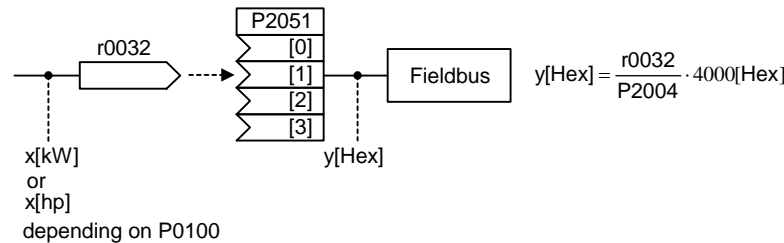
p2004[0...2] Reference power / Reference power

CU240S DP	Access level: 3	P-Group: Communications	Data type: FloatingPoint32
CU240S DP-F	Quick comm. NO	Active: NO	Data set: DDS
CU240S PN	Can be changed: T	Calculated: CALC_MOD_ALL	
CU240S PN-F			

Min	Max	Factory setting
0.01	2000.00	0.75

Description: Full-scale reference power used over the serial link (corresponds to 4000H).

Example: If a BICO connection is made between two parameters, the 'unit' of the parameters (standardized (Hex) or physical (i.e. kW / hp) values) may differ. In this case an automatic conversion to the target value is made.



p2010[0...1]	USS baudrate / USS baudrate		
	Access level: 2	P-Group: Communications	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	4	12	8
Description:	Sets baud rate for USS communication.		
Value:	4: 2400 baud 5: 4800 baud 6: 9600 baud 7: 19200 baud 8: 38400 baud 9: 57600 baud 10: 76800 baud 11: 93750 baud 12: 115200 baud		
Index:	[0] = USS on RS485 [1] = USS on RS232		

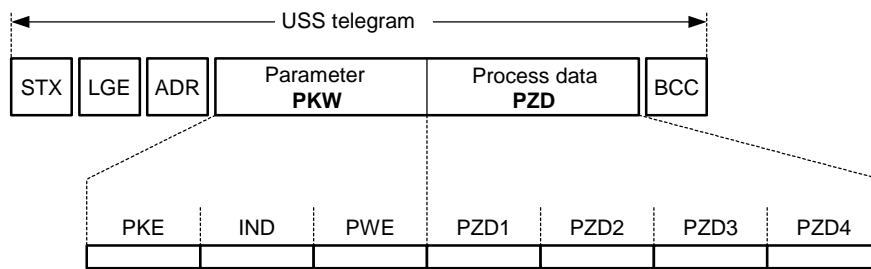
p2011[0...1]	USS address / USS address		
	Access level: 2	P-Group: Communications	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	0	31	0
Description:	Sets unique address for inverter.		
Index:	[0] = USS on RS485 [1] = USS on RS232		
Note:	You can connect up to a further 30 inverters via the serial link (i.e. 31 inverters in total) and control them with the USS serial bus protocol.		

p2012[0...1]	USS PZD length / USS PZD length		
	Access level: 3	P-Group: Communications	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0	Max 8	Factory setting 2

Description: Defines the number of 16-bit words in PZD part of USS telegram.
 In this area, process data (PZD) are continually exchanged between the master and slaves.
 The PZD part of the USS telegram is used for the main setpoint, and to control the inverter.

Index: [0] = USS on RS485
 [1] = USS on RS232

Notice: USS protocol consists of PZD and PKW which can be changed by the user via parameters P2012 and P2013 respectively.



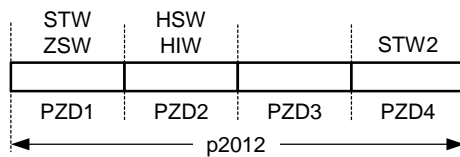
STX	Start of text	PKE	Parameter ID
LGE	Length	IND	Sub-index
ADR	Address	PWE	Parameter value
PKW	Parameter ID value		
PZD	Process data		
BCC	Block check character		

PZD transmits a control word and setpoint or status word and actual values.

The number of PZD-words in a USS-telegram are determined by parameter P2012, where the first two words are either:

- a) control word and main setpoint or
- b) status word and actual value.

When P2012 is greater or equal to 4 the additional control word is transferred as the 4th PZD-word (default setting).



STW	Control word	HSW	Main setpoint
ZSW	Status word	HIW	Main actual value
PZD	Process data		

p2013[0...1]	USS PKW length / USS PKW length		
	Access level: 3	P-Group: Communications	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0	Max 127	Factory setting 127

Description: Defines the number of 16-bit words in PKW part of USS telegram.
The PKW area can be varied.
Depending on the particular requirement, 3-word, 4-word or variable word lengths can be parameterized.
The PKW part of the USS telegram is used to read and write individual parameter values.

Value:
0: No words
3: 3 words
4: 4 words
127: Variable

Example:

	Data type		
	U16 (16 Bit)	U32 (32 Bit)	Float (32 Bit)
p2013 = 3	X	Parameter access fault	Parameter access fault
p2013 = 4	X	X	X
p2013 = 127	X	X	X

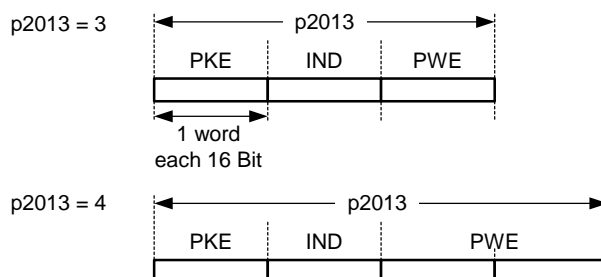
Index:
[0] = USS on RS485
[1] = USS on RS232

Notice: USS protocol consists of PZD and PKW which can be changed by the user via parameters P2012 and P2013 respectively.

Parameter P2013 determines the number of PKW-words in a USS-telegram.

Setting P2013 to 3 or 4 determines the length of the PKW words (3 = three words and 4 = four words).

When P2013 set to 127 automatically adjusts the length of the PKW words are required.



PKE Parameter ID
IND Sub-index
PWE Parameter value

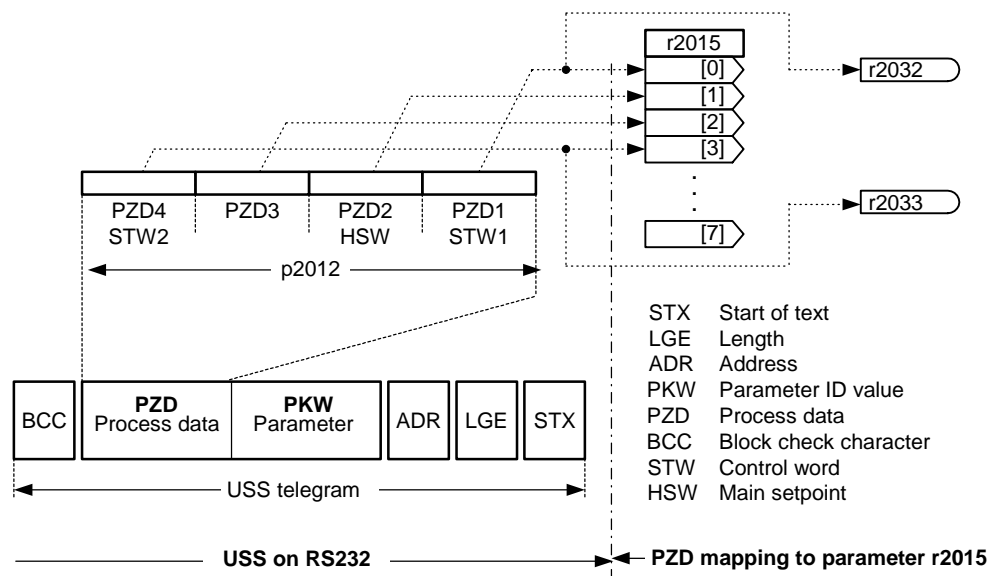
List of Parameters

If a fixed PKW length is selected only one parameter value can be transferred.
 In the case of indexed parameter, you must use the variable PKW length if you wish to have the values of all indices transferred in a single telegram.
 In selecting the fixed PKW length, it is important to ensure the value in question can be transferred using this PKW length.
 P2013 = 3, fixes PKW length, but does not allow access to many parameter values.
 A parameter fault is generated when an out-of-range value is used, the value will not be accepted but the inverter state will not be affected.
 Useful for applications where parameters are not changed, but MM3s are also used.
 Broadcast mode is not possible with this setting.
 P2013 = 4, fixes PKW length.
 Allows access to all parameters, but indexed parameters can only be read one index at a time.
 Word order for single word values are different to setting 3 or 127, see example below.
 P2013 = 127, most useful setting.
 PKW reply length varies depending on the amount of information needed.
 Can read fault information and all indices of a parameter with a single telegram with this setting.

Example:
 Set P0700 to value 5 (0700 = 2BC (hex))

	p2013 = 3	p2013 = 4	p2013 = 127
Master → SINAMICS	22BC 0000 0006	22BC 0000 0000 0006	22BC 0000 0006 0000
SINAMICS → Master	12BC 0000 0006	12BC 0000 0000 0006	12BC 0000 0006

p2014[0...1]	USS telegram off time / USS telegram T_off		
Access level: 3	P-Group: Communications	Data type: Unsigned16	
Quick comm. NO	Active: YES	Data set: -	
Can be changed: T	Calculated: -		
Min 0 [ms]	Max 65535 [ms]	Factory setting 0 [ms]	
Description:	Index 0 defines a time T_off after which a fault will be generated (F0072) if no telegram is received via the USS channel RS485. Index 1 defines a time T_off after which a fault will be generated (F0071) if no telegram is received via the USS channel RS232.		
Index:	[0] = USS on RS485 [1] = USS on RS232		
Notice:	By default (time set to 0), no fault is generated (i.e. watchdog disabled).		

r2015[0...7] CO: PZD from USS on RS232 / PZD<-USS**Access level:** 3**P-Group:** Communications**Data type:** Unsigned16**Unit:** -**Calculated:** -**Data set:** -**Description:** Displays process data received via USS on RS232.

Index:

- [0] = Received word 0
- [1] = Received word 1
- [2] = Received word 2
- [3] = Received word 3
- [4] = Received word 4
- [5] = Received word 5
- [6] = Received word 6
- [7] = Received word 7

Note: The control words can be viewed as bit parameters r2032 and r2033.

Restrictions:

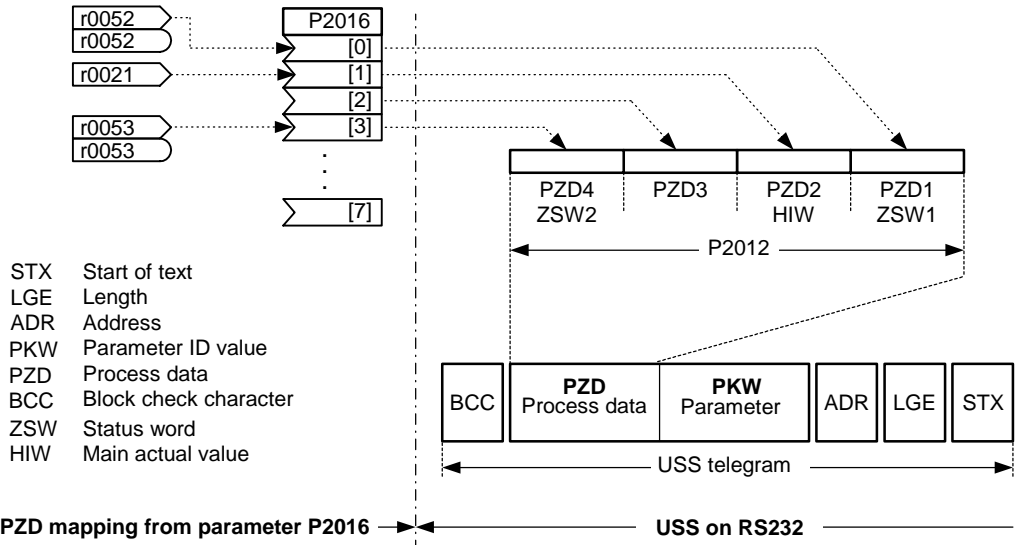
- If the above serial interface controls the inverter (P0700 or P0719) then the 1st control word must be transferred in the 1st PZD-word.
- If the setpoint source is selected via P1000 or P0719, then the main setpoint must be transferred in the 2nd PZD-word,
- When P2012 is greater than or equal to 4 the additional control word (2nd control word) must be transferred in the 4th PZD-word, if the above serial interface controls the inverter (P0700 or P0719).

p2016[0...7]

CI: PZD to USS on RS232 / PZD->USS

Access level: 3	P-Group: Communications	Data type: U32 / Integer16
Quick comm. NO	Active: NO	Data set: -
Can be changed: T	Calculated: -	
Min	Max	Factory setting
-	-	52[0]

Description: Selects signals to be transmitted to serial interface via USS on RS232.



This parameter defines the source of the status words and actual values for the reply PZD.

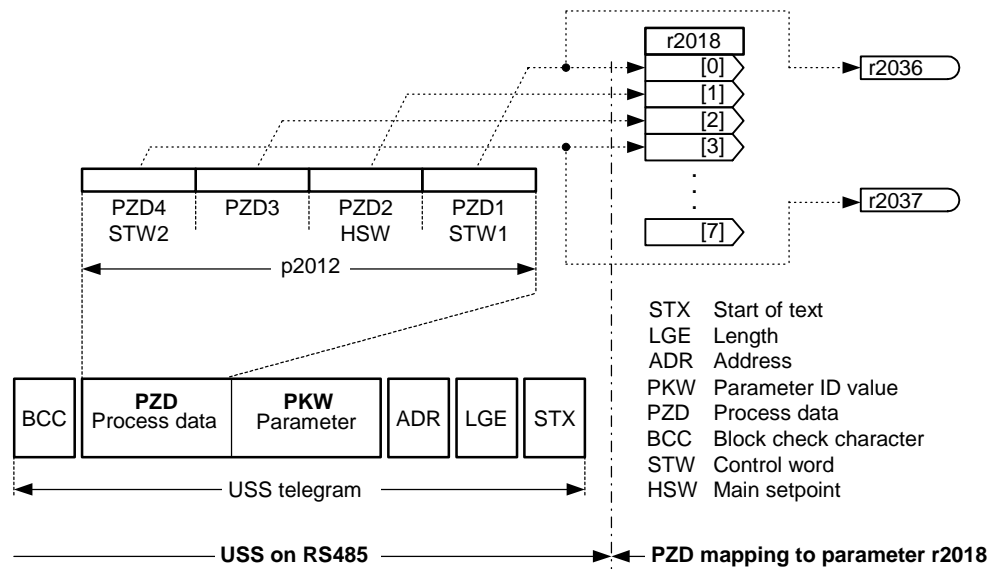
Index 0 cannot be changed and contains always statusword 1.

Example: P2016[0] = 52.0 (default). In this case, the value of r0052 (CO/BO: Status word) is transmitted as 1st PZD to the USS on RS232.

Index:
 [0] = Transmitted word 0
 [1] = Transmitted word 1
 [2] = Transmitted word 2
 [3] = Transmitted word 3
 [4] = Transmitted word 4
 [5] = Transmitted word 5
 [6] = Transmitted word 6
 [7] = Transmitted word 7

Note: If r0052 not indexed, display does not show an index ("0").

r2018[0...7]	CO: PZD from USS on RS485 / PZD<-COM(USS)		
CU240E	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S	Unit: -	Calculated: -	Data set: -
Description:	Displays process data received via USS on RS485.		



Index:

[0] = Received word 0
 [1] = Received word 1
 [2] = Received word 2
 [3] = Received word 3
 [4] = Received word 4
 [5] = Received word 5
 [6] = Received word 6
 [7] = Received word 7

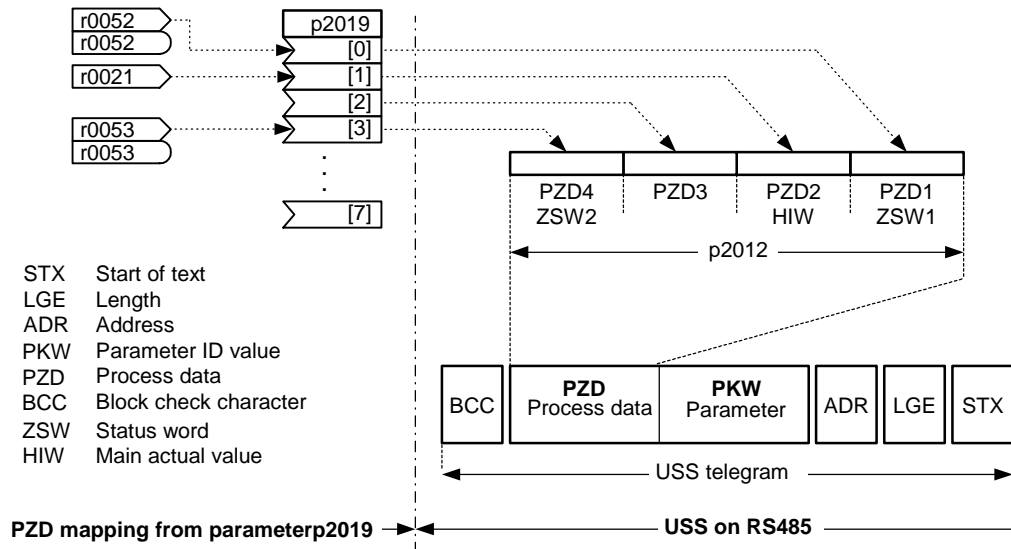
Note:

Restrictions:

- If the above serial interface controls the inverter (P0700 or P0719) then the 1st control word must be transferred in the 1st PZD-word.
- If the setpoint source is selected via P1000 or P0719, then the main setpoint must be transferred in the 2nd PZD-word,
- When P2012 is greater than or equal to 4 the additional control word (2nd control word) must transferred in the 4th PZD-word, if the above serial interface controls the inverter (P0700 or P0719).

p2019[0...7] **CI: PZD to USS on RS485 (USS) / PZD->COM (USS)**
 CU240E **Access level:** 3 **P-Group:** Communications **Data type:** U32 / Integer16
 CU240S **Quick comm. NO** **Active:** NO **Data set:** -
 Can be changed: T **Calculated:** -
 Min **Max** **Factory setting**
 - - 52[0]

Description: Displays process data received via USS on RS485.



Index:
 [0] = Transmitted word 0
 [1] = Transmitted word 1
 [2] = Transmitted word 2
 [3] = Transmitted word 3
 [4] = Transmitted word 4
 [5] = Transmitted word 5
 [6] = Transmitted word 6
 [7] = Transmitted word 7

Note: See P2016 (PZD to USS on RS232)

r2024[0...1] **USS error-free telegrams / USS error-free tel**
 Access level: 3 **P-Group:** Communications **Data type:** Unsigned16
 Unit: - **Calculated:** - **Data set:** -

Description: Displays number of error-free USS telegrams received.

Index:
 [0] = USS on RS485
 [1] = USS on RS232

r2025[0...1] **USS rejected telegrams / USS rejected tel.**
 Access level: 3 **P-Group:** Communications **Data type:** Unsigned16
 Unit: - **Calculated:** - **Data set:** -

Description: Displays number of USS telegrams rejected.

Index:
 [0] = USS on RS485
 [1] = USS on RS232

r2026[0...1]	USS character frame error / USS char.frame err		
	Access level: 3	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays number of USS character frame errors.		
Index:	[0] = USS on RS485 [1] = USS on RS232		
r2027[0...1]	USS overrun error / USS overrun error		
	Access level: 3	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays number of USS telegrams with overrun error.		
Index:	[0] = USS on RS485 [1] = USS on RS232		
r2028[0...1]	USS parity error / USS parity error		
	Access level: 3	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays number of USS telegrams with parity error.		
Index:	[0] = USS on RS485 [1] = USS on RS232		
r2029[0...1]	USS start not identified / USS start unident.		
	Access level: 3	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays number of USS telegrams with unidentified start.		
Index:	[0] = USS on RS485 [1] = USS on RS232		
r2030[0...1]	USS BCC error / USS BCC error		
	Access level: 3	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays number of USS telegrams with BCC error.		
Index:	[0] = USS on RS485 [1] = USS on RS232		
r2031[0...1]	USS length error / USS length error		
	Access level: 3	P-Group: Communications	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays number of USS telegrams with incorrect length.		
Index:	[0] = USS on RS485 [1] = USS on RS232		

r2032.0...15		BO: CtrlWrd1 from USS on RS232 / CtrlWd1 <- USS			
	Access level: 3	P-Group: Communications	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays control word 1 from USS on RS232 (word 1 within USS).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	ON/OFF1	Yes	No	-
	01	OFF2: Electrical stop	No	Yes	-
	02	OFF3: Fast stop	No	Yes	-
	03	Pulse enable	Yes	No	-
	04	RFG enable	Yes	No	-
	05	RFG start	Yes	No	-
	06	Setpoint enable	Yes	No	-
	07	Fault acknowledge	Yes	No	-
	08	JOG right	Yes	No	-
	09	JOG left	Yes	No	-
	10	Control from PLC	Yes	No	-
	11	Reverse (setpoint inversion)	Yes	No	-
	13	Motor potentiometer MOP up	Yes	No	-
	14	Motor potentiometer MOP down	Yes	No	-
	15	CDS Bit 0 (Hand/Auto)	Yes	No	-

r2033.0...15		BO: CtrlWrd2 from USS on RS232 / CtrlWd2 <- USS			
PM240	Access level: 3	P-Group: Communications	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays control word 2 from USS on RS232 (i.e. word 4 within USS).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fixed frequency Bit 0	Yes	No	-
	01	Fixed frequency Bit 1	Yes	No	-
	02	Fixed frequency Bit 2	Yes	No	-
	03	Fixed frequency Bit 3	Yes	No	-
	04	Drive Dataset (DDS) Bit 0	Yes	No	-
	05	Drive Dataset (DDS) Bit 1	Yes	No	-
	08	Enable PID	Yes	No	-
	09	Enable DC brake	Yes	No	-
	11	Enable Droop	Yes	No	-
	12	Torque control	Yes	No	-
	13	External fault 1	No	Yes	-
	15	Command Dataset (CDS) Bit 1	Yes	No	-
Dependency:	P0700 = 4 (USS on RS232) and P0719 = 0 (Cmd / Setpoint = BICO parameter).				

r2033.0...15		BO: CtrlWrd2 from USS on RS232 / CtrlWd2 <- USS			
PM250	Access level: 3	P-Group: Communications	Data type: Unsigned16		
PM260	Unit: -	Calculated: -	Data set: -		
Description:	Displays control word 2 from USS on RS232 (i.e. word 4 within USS).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fixed frequency Bit 0	Yes	No	-
	01	Fixed frequency Bit 1	Yes	No	-
	02	Fixed frequency Bit 2	Yes	No	-
	03	Fixed frequency Bit 3	Yes	No	-
	04	Drive Dataset (DDS) Bit 0	Yes	No	-
	05	Drive Dataset (DDS) Bit 1	Yes	No	-
	08	Enable PID	Yes	No	-
	11	Enable Droop	Yes	No	-
	12	Torque control	Yes	No	-
	13	External fault 1	No	Yes	-
	15	Command Dataset (CDS) Bit 1	Yes	No	-
Dependency:	P0700 = 4 (USS on RS232) and P0719 = 0 (Cmd / Setpoint = BICO parameter).				

r2036.0...15	BO: CtrlWrd1 from USS on RS485 (USS) / CtrlWd 1 <- COM		
CU240E	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S	Unit: -	Calculated: -	Data set: -

Description: Displays control word 1 from USS on RS485 (i.e. word 1 within USS = PZD1).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	ON/OFF1	Yes	No	-
	01	OFF2: Electrical stop	No	Yes	-
	02	OFF3: Fast stop	No	Yes	-
	03	Pulse enable	Yes	No	-
	04	RFG enable	Yes	No	-
	05	RFG start	Yes	No	-
	06	Setpoint enable	Yes	No	-
	07	Fault acknowledge	Yes	No	-
	08	JOG right	Yes	No	-
	09	JOG left	Yes	No	-
	10	Control from PLC	Yes	No	-
	11	Reverse (setpoint inversion)	Yes	No	-
	13	Motor potentiometer MOP up	Yes	No	-
	14	Motor potentiometer MOP down	Yes	No	-
	15	CDS Bit 0 (Hand/Auto)	Yes	No	-

Dependency: See parameter P2012

Note: See r2033 (control word 2 from USS on RS232).

r2037.0...15	BO: CtrlWrd2 from USS on RS485 (USS) / CtrlWd2 <- COM		
CU240E	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S	Unit: -	Calculated: -	Data set: -
PM240			

Description: Displays control word 2 from USS on RS485 (i.e. word 4 within USS = PZD4).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fixed frequency Bit 0	Yes	No	-
	01	Fixed frequency Bit 1	Yes	No	-
	02	Fixed frequency Bit 2	Yes	No	-
	03	Fixed frequency Bit 3	Yes	No	-
	04	Drive Dataset (DDS) Bit 0	Yes	No	-
	05	Drive Dataset (DDS) Bit 1	Yes	No	-
	08	Enable PID	Yes	No	-
	09	Enable DC brake	Yes	No	-
	11	Enable Droop	Yes	No	-
	12	Torque control	Yes	No	-
	13	External fault 1	No	Yes	-
	15	Command Dataset (CDS) Bit 1	Yes	No	-

Dependency: See parameter P2012

Note: See r2033 (control word 2 from USS on RS232).

To enable the external fault (r2037 Bit 13) facility via USS, the following parameters must be set:

- P2012 = 4
- P2106 = 1

r2037.0...15	BO: CtrlWrd2 from USS on RS485 (USS) / CtrlWrd2 <- COM		
CU240E	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S	Unit: -	Calculated: -	Data set: -
PM250, PM260			

Description: Displays control word 2 from USS on RS485 (i.e. word 4 within USS = PZD4).

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fixed frequency Bit 0	Yes	No	-
	01	Fixed frequency Bit 1	Yes	No	-
	02	Fixed frequency Bit 2	Yes	No	-
	03	Fixed frequency Bit 3	Yes	No	-
	04	Drive Dataset (DDS) Bit 0	Yes	No	-
	05	Drive Dataset (DDS) Bit 1	Yes	No	-
	08	Enable PID	Yes	No	-
	11	Enable Droop	Yes	No	-
	12	Torque control	Yes	No	-
	13	External fault 1	No	Yes	-
	15	Command Dataset (CDS) Bit 1	Yes	No	-

Dependency: See parameter P2012

Note: See r2033 (control word 2 from USS on RS232).

To enable the external fault (r2037 Bit 13) facility via USS, the following parameters must be set:

- P2012 = 4
- P2106 = 1

p2038	Selection of actual profile / Actual profile		
CU240E	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	0	3	0
Value:	0: PROFIdrive Profile		
	2: Namur		
	3: reserved		

p2038		Selection of actual profile / Actual profile	
CU240S DP	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S DP-F	Quick comm. NO	Active: NO	Data set: -
CU240S PN	Can be changed: T	Calculated: -	
CU240S PN-F			
	Min 0	Max 3	Factory setting 0
Description:	Selects the profile which can be : PROFdrive Profile or VIK/Namur.		
Value:	0: PROFdrive Profile 2: Namur 3: reserved		
Dependency:	Setting parameter P2038 to Namur by selecting Telegram 20 in P0922. Setting parameter P0922 from Telegram 20 to other setting will reset P2038 to PROFdrive Profile.		
Note:	Changing P2038 also resets all the BICO connections corresponding to settings in P0700 and P0922. Example: P0700 = 4, P2038 = 0, P0922 = 999, P0840 = 2032.0 Set P0840 = 722.0 Now change P2038 : the parameter P0840 will be reset to 2032.0 (P0700 = 4) By changing P0922 or P2038, following parameters can be modified : <ul style="list-style-type: none"> for the control word 1: P0840, P0844, P0848, P0852, P1140, P1141, P1142, P2104, P1055, P1056, P1113, P1035, P1036, P0810, P0820 for the control word 2: P1020, P1021, P1022, P1023, P0820, P0821, P2200, P1230, P1501, P2106 See also : Switching to / from Namur in the description of parameter P0922.		
p2040		Fieldbus telegram off time / FB tel. off time	
CU240S DP	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S DP-F	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min 0 [ms]	Max 65535 [ms]	Factory setting 500 [ms]
Description:	Defines time after which a fault will be generated (F0070) if no telegram is received via the link.		
Dependency:	Setting 0 = watchdog disabled		
p2041[0...4]		FB parameter / FB parameter	
CU240S DP	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S DP-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min 0	Max 65535	Factory setting 0
Description:	Configures the communication. 2041.0: ever 0 (readonly) 2041.1: FB parameter volatile write access on S7 service (0 = non volatile) 2041.2: ever 0 (readonly) 2041.3: selection of diagnose page 2041.4: ever 0 (readonly)		
Index:	[0] = FB parameter 0 [1] = S7 OP volatile [2] = FB parameter 2 [3] = Diagnose page [4] = FB parameter 4		
Note:	See relevant communication board manual for protocol definition and appropriate settings.		

p2042 Selection of ident number / Ident nb

Access level: 3	P-Group: -	Data type: Unsigned16
Quick comm. NO	Active: NO	Data set: -
Can be changed: T	Calculated: -	

Min	Max	Factory setting
0	1	0

Description: Selects if native ident number (0) or NAMUR ident number (1) is sent to the PLC.

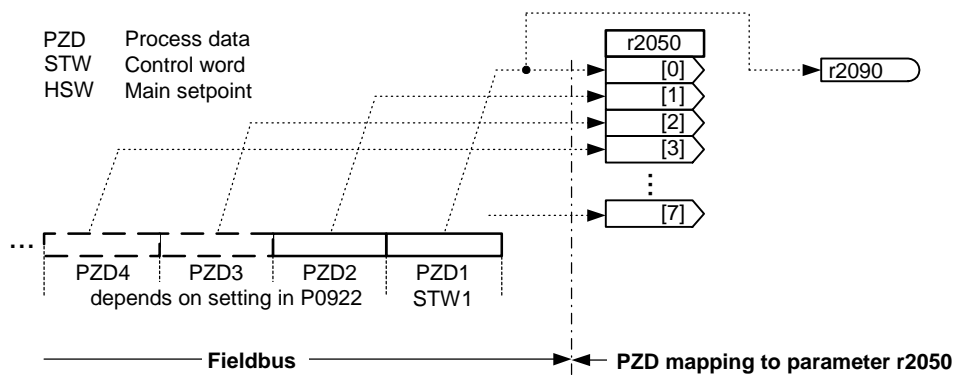
Value:
 0: Native
 1: Namur

Note: NAMUR ident number (P2042=1) is not available on ProfiNet.
 After changing P2042, a power cycle must be done to have changes take effect.
 See also : Switching to / from Namur in the description of parameter P0922.

r2050[0...7] CO: PZD from Fieldbus / PZD from FB

CU240S DP	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S DP-F	Unit: -	Calculated: -	Data set: -
CU240S PN			
CU240S PN-F			

Description: Displays PZD received from Fieldbus.



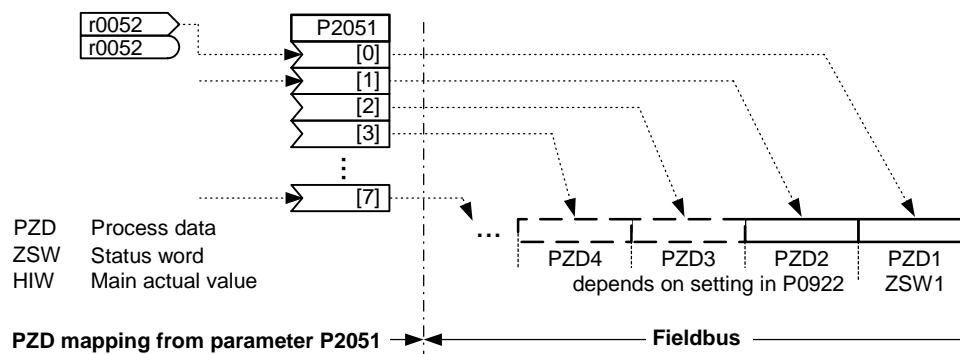
Index:
 [0] = Received word 0
 [1] = Received word 1
 [2] = Received word 2
 [3] = Received word 3
 [4] = Received word 4
 [5] = Received word 5
 [6] = Received word 6
 [7] = Received word 7

Note: The control words can be viewed as bit parameters r2090 and r2091.

p2051[0...7]	CI: PZD to Fieldbus / PZD to FB		
CU240S DP	Access level: 3	P-Group: Communications	Data type: U32 / Integer16
CU240S DP-F	Quick comm. NO	Active: YES	Data set: -
CU240S PN	Can be changed: T	Calculated: -	
CU240S PN-F			

Min	Max	Factory setting
-	-	52[0]

Description: Connects PZD to Fieldbus.
This parameter allows the user to define the source of status words and actual values for the reply PZD.



Index:

- [0] = Transmitted word 0
- [1] = Transmitted word 1
- [2] = Transmitted word 2
- [3] = Transmitted word 3
- [4] = Transmitted word 4
- [5] = Transmitted word 5
- [6] = Transmitted word 6
- [7] = Transmitted word 7

Dependency: When Standard Telegram selected (p0922) and Control from PROFIBUS, parameter cannot be changed except Standard Telegram 20, index 5.

r2053[0...7]	FB identification / FB identification		
CU240S DP	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S DP-F	Unit: -	Calculated: -	Data set: -
Description:	Displays identification data of the communication. 2053[0]: = 0 = No communication option available 2053[0]: = 1 = PROFIBUS DP 2053[0]: = 2 = DeviceNet 2053[0]: = 3 = CAN 2053[0]: = 4 = AS-i 2053[0]: = 5 = LON 2053[0]: = 6 = Modbus 2053[0]: = 10 = PROFINET IO 2053[0]: = 11 = ES bus (ET200pro) 2053[0]: = 4660 = ES bus (ET200s) 2053[0]: = 65535 = not defined 2053[1]: firmware version (major and minor each with 2 digits) 2053[2]: firmware version detail (release and build each with 2 digits) 2053[3]: firmware date (year with century) 2053[4]: firmware date (day and month each with 2 digits) 2053[5]: datastructure version 2053[6]: driver version 2053[7]: company ID (42 = SIEMENS)		
Index:	[0] = Fieldbus type (PROFIBUS = 1) [1] = Firmware version [2] = Firmware version detail [3] = Firmware date (year) [4] = Firmware date (day/month) [5] = datastructure version [6] = driver version [7] = company ID		

r2054[0...15]	FB diagnosis / FB diagnosis		
CU240S DP	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S DP-F	Unit: -	Calculated: -	Data set: -
Description:	Displays diagnostic information of communication.		
Index:	[0] = FB diagnosis 0 [1] = FB diagnosis 1 [2] = FB diagnosis 2 [3] = FB diagnosis 3 [4] = FB diagnosis 4 [5] = FB diagnosis 5 [6] = FB diagnosis 6 [7] = FB diagnosis 7 [8] = FB diagnosis 8 [9] = FB diagnosis 9 [10] = FB diagnosis 10 [11] = FB diagnosis 11 [12] = FB diagnosis 12 [13] = FB diagnosis 13 [14] = FB diagnosis 14 [15] = FB diagnosis 15		
Note:	Diagnose entries 2054[0]: state of PROFIBUS: 0=off, 1=baud search; 2=baud found; 3=data exchange 2054[1]: C0 master configuration info for cyclic data, combination of 5 digits pxyxy (decimal) p : 0 no additional cyclic data (no PKW and no PROFIsafe) 1 PKW data configured (4 words input and 4 words output) 2 PROFIsafe data configured (3 words input and 3 words output) 3 PKW and PROFIsafe data configured 4..9 wrong configuration xx: PZD input length (reference values) yy: PZD output length (actual values) The values for PZD input and output length (xx and yy) do not contain any additional data length. 2054[2]: count of C2 connections 0..2 2054[3]: parameter access error: internal error number 2054[4]: parameter access error: parameter number 2054[5]: parameter access error: subindex 2054[6]: remote publisher count and remote publisher ok (example: 11114, 4 publisher, each is ok) 2054[7]: address of remote publisher 1 2054[8]: address of remote publisher 2 2054[9]: address of remote publisher 3 2054[10]: address of remote publisher 4 2054[11]: empty (=0) 2054[12]: empty (=0) 2054[13]: empty (=0) 2054[14]: empty (=0) 2054[15]: empty (=0)		

r2058[0...15]	FB rev config / FB rev config		
CU240S DP	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S DP-F	Unit: -	Calculated: -	Data set: -

Description: Displays reverse config data display communication.

Index:
 [0] = FB diagnosis 0
 [1] = FB diagnosis 1
 [2] = FB diagnosis 2
 [3] = FB diagnosis 3
 [4] = FB diagnosis 4
 [5] = FB diagnosis 5
 [6] = FB diagnosis 6
 [7] = FB diagnosis 7
 [8] = FB diagnosis 8
 [9] = FB diagnosis 9
 [10] = FB diagnosis 10
 [11] = FB diagnosis 11
 [12] = FB diagnosis 12
 [13] = FB diagnosis 13
 [14] = FB diagnosis 14
 [15] = FB diagnosis 15

r2059[0...4]	CO: Displays SOL link stats for Sol Master. / Disp SOL stats		
CU240S DP	Access level: 4	P-Group: Communications	Data type: Unsigned16
CU240S DP-F	Unit: -	Calculated: -	Data set: -
CU240S PN			
CU240S PN-F			

Index:
 [0] = messages txd
 [1] = valid messages rxd
 [2] = crc errors
 [3] = stx errors
 [4] = reconfigurations

r2090.0...15	BO: Control word 1 from Fieldbus / CtrlWd1 <- FB		
CU240S DP	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S DP-F	Unit: -	Calculated: -	Data set: -
CU240S PN			
CU240S PN-F			

Description: Displays control word 1 received from Fieldbus.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	ON/OFF1	Yes	No	-
	01	OFF2: Electrical stop	No	Yes	-
	02	OFF3: Fast stop	No	Yes	-
	03	Pulse enable	Yes	No	-
	04	RFG enable	Yes	No	-
	05	RFG start	Yes	No	-
	06	Setpoint enable	Yes	No	-
	07	Fault acknowledge	Yes	No	-
	08	JOG right	Yes	No	-
	09	JOG left	Yes	No	-
	10	Control from PLC	Yes	No	-
	11	Reverse (setpoint inversion)	Yes	No	-
	13	Motor potentiometer MOP up	Yes	No	-
	14	Motor potentiometer MOP down	Yes	No	-
	15	CDS Bit 0 (Hand/Auto)	Yes	No	-

Note: If P0700 = 6 (PROFIBUS) then P810 must be set to 2090.15 for correct operation.
 This will not be cleared automatically when P0700 is no longer equal to 6.

r2091.0...15	BO: Control word 2 from Fieldbus / CtrlWd2 <- FB		
CU240S DP	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S DP-F	Unit: -	Calculated: -	Data set: -
CU240S PN			
CU240S PN-F			
PM240			

Description: Displays control word 2 received from Fieldbus.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fixed frequency Bit 0	Yes	No	-
	01	Fixed frequency Bit 1	Yes	No	-
	02	Fixed frequency Bit 2	Yes	No	-
	03	Fixed frequency Bit 3	Yes	No	-
	04	Drive Dataset (DDS) Bit 0	Yes	No	-
	05	Drive Dataset (DDS) Bit 1	Yes	No	-
	08	Enable PID	Yes	No	-
	09	Enable DC brake	Yes	No	-
	11	Enable Droop	Yes	No	-
	12	Torque control	Yes	No	-
	13	External fault 1	No	Yes	-
	15	Command Dataset (CDS) Bit 1	Yes	No	-

r2091.0...15	BO: Control word 2 from Fieldbus / CtrlWd2 <- FB		
CU240S DP	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S DP-F	Unit: -	Calculated: -	Data set: -
CU240S PN			
CU240S PN-F			
PM250, PM260			

Description: Displays control word 2 received from Fieldbus.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fixed frequency Bit 0	Yes	No	-
	01	Fixed frequency Bit 1	Yes	No	-
	02	Fixed frequency Bit 2	Yes	No	-
	03	Fixed frequency Bit 3	Yes	No	-
	04	Drive Dataset (DDS) Bit 0	Yes	No	-
	05	Drive Dataset (DDS) Bit 1	Yes	No	-
	08	Enable PID	Yes	No	-
	11	Enable Droop	Yes	No	-
	12	Torque control	Yes	No	-
	13	External fault 1	No	Yes	-
	15	Command Dataset (CDS) Bit 1	Yes	No	-

p2100[0...2]	Alarm number selection / Alarm No selection		
	Access level: 3	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	0	65535	0

Description: Selects up to 3 faults or warnings for non-default reactions.

Example: If, for example, an OFF3 is to be carried out instead of an OFF2 for a fault, the fault number has to be entered in P2100 and the desired reaction selected in P2101 (in this case (OFF3) P2101 = 3).

Index:
 [0] = Fault Number 1
 [1] = Fault Number 2
 [2] = Fault Number 3

Note: All fault codes have a default reaction to OFF2.
 Some fault codes caused by hardware trips (e.g. overcurrent) cannot be changed from the default reactions.

p2101[0...2]	Stop reaction value / Stop reaction val.		
	Access level: 3	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min 0	Max 4	Factory setting 0
Description:	Sets drive stop reaction values for faults selected by P2100 (alarm number selection). This indexed parameter specifies the special reaction to the faults/warnings defined in P2100 indices 0 to 2.		
Value:	0: No reaction, no display 1: OFF1 stop reaction 2: OFF2 stop reaction 3: OFF3 stop reaction 4: No reaction warning only		
Index:	[0] = Stop reaction value 1 [1] = Stop reaction value 2 [2] = Stop reaction value 3		
Note:	Settings 1 - 3 are only available for fault codes. Setting 4 is only available for warnings. Index 0 (P2101) refers to fault/warning in index 0 (P2100).		
p2103[0...2]	BI: 1. Faults acknowledgement / 1. Faults ackn		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 722.2
Description:	Defines first source of fault acknowledgement.		
p2104[0...2]	BI: 2. Faults acknowledgement / 2. Faults ackn		
CU240E	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	Selects second source of fault acknowledgement.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
p2104[0...2]	BI: 2. Faults acknowledgement / 2. Faults ackn		
CU240S DP	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 2090.7
Description:	Selects second source of fault acknowledgement.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		

p2104[0...2]	BI: 2. Faults acknowledgement / 2. Faults ackn		
CU240S PN	Access level: 3	P-Group: Commands	Data type: U32 / Binary
CU240S PN-F	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	8890.7
Description:	Selects second source of fault acknowledgement.		
Dependency:	When Standard Telegram selected (P0700 = 6, P0922 = Standard Telegram), parameter cannot be changed.		
p2106[0...2]	BI: External fault / External fault		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	1
Description:	Selects source of external faults.		
Dependency:	When Standard Telegram 350 and PROFIBUS selected (P0700 = 6, P0922 = 350), parameter cannot be changed.		
r2110[0...3]	CO: Warning number / Warning number		
	Access level: 2	P-Group: Messages	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays warning information. A maximum of 2 active warnings (indices 0 and 1) and 2 historical warnings (indices 2 and 3) may be viewed.		
Index:	[0] = Recent Warnings --, warning 1 [1] = Recent Warnings --, warning 2 [2] = Recent Warnings -1, warning 3 [3] = Recent Warnings -1, warning 4		
Notice:	Indices 0 and 1 are not stored.		
Note:	The LED indicates the warning status in this case. The keypad will flash while a warning is active.		
p2111	Total number of warnings / Total no. warnings		
	Access level: 3	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	0	4	0
Description:	Displays number of warning (up to 4) since last reset. Set to 0 to reset the warning history.		

r2114[0...1]	Run time counter / Run time counter		
	Access level: 3	P-Group: Messages	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	<p>Displays run time counter.</p> <p>It is the total time the drive has been powered up. When power is switched off, the value is saved, then restored on powerup.</p> <p>The run time counter will be calculate as followed:</p> <p>Multiply the value in r2114[0] by 65536 and then add it to the value in r2114[1]. The resultant answer will be in seconds. This means that r2114[0] is not days.</p> <p>Total powerup time = 65536 * r2114[0] + r2114[1] seconds.</p>		
Example:	<p>If r2114[0] = 1 and r2114[1] = 20864</p> <p>We get 1 * 65536 + 20864 = 86400 seconds which equals 1 day.</p>		
Index:	<p>[0] = System Time, Seconds, Upper Word</p> <p>[1] = System Time, Seconds, Lower Word</p>		
Note:	<p>When the real time is not given in P2115, the time in this parameter is used by r0948 to indicate when a fault has occurred.</p> <p>See r0948 (fault time).</p>		

p2115[0...2]	Real time clock / Real time clk														
	Access level: 4	P-Group: Messages	Data type: Unsigned16												
	Quick comm. NO	Active: YES	Data set: -												
	Can be changed: T	Calculated: -													
	Min 0	Max 65535	Factory setting 257												
Description:	<p>Displays real time.</p> <p>All inverters require an on-board clock function with which fault conditions may be timestamped and logged. However, they have no battery backed Real Time Clock (RTC). Inverters may support a software driven RTC which requires synchronisation with the RTC supplied via a serial interface.</p> <p>The time is stored in a word array parameter P2115. The time will be set by USS Protocol standard "word array parameter write" telegrams. Once the last word is received in index 2, the software will start running the timer itself using internal running 1 millisecond tic. Hence becoming like RTC.</p> <p>If powercycle takes place, then the real time must be sent again to the inverter.</p> <p>Time is maintained in a word array parameter and encoded as follows - the same format will be used in fault report logs.</p>														
	<table border="1"> <thead> <tr> <th>Index</th> <th>High Byte (MSB)</th> <th>Low Byte (LSB)</th> </tr> </thead> <tbody> <tr> <td>0</td> <td>Seconds (0 - 59)</td> <td>Minutes (0 - 59)</td> </tr> <tr> <td>1</td> <td>Hours (0 - 23)</td> <td>Days (1 - 31)</td> </tr> <tr> <td>2</td> <td>Month (1 - 12)</td> <td>Years (00 - 250)</td> </tr> </tbody> </table>			Index	High Byte (MSB)	Low Byte (LSB)	0	Seconds (0 - 59)	Minutes (0 - 59)	1	Hours (0 - 23)	Days (1 - 31)	2	Month (1 - 12)	Years (00 - 250)
Index	High Byte (MSB)	Low Byte (LSB)													
0	Seconds (0 - 59)	Minutes (0 - 59)													
1	Hours (0 - 23)	Days (1 - 31)													
2	Month (1 - 12)	Years (00 - 250)													
	<p>The values are in binary form.</p>														
Index:	<p>[0] = Real Time, Seconds+Minutes</p> <p>[1] = Real Time, Hours+Days</p> <p>[2] = Real Time, Month+Year</p>														
Note:	<p>See r0948 (fault time).</p>														

p2120	Indication counter / Indication counter		
	Access level: 4	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0	Max 65535	Factory setting 0
Description:	Indicates total number of fault/warning events. This parameter is incremented whenever an fault/warning event occurs. This parameter is used by the PC tools.		
r2131	CO: Last fault number code / Last fault code		
	Access level: 2	P-Group: Messages	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
r2132	CO: First warning number code / First warning code		
	Access level: 2	P-Group: Messages	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
p2150[0...2]	Hysteresis frequency f_hys / Hyst. freq. f_hys		
	Access level: 3	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 10.00 [Hz]	Factory setting 3.00 [Hz]
Description:	Defines hysteresis level applied for comparing frequency and speed to threshold.		
Dependency:	See function diagram 4100.		
p2151[0...2]	CI: Speed setpoint for messages / n-Set for msg		
	Access level: 2	P-Group: Messages	Data type: U32 / Integer32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -	Max -	Factory setting 1170[0]
Description:	Selects the source of setpoint frequency, actual frequency is compared with this frequency to detect frequency deviation (see monitoring bit r2197.7).		
p2152[0...2]	Delay time of f>fmax / Delay f>fmax		
	Access level: 2	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [ms]	Max 10000 [ms]	Factory setting 200 [ms]
Description:	Selects the delay time if actual frequency above maximum frequency.		

p2153[0...2]	Time-constant speed filter / Tconst. speed filt		
	Access level: 2	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_REG	
	Min 0 [ms]	Max 1000 [ms]	Factory setting 5 [ms]
Description:	Specifies time constant of first-order speed filter. The filtered speed is then compared to the thresholds.		
Dependency:	See function diagrams 4100 and 4120.		
p2155[0...2]	Threshold frequency f_1 / Threshold freq f_1		
	Access level: 3	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 30.00 [Hz]
Description:	Sets a threshold for comparing actual speed or frequency to threshold values f_1. This threshold controls status bits 4 and 5 in status word 2 (r0053).		
Dependency:	See function diagram 4100.		
p2156[0...2]	Delay time of threshold freq f_1 / Delay time of f_1		
	Access level: 3	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [ms]	Max 10000 [ms]	Factory setting 10 [ms]
Description:	Sets delay time prior to threshold frequency f_1 comparison (P2155).		
p2157[0...2]	Threshold frequency f_2 / Threshold freq f_2		
	Access level: 2	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 30.00 [Hz]
Description:	Threshold_2 for comparing speed or frequency to thresholds.		
Dependency:	See function diagram 4120.		
p2158[0...2]	Delay time of threshold freq f_2 / Delay time of f_2		
	Access level: 2	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [ms]	Max 10000 [ms]	Factory setting 10 [ms]
Description:	When comparing speed or frequency to threshold f_2 (P2157) this is the time delay before status bits are cleared.		

p2159[0...2]	Threshold frequency f_3 / Threshold freq f_3		
	Access level: 2	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 30.00 [Hz]
Description:	Threshold_3 for comparing speed or frequency to thresholds.		
Dependency:	See function diagram 4120.		
p2160[0...2]	Delay time of threshold freq f_3 / Delay time of f_3		
	Access level: 2	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [ms]	Max 10000 [ms]	Factory setting 10 [ms]
Description:	When comparing speed or frequency to threshold f_3 (P2159) this is the time delay before status bits are set.		
p2161[0...2]	Min. threshold for freq. setp. / Setp.min.threshold		
	Access level: 2	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 10.00 [Hz]	Factory setting 3.00 [Hz]
Description:	Minimum threshold value for comparing speed or frequency setpoint.		
Dependency:	See function diagram 4130.		
p2162[0...2]	Hysteresis freq. for overspeed / Overspd. hyst.freq		
	Access level: 2	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 25.00 [Hz]	Factory setting 3.00 [Hz]
Description:	Hysteresis speed (frequency) for overspeed detection. For vector control modes, the hysteresis acts above the max. frequency. For V/f control modes the hysteresis acts below the max. frequency.		
Dependency:	See function diagram 4110.		
p2163[0...2]	Entry freq. for perm. deviation / Entry freq. deviat		
	Access level: 2	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 20.00 [Hz]	Factory setting 3.00 [Hz]
Description:	Threshold for detecting speed deviation from setpoint.		
Dependency:	See function diagram 4110.		

p2164[0...2]	Hysteresis frequency deviation / Hyster freq deviat		
	Access level: 3	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 10.00 [Hz]	Factory setting 3.00 [Hz]
Description:	Hysteresis frequency for detecting permitted deviation (from setpoint) or frequency or speed. This frequency controls bit 8 in status word 1 (r0052).		
p2165[0...2]	Delay time permitted deviation / Delay_T perm. dev.		
	Access level: 2	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [ms]	Max 10000 [ms]	Factory setting 200 [ms]
Description:	Delay time for detecting permitted deviation of speed or frequency from setpoint.		
p2166[0...2]	Delay time ramp up completed / Delay_T rampUpCmpl		
	Access level: 2	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [ms]	Max 10000 [ms]	Factory setting 10 [ms]
Description:	Delay time for signal that indicates completion of ramp-up.		
Dependency:	See function diagram 4130.		
p2167[0...2]	Switch-off frequency f_off / SwOff freq. f_off		
	Access level: 3	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 10.00 [Hz]	Factory setting 1.00 [Hz]
Description:	Defines the threshold of the monitoring function $ f_{act} > P2167 (f_{off})$. P2167 influences following functions: <ul style="list-style-type: none"> • If the actual frequency falls below this threshold and the time delay has expired, bit 1 in status word 2 (r0053) is reset. • If a OFF1 or OFF3 was applied and bit 1 is reset the inverter will disable the pulse (OFF2). 		
Dependency:	See function diagram 4110.		
p2168[0...2]	Delay time T_off / Delay time T_off		
	Access level: 3	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [ms]	Max 10000 [ms]	Factory setting 10 [ms]
Description:	Defines time for which the inverter may operate below switch-off frequency (P2167) before switch off occurs.		
Dependency:	Active if holding brake (P1215) not parameterized.		

r2169	CO: Act. filtered frequency / Act. filt. freq		
	Access level: 2	P-Group: Messages	Data type: FloatingPoint32
	Unit: [Hz]	Calculated: -	Data set: -
Description:	Filtered speed (or frequency) for monitoring behind first-order lowpass filter.		
p2170[0...2]	Threshold current I_thresh / Threshold current		
	Access level: 3	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [%]	Max 400.0 [%]	Factory setting 100.0 [%]
Description:	Defines threshold current in [%] relative to P0305 (rated motor current) to be used in comparisons of I_act and I_Thresh. This threshold controls bit 3 in status word 3 (r0053).		
Dependency:	See function diagrams 4110 and 4130.		
p2171[0...2]	Delay time current / Delay time current		
	Access level: 3	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [ms]	Max 10000 [ms]	Factory setting 10 [ms]
Description:	Defines delay time prior to activation of current comparison.		
p2172[0...2]	Threshold DC-link voltage / Vdc threshold		
PM240	Access level: 3	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [V]	Max 2000 [V]	Factory setting 800 [V]
Description:	Defines DC link voltage to be compared to actual voltage. This voltage controls bits 7 and 8 in status word 3 (r0053).		
Dependency:	See function diagram 4115.		
p2173[0...2]	Delay time DC-link voltage / Vdc delay time		
	Access level: 3	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [ms]	Max 10000 [ms]	Factory setting 10 [ms]
Description:	Defines delay time prior to activation of threshold comparison.		
p2174[0...2]	Torque threshold M_thresh / Torque threshold		
	Access level: 2	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_ALL	
	Min 0.00 [Nm]	Max 99999.00 [Nm]	Factory setting 5.13 [Nm]
Description:	Defines torque threshold for comparing actual torque.		
Dependency:	See function diagram 4130.		

p2176[0...2]	Delay time for torque threshold / Delay time torque		
	Access level: 2	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [ms]	Max 10000 [ms]	Factory setting 10 [ms]
Description:	Delay time for comparing actual torque to threshold.		
p2177[0...2]	Delay time for motor is blocked / Delay_T MotBlocked		
	Access level: 2	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [ms]	Max 10000 [ms]	Factory setting 10 [ms]
Description:	Delay time for identification that motor is blocked.		
p2178[0...2]	Delay time for motor pulled out / Delay_T MotPullOut		
CU240E	Access level: 2	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_REG	
	Min 0 [ms]	Max 10000 [ms]	Factory setting 10 [ms]
Description:	Delay time for identification that motor is pulled out.		
p2178[0...2]	Delay time for motor pulled out / Delay_T MotPullOut		
CU240S	Access level: 2	P-Group: Messages	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: YES	Data set: DDS
CU240S DP-F	Can be changed: U, T	Calculated: CALC_MOD_REG	
CU240S PN			
CU240S PN-F			
	Min 0 [ms]	Max 10000 [ms]	Factory setting 10 [ms]
Description:	Delay time for identification that motor is pulled out.		
Note:	If the Encoder is enabled (P0400 > 0) and the Motor Holding Brake is enabled (P1215 > 0), then in order to stop encoder loss trips when the brake is applied, the delay time for motor pulled out should be > brake holding times (i.e. P2178 > P1216 and P2178 > P1217).		
p2179	Current limit for no load ident. / Cur.lim:no-load ID		
	Access level: 3	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0.0 [%]	Max 10.0 [%]	Factory setting 3.0 [%]
Description:	Threshold current for A0922 (load missing) in [%] relative to P0305 (rated motor current).		
Dependency:	See function diagram 4110.		
Notice:	If a motor setpoint cannot be entered and the current limit (P2179) is not exceeded, warning A0922 (no load applied) is issued when delay time (P2180) expires.		
Note:	It may be that the motor is not connected (load missing) or a phase could be missing.		

p2180	Delay time for load missing / Load missing delay		
	Access level: 3	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0 [ms]	Max 10000 [ms]	Factory setting 2000 [ms]
Description:	Delay time load missing		
p2181[0...2]	Belt failure detection mode / Belt fail detect		
	Access level: 2	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: T	Calculated: -	
	Min 0	Max 6	Factory setting 0
Description:	<p>Sets belt failure detection mode.</p> <p>This function allows detection of mechanical failure of the drive train, e.g. a broken drive belt. It can also detect conditions which cause an overload, such as a jam. Parameters P2182 - P2190 are set to default when this parameter is changed from 0.</p> <p>This is achieved by comparing the actual frequency/torque curve with a programmed envelope (see P2182 - P2190).</p> <p>If the curve falls outside the envelope, a warning or trip is generated.</p>		
Value:	<p>0: Belt failure detection disabled</p> <p>1: Warning: Low torque / speed</p> <p>2: Warning: High torque / speed</p> <p>3: Warning: High / low torque / speed</p> <p>4: Trip: Low torque / speed</p> <p>5: Trip: High torque / speed</p> <p>6: Trip: High / low torque / speed</p>		
p2182[0...2]	Belt threshold frequency 1 / Belt threshold f_1		
	Access level: 3	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 5.00 [Hz]
Description:	<p>Sets the lower frequency threshold f_1 for defining the area where the belt failure detection is effective. The frequency torque envelope is defined by 9 parameters - 3 are frequency parameters (P2182 - P2184), and the other 6 define the low and high torque limits (P2185 - P2190) for each frequency.</p>		
Dependency:	See function diagram 4140.		
Note:	<p>Below the the threshold in p2182 and above the threshold in p2184, belt failure detection mode is not active. In this case the values for normal operation with the torque limits given in p1521 and p1520 are valid.</p>		
p2183[0...2]	Belt threshold frequency 2 / Belt threshold f_2		
	Access level: 2	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 30.00 [Hz]
Description:	Sets the frequency threshold f_2 for defining the envelope in which the torque values are valid.		

p2184[0...2]	Belt threshold frequency 3 / Belt threshold f_3		
	Access level: 2	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [Hz]	Max 650.00 [Hz]	Factory setting 50.00 [Hz]
Description:	Sets the upper frequency threshold f_3 for defining the area where the belt failure detection is effective.		

p2185[0...2]	Upper torque threshold 1 / Upper trq. thresh1		
	Access level: 2	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_ALL	
	Min 0.0 [Nm]	Max 99999.0 [Nm]	Factory setting 99999.0 [Nm]
Description:	Upper limit threshold value 1 for comparing actual torque.		
Note:	The factory setting depends on rating data of Power Module and Motor.		

p2186[0...2]	Lower torque threshold 1 / Lower trq. thresh1		
	Access level: 2	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [Nm]	Max 99999.0 [Nm]	Factory setting 0.0 [Nm]
Description:	Lower limit threshold value 1 for comparing actual torque.		

p2187[0...2]	Upper torque threshold 2 / Upper trq. thresh2		
	Access level: 2	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_ALL	
	Min 0.0 [Nm]	Max 99999.0 [Nm]	Factory setting 99999.0 [Nm]
Description:	Upper limit threshold value 2 for comparing actual torque.		
Note:	The factory setting depends on rating data of Power Module and Motor.		

p2188[0...2]	Lower torque threshold 2 / Lower trq. thresh2		
	Access level: 2	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [Nm]	Max 99999.0 [Nm]	Factory setting 0.0 [Nm]
Description:	Lower limit threshold value 2 for comparing actual torque.		

p2189[0...2]	Upper torque threshold 3 / Upper trq. thresh3		
	Access level: 2	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: CALC_MOD_ALL	
	Min 0.0 [Nm]	Max 99999.0 [Nm]	Factory setting 99999.0 [Nm]
Description:	Upper limit threshold value 3 for comparing actual torque.		
Note:	The factory setting depends on rating data of Power Module and Motor.		

p2190[0...2]	Lower torque threshold 3 / Lower trq. thresh3		
	Access level: 2	P-Group: Messages	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.0 [Nm]	Max 99999.0 [Nm]	Factory setting 0.0 [Nm]
Description:	Lower limit threshold value 3 for comparing actual torque.		

p2192[0...2]	Time delay for belt failure / Belt fail delay_T		
	Access level: 2	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0 [s]	Max 65 [s]	Factory setting 10 [s]
Description:	P2192 defines a delay before warning/trip becomes active. It is used to eliminate events caused by transient conditions. It is used for both methods of fault detection.		

r2197.0...12	CO/BO: Monitoring word 1 / Monitor Wd1				
PM240	Access level: 2	P-Group: Messages	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Monitoring word 1 which indicates the state of monitor functions. Each bit represents one monitor function.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	f_act <= P1080 (f_min)	Yes	No	-
	01	f_act <= P2155 (f_1)	Yes	No	-
	02	f_act > P2155 (f_1)	Yes	No	-
	03	f_act >= zero	Yes	No	-
	04	f_act >= setp. (f_set)	Yes	No	-
	05	f_act <= P2167 (f_off)	Yes	No	-
	06	f_act >= P1082 (f_max)	Yes	No	-
	07	f_act == setp. (f_set)	Yes	No	-
	08	Act. current r0068 >= P2170	Yes	No	-
	09	Act. unfilt. Vdc < P2172	Yes	No	-
	10	Act. unfilt. Vdc > P2172	Yes	No	-
	11	Load missing	Yes	No	-
	12	f_act > P1082 with delay	Yes	No	-
Note:	See function diagrams 4100 and 4110.				

r2197.0...12		CO/BO: Monitoring word 1 / Monitor Wd1			
PM250	Access level: 2	P-Group: Messages	Data type: Unsigned16		
PM260	Unit: -	Calculated: -	Data set: -		
Description:	Monitoring word 1 which indicates the state of monitor functions. Each bit represents one monitor function.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	f_act <= P1080 (f_min)	Yes	No	-
	01	f_act <= P2155 (f_1)	Yes	No	-
	02	f_act > P2155 (f_1)	Yes	No	-
	03	f_act >= zero	Yes	No	-
	04	f_act >= setp. (f_set)	Yes	No	-
	05	f_act <= P2167 (f_off)	Yes	No	-
	06	f_act >= P1082 (f_max)	Yes	No	-
	07	f_act == setp. (f_set)	Yes	No	-
	08	Act. current r0068 >= P2170	Yes	No	-
	11	Load missing	Yes	No	-
	12	f_act > P1082 with delay	Yes	No	-
Note:	See function diagrams 4100 and 4110.				

r2198.0...12		CO/BO: Monitoring word 2 / Monitor Wd2			
	Access level: 2	P-Group: Messages	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Monitoring word 2 which indicates the state of monitor functions. Each bit represents one monitor function.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	f_act <= P2157 (f_2)	Yes	No	-
	01	f_act > P2157 (f_2)	Yes	No	-
	02	f_act <= P2159 (f_3)	Yes	No	-
	03	f_act > P2159 (f_3)	Yes	No	-
	04	f_set < P2161 (f_min_set)	Yes	No	-
	05	f_set > 0	Yes	No	-
	06	Motor blocked	Yes	No	-
	07	Motor pulled out	Yes	No	-
	08	l_act r0068 < P2170	Yes	No	-
	09	m_act > P2174 & setpoint reached	Yes	No	-
	10	m_act > P2174	Yes	No	-
	11	Belt failure warning	Yes	No	-
	12	Belt failure trip	Yes	No	-
Note:	See function diagrams 4120 to 4140.				

p2200[0...2]	BI: Enable PID controller / Enab. PID ctrl		
	Access level: 2	P-Group: Technology	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Allows user to enable/disable the PID controller. Setting to 1 enables the PID closed-loop controller.		
Dependency:	Setting 1 automatically disables normal ramp times set in P1120 and P1121 and the normal frequency setpoints. Following an OFF1 or OFF3 command, however, the inverter frequency will ramp down to zero using the ramp time set in P1121 (P1135 for OFF3).		
Notice:	When Standard Telegram 350 and PROFIBUS selected (P0700 = 6, P0922 = 350), parameter cannot be changed. The minimum and maximum motor frequencies (P1080 and P1082) as well as the skip frequencies (P1091 to P1094) remain active on the inverter output.		
Note:	However, enabling skip frequencies with PID control can produce instabilities. The PID setpoint source is selected using P2253. The PID setpoint and the PID feedback signal are interpreted as [%] values (not [Hz]). The output of the PID controller is displayed as [%] and then normalized into [Hz] through P2000 (reference frequency) when PID is enabled. The reverse command is not active whilst PID is active. Attention: p2200 and p2803 are locked parameter against each other. PID and FFB of the same dataset cannot be active at same time.		
p2201[0...2]	Fixed PID setpoint 1 / Fixed PID setp. 1		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	0.00 [%]
Description:	Defines Fixed PID Setpoint 1. There are 2 types of fixed frequencies: 1. Direct selection (P2216 = 1): - In this mode of operation 1 Fixed Frequency selector (P2220...P2223) selects 1 fixed frequency. - If several inputs are active together, the selected frequencies are summed. E.g.: PID-FF1 + PID-FF2 + PID-FF3 + PID-FF4. 2. Binary coded selection (P2216 = 2): - Up to 16 different fixed frequency values can be selected using this method. - The fixed frequencies are selected according to FP3310.		
Dependency:	P2200 = 1 required in user access level 2 to enable setpoint source.		
Note:	You may mix different types of frequencies; however, remember that they will be summed if selected together. P2201 = 100 % corresponds to 4000 hex.		
p2202[0...2]	Fixed PID setpoint 2 / Fixed PID setp. 2		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	10.00 [%]
Description:	Defines Fixed PID Setpoint 2		
Note:	See P2201 (Fixed PID Setpoint 1).		

p2203[0...2]	Fixed PID setpoint 3 / Fixed PID setp. 3		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 20.00 [%]
Description:	Defines Fixed PID Setpoint 3		
Note:	See P2201 fixed PID setpoint 1 (FF-PID 1).		
p2204[0...2]	Fixed PID setpoint 4 / Fixed PID setp. 4		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 30.00 [%]
Description:	Defines Fixed PID Setpoint 4		
Note:	See P2201 (Fixed PID Setpoint 1).		
p2205[0...2]	Fixed PID setpoint 5 / Fixed PID setp. 5		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 40.00 [%]
Description:	Defines Fixed PID Setpoint 5		
Note:	See P2201 (Fixed PID Setpoint 1).		
p2206[0...2]	Fixed PID setpoint 6 / Fixed PID setp. 6		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 50.00 [%]
Description:	Defines Fixed PID Setpoint 6		
Note:	See P2201 (Fixed PID Setpoint 1).		
p2207[0...2]	Fixed PID setpoint 7 / Fixed PID setp. 7		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 60.00 [%]
Description:	Defines Fixed PID Setpoint 7		
Note:	See P2201 (Fixed PID Setpoint 1).		

p2208[0...2]	Fixed PID setpoint 8 / Fixed PID setp. 8		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 70.00 [%]
Description:	Defines Fixed PID Setpoint 8		
Note:	See P2201 (Fixed PID Setpoint 1).		
p2209[0...2]	Fixed PID setpoint 9 / Fixed PID setp. 9		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 80.00 [%]
Description:	Defines Fixed PID Setpoint 9		
Note:	See P2201 (Fixed PID Setpoint 1).		
p2210[0...2]	Fixed PID setpoint 10 / Fixed PID setp. 10		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 90.00 [%]
Description:	Defines Fixed PID Setpoint 10		
Note:	See P2201 (Fixed PID Setpoint 1).		
p2211[0...2]	Fixed PID setpoint 11 / Fixed PID setp. 11		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 100.00 [%]
Description:	Defines Fixed PID Setpoint 11		
Note:	See P2201 (Fixed PID Setpoint 1).		
p2212[0...2]	Fixed PID setpoint 12 / Fixed PID setp. 12		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 110.00 [%]
Description:	Defines Fixed PID Setpoint 12		
Note:	See P2201 (Fixed PID Setpoint 1).		

p2213[0...2]	Fixed PID setpoint 13 / Fixed PID setp. 13		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 120.00 [%]
Description:	Defines Fixed PID Setpoint 13		
Note:	See P2201 (Fixed PID Setpoint 1).		
p2214[0...2]	Fixed PID setpoint 14 / Fixed PID setp. 14		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 130.00 [%]
Description:	Defines Fixed PID Setpoint 14		
Note:	See P2201 (Fixed PID Setpoint 1).		
p2215[0...2]	Fixed PID setpoint 15 / Fixed PID setp. 15		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 130.00 [%]
Description:	Defines Fixed PID Setpoint 15		
Note:	See P2201 (Fixed PID Setpoint 1).		
p2216[0...2]	Fixed PID setpoint mode / Fix.PID Mode		
	Access level: 2	P-Group: Technology	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: T	Calculated: -	
	Min 1	Max 2	Factory setting 1
Description:	Fixed frequencies for PID setpoint can be selected in two different modes. Parameter P2216 defines the mode.		
Value:	1: Direct selection 2: Binary selection		
p2220[0...2]	BI: Fixed PID setp. select Bit 0 / PID setp->Bit 0		
	Access level: 3	P-Group: Commands	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 722.3
Description:	Defines command source of fixed PID setpoint selection Bit 0.		

p2221[0...2]	BI: Fixed PID setp. select Bit 1 / PID setp->Bit 1			
	Access level: 3	P-Group: Commands	Data type: U32 / Binary	
	Quick comm. NO	Active: NO	Data set: CDS	
	Can be changed: T	Calculated: -		
	Min	Max	Factory setting	
	-	-	722.4	
Description:	Defines command source of fixed PID setpoint selection Bit 1.			
p2222[0...2]	BI: Fixed PID setp. select Bit 2 / PID setp->Bit 2			
	Access level: 3	P-Group: Commands	Data type: U32 / Binary	
	Quick comm. NO	Active: NO	Data set: CDS	
	Can be changed: T	Calculated: -		
	Min	Max	Factory setting	
	-	-	722.5	
Description:	Defines command source of fixed PID setpoint selection Bit 2.			
p2223[0...2]	BI: Fixed PID setp. select Bit 3 / PID setp->Bit 3			
CU240E	Access level: 3	P-Group: Commands	Data type: U32 / Binary	
CU240S DP-F	Quick comm. NO	Active: NO	Data set: CDS	
CU240S PN-F	Can be changed: T	Calculated: -		
	Min	Max	Factory setting	
	-	-	0	
Description:	Defines command source of fixed PID setpoint selection Bit 3.			
p2223[0...2]	BI: Fixed PID setp. select Bit 3 / PID setp->Bit 3			
CU240S	Access level: 3	P-Group: Commands	Data type: U32 / Binary	
CU240S DP	Quick comm. NO	Active: NO	Data set: CDS	
CU240S PN	Can be changed: T	Calculated: -		
	Min	Max	Factory setting	
	-	-	722.6	
Description:	Defines command source of fixed PID setpoint selection Bit 3.			
r2224	CO: Act. fixed PID setpoint / Fixed.PID setp			
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32	
	Unit: [%]	Calculated: -	Data set: -	
Description:	Displays total output of PID fixed setpoint selection.			
Note:	r2224 = 100 % corresponds to 4000 hex			
r2225.0	BO: PID Fixed frequency status / PID FF Status			
	Access level: 3	P-Group: Commands	Data type: Unsigned16	
	Unit: -	Calculated: -	Data set: -	
Description:	Displays the status of PID fixed frequencies.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Status of FF	Yes	No
				FP
				-

p2231[0...2]	PID-MOP mode / PID-MOP mode.			
	Access level: 2	P-Group: Technology	Data type: Unsigned16	
	Quick comm. NO	Active: YES	Data set: DDS	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	-	-	0	
Description:	PID-MOP mode specification			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Setpoint store activ	Yes	No
	01	No On-state for MOP necessary	Yes	No
Note:	Defines the operation mode of the motorized potentiometer. See P2240 (setpoint of PID-MOP).			
p2232	Inhibit rev. direct. of PID-MOP / Inhib. PID-MOD rev			
	Access level: 2	P-Group: Technology	Data type: Unsigned16	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: T	Calculated: -		
	Min	Max	Factory setting	
	0	1	1	
Description:	Inhibits reverse setpoint selection of the PID-MOP.			
Value:	0: Reverse direction is allowed 1: Reverse direction inhibited			
Note:	Setting 0 enables a change of motor direction using the motor potentiometer setpoint (increase/decrease frequency). The "reversing key" of the OP (e.g. BOP) is not affected by the settings of P2232. Use P1110 to fully prevent change of motor direction.			
p2235[0...2]	BI: Enable PID-MOP (UP-cmd) / PID-MOP (UP)			
	Access level: 3	P-Group: Technology	Data type: U32 / Binary	
	Quick comm. NO	Active: NO	Data set: CDS	
	Can be changed: T	Calculated: -		
	Min	Max	Factory setting	
	-	-	19.13	
Description:	Defines source of UP command.			
Dependency:	To change setpoint: - Configure a digital input as source - Use UP / DOWN key on OP (e.g. BOP).			
Notice:	If this command is enabled by short pulses of less than 1 second, the frequency is changed in steps of 0.2 % (P0310). When the signal is enabled longer than 1 second the ramp generator accelerates with the rate of P2247.			

p2236[0...2]	BI: Enable PID-MOP (DOWN-cmd) / PID-MOP (DWN)		
	Access level: 3	P-Group: Technology	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	19.14
Description:	Defines source of DOWN command.		
Dependency:	To change setpoint: - Configure a digital input as source - Use UP / DOWN key on OP (e.g. BOP).		
Notice:	If this command is enabled by short pulses of less than 1 second, the frequency is changed in steps of 0.2 % (P0310). When the signal is enabled longer than 1 second the ramp generator decelerates with the rate of P2248.		
p2240[0...2]	Setpoint of PID-MOP / Setp. of PID-MOP		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-200.00 [%]	200.00 [%]	10.00 [%]
Description:	Setpoint of the motor potentiometer. Allows user to set a digital PID setpoint in [%].		
Note:	P2240 = 100 % corresponds to 4000 hex The start value gets active (for the MOP output) only at the start of the MOP. The parameter P2231 influences the start value behaviour as follows: <ul style="list-style-type: none"> • P2231=0: P2240 gets immediately active in the OFF-state and when changed in the ON-state, it gets active after the next OFF and ON cycle. • P2231=1: The last MOP output before stop is stored as starting value, since storing is selected, so a change of P2240 while in ON-state has no effect. In OFF-state P2240 can be changed. • P2231=2: The MOP is active every time, so the change of P2240 affects after the next power cycle or a change of P2231 to 0. • P2231=3: The last MOP output before power down is stored as starting value, since the MOP is active independent from the ON-command, a change of P2240 has only effect in the case of a change of P2231. 		
p2241[0...2]	BI: PID-MOP select setpoint auto/manu / Setp. auto/manu		
	Access level: 3	P-Group: Technology	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source to change over from manual to automatic mode. If using the motorized potentiometer in the manual mode the setpoint is changed using two signals for up and down, e.g. P2235 and P2236. If using the automatic mode the setpoint must be interconnected via the connector input (P2242). 0 : manually 1 : automatically		
Notice:	Refer to: P2235, P1036, P2242		

p2242[0...2]	CI: PID-MOP auto setpoint / PMOP auto setpoint		
	Access level: 3	P-Group: Technology	Data type: U32 / Integer32
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the setpoint of the motorized potentiometer if automatic mode P2241 is selected.		
Notice:	Refer to: P2241		
p2243[0...2]	BI: PID-MOP accept rampgenerator setpoint / PMOP acc RFG setpo		
	Access level: 3	P-Group: Technology	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the setting command to accept the setting value for the motorized potentiometer. The value becomes effective for a 0/1 edge of the setting command.		
Notice:	Refer to: P2244		
p2244[0...2]	CI: PID-MOP rampgenerator setpoint / PMOP RFG setpoint		
	Access level: 3	P-Group: Technology	Data type: U32 / Integer32
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Sets the signal source for the setpoint value for the MOP. The value becomes effective for a 0/1 edge of the setting command.		
Notice:	Refer to: P2243		
r2245	CO: PID-MOP input frequency of the RFG / PMOP RFG input		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays the motorized potentiometer setpoint before it passed the PID-MOP RFG.		
p2247[0...2]	PID-MOP ramp-up time of the RFG / PMOP ramp-up time		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	0.00 [s]	1000.00 [s]	10.00 [s]
Description:	Sets the ramp-up time for the internal PID-MOP ramp-function generator. The setpoint is changed from zero up to limit defined in P1082 within this time.		
Notice:	Refer to: P2248, P1082		

p2248[0...2]	PID-MOP ramp-down time of the RFG / PMOP rampdown time		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.00 [s]	Max 1000.00 [s]	Factory setting 10.00 [s]
Description:	Sets the ramp-down time for the internal PID-MOP ramp-function generator. The setpoint is changed from limit defined in P1082 down to zero within this time.		
Notice:	Refer to: P2247, P1082		
r2250	CO: Output setpoint of PID-MOP / PMOP outp. setp		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays output setpoint of motor potentiometer in [%].		
p2251	PID mode / PID mode		
	Access level: 3	P-Group: Technology	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min 0	Max 1	Factory setting 0
Description:	Enables function of PID controller.		
Value:	0: PID as setpoint 1: PID as trim		
Dependency:	Active when PID loop is enabled (see P2200).		
p2253[0...2]	CI: PID setpoint / PID setpoint		
	Access level: 2	P-Group: Technology	Data type: U32 / Integer16
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: U, T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	Defines setpoint source for PID setpoint input. This parameter allows the user to select the source of the PID setpoint. Normally, a digital setpoint is selected either using a fixed PID setpoint or an active setpoint.		
p2254[0...2]	CI: PID trim source / PID trim source		
	Access level: 3	P-Group: Technology	Data type: U32 / Integer16
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: U, T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	Selects trim source for PID setpoint. This signal is multiplied by the trim gain and added to the PID setpoint.		

p2255	PID setpoint gain factor / PID setp.gain fact		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0.00	Max 100.00	Factory setting 100.00
Description:	Gain factor for PID setpoint. The PID setpoint input is multiplied by this gain factor to produce a suitable ratio between setpoint and trim.		
p2256	PID trim gain factor / PID trim gain fact		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0.00	Max 100.00	Factory setting 100.00
Description:	Gain factor for PID trim. This gain factor scales the trim signal, which is added to the main PID setpoint.		
p2257	Ramp-up time for PID setpoint / PID setp. ramp-up		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0.00 [s]	Max 650.00 [s]	Factory setting 1.00 [s]
Description:	Sets the ramp-up time for the PID setpoint.		
Dependency:	P2200 = 1 (PID control is enabled) disables normal ramp-up time (P1120). PID ramp time effective only on PID setpoint and only active when PID setpoint is changed or when RUN command is given (when PID setpoint uses this ramp to reach its value from 0 %).		
Notice:	Setting the ramp-up time too short may cause the inverter to trip, on overcurrent for example.		
p2258	Ramp-down time for PID setpoint / PID setp. ramp-dwn		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0.00 [s]	Max 650.00 [s]	Factory setting 1.00 [s]
Description:	Sets ramp-down time for PID setpoint.		
Dependency:	P2200 = 1 (PID control is enabled) disables normal ramp-down time (P1121). PID setpoint ramp effective only on PID setpoint changes. P1121 (ramp-down time) and P1135 (OFF3 ramp-down time) define the ramp times used after OFF1 and OFF3 respectively.		
Notice:	Setting the ramp-down time too short can cause the inverter to trip on overvoltage F0002 / overcurrent F0001.		
r2260	CO: PID setpoint after PID-RFG / PID setp <-RFG		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays total active PID setpoint after PID-RFG in [%].		
Note:	r2260 = 100 % corresponds to 4000 hex.		

p2261	PID setpoint filter timeconstant / PID setp.filt.Tcon		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0.00 [s]	Max 60.00 [s]	Factory setting 0.00 [s]
Description:	Sets a time constant for smoothing the PID setpoint.		
Note:	p2261 = 0 = no smoothing.		
r2262	CO: Filtered PID setp. after RFG / Filt. PID setp		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays filtered PID setpoint after PID-RFG in [%]. r2262 is the result of the value in r2260, filtered with PT1-Filter and the time constant given in p2261.		
Note:	r2262 = 100 % corresponds to 4000 hex.		
p2263	PID controller type / PID ctrl. type		
	Access level: 3	P-Group: Technology	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min 0	Max 1	Factory setting 0
Description:	Sets the PID controller type.		
Value:	0: D component on feedback signal 1: D component on error signal		
p2264[0...2]	CI: PID feedback / PID feedback		
	Access level: 2	P-Group: Technology	Data type: U32 / Integer16
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: U, T	Calculated: -	
	Min -	Max -	Factory setting 755[0]
Description:	Selects the source of the PID feedback signal.		
Note:	When analog input is selected, offset and gain can be implemented using parameters P0756 to P0760 (AI scaling).		
p2265	PID feedback filter timeconstant / Fdbck.filt. Tconst		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0.00 [s]	Max 60.00 [s]	Factory setting 0.00 [s]
Description:	Defines time constant for PID feedback filter.		
r2266	CO: PID filtered feedback / PID filt.fdbck		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays PID feedback signal in [%].		
Note:	r2266 = 100 % corresponds to 4000 hex.		

p2267	Max. value for PID feedback / PID fdbck max. val		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 100.00 [%]
Description:	Sets the upper limit for the value of the feedback signal in [%].		
Notice:	When PID is enabled (P2200 = 1) and the signal rises above this value, the inverter will trip with F0222 .		
Note:	p2267 = 100 % corresponds to 4000 hex.		
p2268	Min. value for PID feedback / PID fdbck min. val		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 0.00 [%]
Description:	Sets lower limit for value of feedback signal in [%].		
Notice:	When PID is enabled (P2200 = 1) and the signal drops below this value, the inverter will trip with F0221.		
Note:	P2268 = 100 % corresponds to 4000 hex.		
p2269	Gain applied to PID feedback / PID feedback gain		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0.00	Max 500.00	Factory setting 100.00
Description:	Allows the user to scale the PID feedback as a percentage value [%]. A gain of 100.0 % means that feedback signal has not changed from its default value.		
p2270	PID feedback function selector / PID fdbck fnct sel		
	Access level: 3	P-Group: Technology	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0	Max 3	Factory setting 0
Description:	Applies mathematical functions to the PID feedback signal, allowing multiplication of the result by P2269 (gain applied to PID feedback).		
Value:	0: Disabled 1: Square root (root(x)) 2: Square (x*x) 3: Cube (x*x*x)		

p2271	PID transducer type / PID trans. type	Access level: 2	P-Group: Technology	Data type: Unsigned16
		Quick comm. NO	Active: YES	Data set: -
		Can be changed: U, T	Calculated: -	
		Min 0	Max 1	Factory setting 0
Description:	Allows the user to select the transducer type for the PID feedback signal.			
Value:	0: Disabled 1: Inversion of PID feedback signal			
Notice:	It is essential that you select the correct transducer type. If you are unsure whether 0 or 1 is applicable, you can determine the correct type as follows: 1. Disable the PID function (P2200 = 0). 2. Increase the motor frequency while measuring the feedback signal. 3. If the feedback signal increases with an increase in motor frequency, the PID transducer type should be 0. 4. If the feedback signal decreases with an increase in motor frequency the PID transducer type should be set to 1.			
r2272	CO: PID scaled feedback / PID scal fdbck	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
		Unit: [%]	Calculated: -	Data set: -
Description:	Displays PID scaled feedback signal in [%].			
Note:	r2272 = 100 % corresponds to 4000 hex.			
r2273	CO: PID error / PID error	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
		Unit: [%]	Calculated: -	Data set: -
Description:	Displays PID error (difference) signal between setpoint and feedback signals in [%].			
Note:	r2273 = 100 % corresponds to 4000 hex.			
p2274	PID derivative time / PID deriv. time	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
		Quick comm. NO	Active: YES	Data set: -
		Can be changed: U, T	Calculated: -	
		Min 0.000 [s]	Max 60.000 [s]	Factory setting 0.000 [s]
Description:	Sets PID derivative time. P2274 = 0: The derivative term does not have any effect (it applies a gain of 1).			
p2280	PID proportional gain / PID prop. gain	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
		Quick comm. NO	Active: YES	Data set: -
		Can be changed: U, T	Calculated: -	
		Min 0.000	Max 65.000	Factory setting 3.000
Description:	Allows user to set proportional gain for PID controller. The PID controller is implemented using the standard model. For best results, enable both P and I terms.			
Dependency:	P2280 = 0 (P term of PID = 0): The I term acts on the square of the error signal. P2285 = 0 (I term of PID = 0): PID controller acts as a P or PD controller respectively.			
Note:	If the system is prone to sudden step changes in the feedback signal, P term should normally be set to a small value (0.5) with a faster I term for optimum performance.			

p2285	PID integral time / PID integral time		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0.000 [s]	Max 60.000 [s]	Factory setting 0.000 [s]
Description:	Sets integral time constant for PID controller.		
Note:	See P2280 (PID proportional gain).		
p2291	PID output upper limit / PID outp.upper lim		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 100.00 [%]
Description:	Sets upper limit for PID controller output in [%].		
Dependency:	If f_max (P1082) is greater than P2000 (reference frequency), either P2000 or P2291 (PID output upper limit) must be changed to achieve f_max.		
Note:	P2291 = 100 % corresponds to 4000 hex (as defined by P2000 (reference frequency)).		
p2292	PID output lower limit / PID outp.lower lim		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 0.00 [%]
Description:	Sets lower limit for the PID controller output in [%].		
Dependency:	A negative value allows bipolar operation of PID controller.		
Note:	P2292 = 100 % corresponds to 4000 hex.		
p2293	Ramp-up /-down time of PID limit / PID lim. ramp time		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0.00 [s]	Max 100.00 [s]	Factory setting 1.00 [s]
Description:	Sets maximum ramp rate on output of PID. When PI is enabled, the output limits are ramped up from 0 to the limits set in P2291 (PID output upper limit) and P2292 (PID output lower limit). Limits prevent large step changes appearing on the output of the PID when the inverter is started. Once the limits have been reached, the PID controller output is instantaneous. These ramp times are used whenever a RUN command is issued.		
Note:	If an OFF1 or OFF 3 are issued, the inverter output frequency ramps down as set in P1121 (ramp-down time) or P1135 (OFF3 ramp-down time).		
r2294	CO: Act. PID output / Act.PID output		
	Access level: 2	P-Group: Technology	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays PID output in [%].		
Note:	r2294 = 100 % corresponds to 4000 hex.		

p2295	Gain applied to PID output / PID output scale		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min -100.00	Max 100.00	Factory setting 100.00
Description:	Allows the user to scale the PID output as a percentage value [%]. A gain of 100.0 % means that output signal has not changed from its default value.		
p2350	PID autotune enable / PID autotune		
	Access level: 2	P-Group: Technology	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0	Max 4	Factory setting 0
Description:	Enables autotune function of PID controller.		
Value:	0: PID autotuning disabled 1: PID autotuning via Ziegler Nichols (ZN) standard 2: PID autotuning as 1 plus some overshoot (O/S) 3: PID autotuning as 2 little or no overshoot (O/S) 4: PID autotuning PI only, quarter damped response		
Dependency:	Active when PID loop is enabled (see P2200).		
Note:	<ul style="list-style-type: none"> • P2350 = 1 This is the standard Ziegler Nichols (ZN) tuning which should be a quarter damped response to a step. • P2350 = 2 This tuning will give some overshoot (O/S) but should be faster than option 1. • P2350 = 3 This tuning should give little or no overshoot but will not be as fast as option 2. • P2350 = 4 This tuning only changes values of P and I and should be a quarter damped response. <p>The option to be selected depends on the application but broadly speaking option 1 will give a good response, whereas if a faster response is desired option 2 should be selected.</p> <p>If no overshoot is desired then option 3 is the choice. For cases where no D term is wanted then option 4 can be selected.</p> <p>The tuning procedure is the same for all options. It is just the calculation of P and D values that is different.</p> <p>After autotune this parameter is set to zero (autotune completed).</p>		
p2354	PID tuning timeout length / PID tuning t/o.		
	Access level: 3	P-Group: Technology	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 60 [s]	Max 65000 [s]	Factory setting 240 [s]
Description:	This parameter determines the time that the autotuning code will wait before aborting a tuning run if no oscillation has been obtained.		

p2355	PID tuning offset / PID tuning offset		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0.00 [%]	Max 20.00 [%]	Factory setting 5.00 [%]
Description:	Sets applied offset and deviation for PID autotuning.		
Note:	This can be varied depending on plant conditions e.g. a very long system time constant might require a larger value.		

p2470[0...2]	Encoder speed scaling factor / Encod speed scal		
CU240S	Access level: 2	P-Group: Encoder	Data type: FloatingPoint32
CU240S DP	Quick comm. NO	Active: YES	Data set: DDS
CU240S DP-F	Can be changed: T	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min 0.00	Max 9999.99	Factory setting 1.00
Description:	Scaling factor to be applied to the measured encoder speed.		

r2477	CO: Act. scaled encoder speed / Act scal enc speed		
CU240S	Access level: 2	P-Group: Encoder	Data type: FloatingPoint32
CU240S DP	Unit: -	Calculated: -	Data set: -
CU240S DP-F			
CU240S PN			
CU240S PN-F			
Description:	Scaled readout of the encoder speed.		

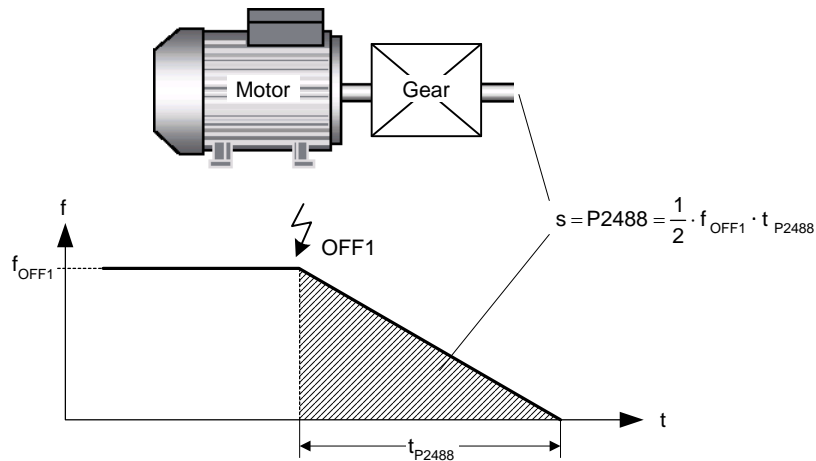
r2478	CO: Act. scaled encoder frequency / Act scal enc freq		
CU240S	Access level: 2	P-Group: Closed-loop control	Data type: FloatingPoint32
CU240S DP	Unit: [Hz]	Calculated: -	Data set: -
CU240S DP-F			
CU240S PN			
CU240S PN-F			
Description:	Scaled readout of the encoder frequency (Hz).		

p2480[0...2]	BI: Enable positioning ramp down / Enable positioning		
	Access level: 3	P-Group: Closed-loop control	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: U, T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	Defines the source signal for enabling/disabling positioning.		

p2481[0...2]	Gearbox ratio input / Gearbox ratio in		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.01	Max 9999.99	Factory setting 1.00
Description:	P2481 and P2482 define the gear box ratio for the positioning ramp down functionality. P2481 sets the motor shaft side (gear box input). $i = \text{Motor revolutions} / \text{Load revolutions} = p2481 / p2482$		
p2482[0...2]	Gearbox ratio output / Gearbox ratio out		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.01	Max 9999.99	Factory setting 1.00
Description:	P2481 and P2482 define the gear box ratio for the positioning ramp down functionality. P2482 sets the load side (gear box output).		
p2484[0...2]	No. of shaft turns = 1 Unit / Position ref. unit		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min 0.01	Max 9999.99	Factory setting 1.00
Description:	Sets the number of rotations of the motor shaft required to represent 1 unit of user selected units. $p2484 = \text{No. of revolutions} / 1 [\text{unit}]$ The following equation determines the number of motor shaft revolutions to stop: $\text{Revolutions_Motor} = p2488 * p2484 * (p2481 / p2482)$		
p2487[0...2]	Positional error trim value / Positional trim / Positional error		
	Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: DDS
	Can be changed: U, T	Calculated: -	
	Min -99.00	Max 200.00	Factory setting 0.00
Description:	This parameter can be used to optimise the positioning ramp down. When Encoder is DISABLED: <ul style="list-style-type: none"> • Offset errors due to mechanical errors or other reasons can so be corrected. The value is in measures of P2488. • Negative value entered when final position is before required end point. • Positive value entered when final position is after the required end point. When Encoder is ENABLED: <ul style="list-style-type: none"> • The profile of the deceleration curve can be altered. • Negative value entered will result in a sharper deceleration (Concave). • Positive value entered will result in a shallower deceleration (Convex). 		

p2488[0...2]	Distance / No. of revolutions / Distance / No. rev		
Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32	
Quick comm. NO	Active: NO	Data set: DDS	
Can be changed: U, T	Calculated: -		
Min 0.01	Max 99999999.99	Factory setting 1.00	

Description: Sets the required distance or number of revolutions (see P2484).



r2489[0...2]	CO: Tracking parameter / Track / Tracking parameter		
Access level: 3	P-Group: Closed-loop control	Data type: FloatingPoint32	
Unit: -	Calculated: -	Data set: -	

Description: This parameter displays tracking values of the positioning ramp down functionality.

Index:
 [0] = Remaining number of shaft rotations since trigger.
 [1] = Accumulated shaft rotations during the positioning ramp down.
 [2] = Accumulated encoder increments during the positioning ramp down

Note:
 Index [0]:
 The displayed value is in measures of P2488. Due to the open loop control mode of the positioning ramp down, the value may show a residual difference between calculated and actually performed motor rotations. P2487 can be used for trimming.
 Index [1]:
 The displayed value is in measures of P2488. The value is available only with P400 > 0.
 Index [2]:
 The value is available only if an encoder is connected. The raw encoder counter value is shown in r0485.

p2800	Enable FFBs / Enable FFBs		
Access level: 3	P-Group: Technology	Data type: Unsigned16	
Quick comm. NO	Active: NO	Data set: -	
Can be changed: U, T	Calculated: -		
Min 0	Max 1	Factory setting 0	

Description: Free function blocks (FFB) are enabled in two steps:
 1. Parameter P2800 enables all free function blocks (P2800 = 1).
 2. Parameters P2801 and P2802 respectively, enable each free function block individually. Additionally fast free function blocks can be enabled via P2803 = 1.

Value:
 0: Disable
 1: Enable

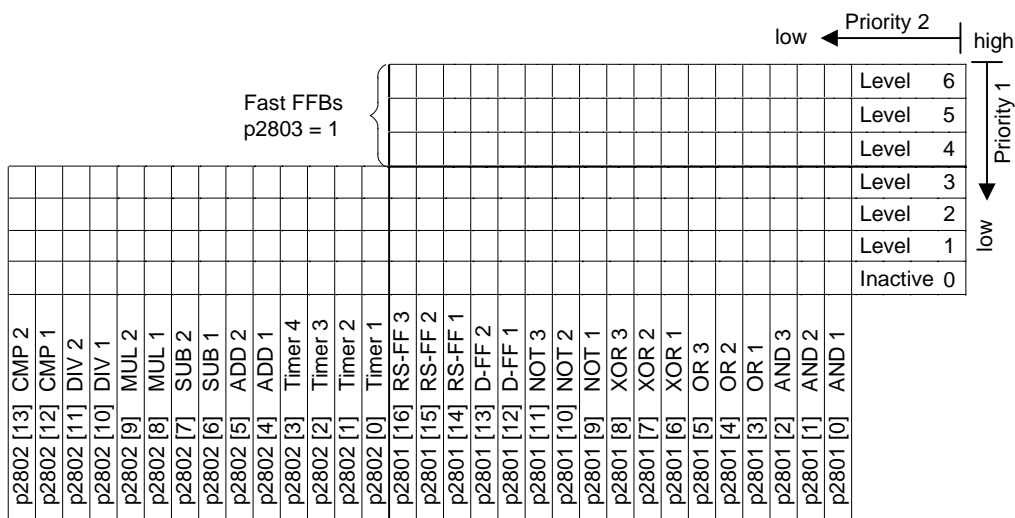
Dependency: All active function blocks will be calculated in every 128 ms, fast free function blocks in every 8 ms.

p2801[0...16] Activate FFBs / Activate FFBs

Access level: 3	P-Group: Technology	Data type: Unsigned16
Quick comm.: NO	Active: NO	Data set: -
Can be changed: U, T	Calculated: -	
Min	Max	Factory setting
0	6	0

Description: Parameters P2801 and P2802 respectively, enable each free function block individually (P2801[x] > 0 or P2802[x] > 0). In addition, parameters P2801 and P2802 determine the chronological order of each function block by setting the level in which the free function block will work.

The following table shows that the priority decreases from right to left and from top to bottom.



Value:
 0: Not Active
 1: Level 1
 2: Level 2
 3: Level 3
 4: Level 4
 5: Level 5
 6: Level 6

Example: P2801[3] = 2, P2801[4] = 2, P2802[3] = 3, P2802[4] = 2
 FFbs will be calculated in following order:
 P2802[3], P2801[3], P2801[4], P2802[4]

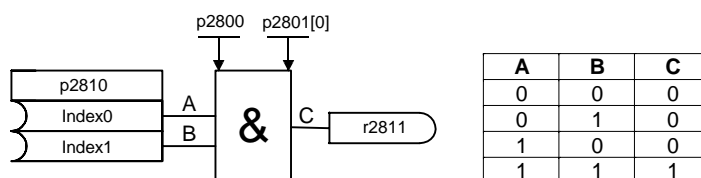
Index:
 [0] = Enable AND 1
 [1] = Enable AND 2
 [2] = Enable AND 3
 [3] = Enable OR 1
 [4] = Enable OR 2
 [5] = Enable OR 3
 [6] = Enable XOR 1
 [7] = Enable XOR 2
 [8] = Enable XOR 3
 [9] = Enable NOT 1
 [10] = Enable NOT 2
 [11] = Enable NOT 3
 [12] = Enable D-FF 1
 [13] = Enable D-FF 2
 [14] = Enable RS-FF 1
 [15] = Enable RS-FF 2
 [16] = Enable RS-FF 3

Dependency: Set P2800 to 1 to enable function blocks.

All active function blocks will be calculated in every 128 ms, if set to level 1 ... 3. Fast free function blocks (level 4 ... 6) will be calculated in every 8 ms.

p2802[0...13] Activate FFBS / Activate FFBS			
	Access level: 3	P-Group: Technology	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0	Max 3	Factory setting 0
Description:	Enables free function blocks (FFB) and determines the chronological order of each function block. See parameter P2801.		
Value:	0: Not Active 1: Level 1 2: Level 2 3: Level 3		
Index:	[0] = Enable timer 1 [1] = Enable timer 2 [2] = Enable timer 3 [3] = Enable timer 4 [4] = Enable ADD 1 [5] = Enable ADD 2 [6] = Enable SUB 1 [7] = Enable SUB 2 [8] = Enable MUL 1 [9] = Enable MUL 2 [10] = Enable DIV 1 [11] = Enable DIV 2 [12] = Enable CMP 1 [13] = Enable CMP 2		
Dependency:	Set P2800 to 1 to enable function blocks. All active function blocks, enabled with P2802, will be calculated in every 128 ms.		
p2803[0...2] Enable FastFFBs / Enable FastFFBs			
	Access level: 3	P-Group: Technology	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: CDS
	Can be changed: U, T	Calculated: -	
	Min 0	Max 1	Factory setting 0
Description:	Fast free function blocks (FFB) are enabled in two steps: 1. Parameter P2803 enables the use of fast free function blocks (P2803 = 1). 2. Parameter P2801 enables each fast free function block individually and determines the chronological order (P2801[x] = 4 ... 6).		
Value:	0: Disable 1: Enable		
Dependency:	All active fast function blocks will be calculated in every 8 ms.		
Note:	Attention: P2200 and P2803 are locked parameter against each other. PID and FFB of the same dataset cannot be active at same time.		

p2810[0...1]	BI: AND 1 / AND 1	Access level: 3	P-Group: Technology	Data type: U32 / Binary
		Quick comm. NO	Active: NO	Data set: -
		Can be changed: U, T	Calculated: -	
		Min -	Max -	Factory setting 0
Description:	P2810[0], P2810[1] define inputs of AND 1 element, output is P2811.			



Index:	[0] = Binector input 0 (BI 0) [1] = Binector input 1 (BI 1)
Dependency:	P2801[0] assigns the AND element to the processing sequence.

r2811.0	BO: AND 1 / AND 1	Access level: 3	P-Group: Technology	Data type: Unsigned16	
		Unit: -	Calculated: -	Data set: -	
Description:	Output of AND 1 element. Displays and logic of bits defined in P2810[0], P2810[1].				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Output of BO	Yes	No	-
Dependency:	P2801[0] assigns the AND element to the processing sequence.				

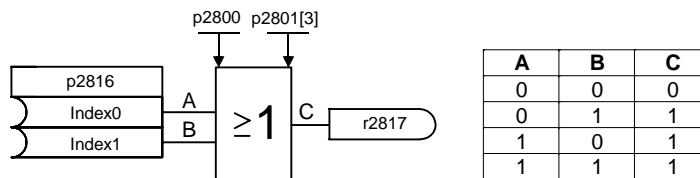
p2812[0...1]	BI: AND 2 / AND 2	Access level: 3	P-Group: Technology	Data type: U32 / Binary
		Quick comm. NO	Active: NO	Data set: -
		Can be changed: U, T	Calculated: -	
		Min -	Max -	Factory setting 0
Description:	P2812[0], 2812[1] define inputs of AND 2 element, output is P2813.			
Index:	[0] = Binector input 0 (BI 0) [1] = Binector input 1 (BI 1)			
Dependency:	P2801[1] assigns the AND element to the processing sequence.			

r2813.0	BO: AND 2 / AND 2	Access level: 3	P-Group: Technology	Data type: Unsigned16	
		Unit: -	Calculated: -	Data set: -	
Description:	Output of AND 2 element. Displays and logic of bits defined in P2812[0], P2812[1].				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Output of BO	Yes	No	-
Dependency:	P2801[1] assigns the AND element to the processing sequence.				

p2814[0...1]	BI: AND 3 / AND 3		
Access level: 3	P-Group: Technology	Data type: U32 / Binary	
Quick comm. NO	Active: NO	Data set: -	
Can be changed: U, T	Calculated: -		
Min	Max	Factory setting	
-	-	0	
Description:	P2814[0], P2814[1] define inputs of AND 3 element, output is P2815.		
Index:	[0] = Binector input 0 (BI 0) [1] = Binector input 1 (BI 1)		
Dependency:	P2801[2] assigns the AND element to the processing sequence.		

r2815.0	BO: AND 3 / AND 3			
Access level: 3	P-Group: Technology	Data type: Unsigned16		
Unit: -	Calculated: -	Data set: -		
Description:	Output of AND 3 element. Displays and logic of bits defined in P2814[0], P2814[1].			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Output of BO	Yes	No
Dependency:	P2801[2] assigns the AND element to the processing sequence.			

p2816[0...1]	BI: OR 1 / OR 1		
Access level: 3	P-Group: Technology	Data type: U32 / Binary	
Quick comm. NO	Active: NO	Data set: -	
Can be changed: U, T	Calculated: -		
Min	Max	Factory setting	
-	-	0	
Description:	P2816[0], P2816[1] define inputs of OR 1 element, output is P2817.		



Index:	[0] = Binector input 0 (BI 0) [1] = Binector input 1 (BI 1)
Dependency:	P2801[3] assigns the OR element to the processing sequence.

r2817.0	BO: OR 1 / OR 1		
Access level: 3	P-Group: Technology	Data type: Unsigned16	
Unit: -	Calculated: -	Data set: -	
Description:	Output of OR 1 element. Displays or logic of bits defined in P2816[0], P2816[1].		
Bit field:	Bit	Signal name	1 signal
	00	Output of BO	Yes
Dependency:	P2801[3] assigns the OR element to the processing sequence.		

p2818[0...1]	BI: OR 2 / OR 2			
	Access level: 3	P-Group: Technology	Data type: U32 / Binary	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	-	-	0	
Description:	P2818[0], P2818[1] define inputs of OR 2 element, output is P2819.			
Index:	[0] = Binector input 0 (BI 0) [1] = Binector input 1 (BI 1)			
Dependency:	P2801[4] assigns the OR element to the processing sequence.			
r2819.0	BO: OR 2 / OR 2			
	Access level: 3	P-Group: Technology	Data type: Unsigned16	
	Unit: -	Calculated: -	Data set: -	
Description:	Output of OR 2 element. Displays or logic of bits defined in P2818[0], P2818[1].			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Output of BO	Yes	No
				FP
				-
Dependency:	P2801[4] assigns the OR element to the processing sequence.			
p2820[0...1]	BI: OR 3 / OR 3			
	Access level: 3	P-Group: Technology	Data type: U32 / Binary	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	-	-	0	
Description:	P2820[0], P2820[1] define inputs of OR 3 element, output is P2821.			
Index:	[0] = Binector input 0 (BI 0) [1] = Binector input 1 (BI 1)			
Dependency:	P2801[5] assigns the OR element to the processing sequence.			
r2821.0	BO: OR 3 / OR 3			
	Access level: 3	P-Group: Technology	Data type: Unsigned16	
	Unit: -	Calculated: -	Data set: -	
Description:	Output of OR 3 element. Displays or logic of bits defined in P2820[0], P2820[1].			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Output of BO	Yes	No
				FP
				-
Dependency:	P2801[5] assigns the OR element to the processing sequence.			

p2822[0...1] **BI: XOR 1 / XOR 1**

Access level: 3 **P-Group:** Technology **Data type:** U32 / Binary

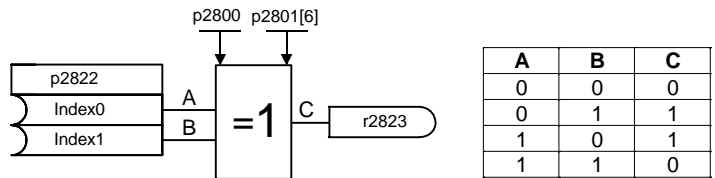
Quick comm. NO **Active:** NO **Data set:** -

Can be changed: U, T **Calculated:** -

Min **Max** **Factory setting**

- - 0

Description: P2822[0], P2822[1] define inputs of XOR 1 element, output is P2823.



Index: [0] = Binector input 0 (BI 0)
[1] = Binector input 1 (BI 1)

Dependency: P2801[6] assigns the XOR element to the processing sequence.

r2823.0 **BO: XOR 1 / XOR 1**

Access level: 3 **P-Group:** Technology **Data type:** Unsigned16

Unit: - **Calculated:** - **Data set:** -

Description: Output of XOR 1 element.
Displays exclusive-or logic of bits defined in P2822[0], P2822[1].

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Output of BO	Yes	No	-

Dependency: P2801[6] assigns the XOR element to the processing sequence.

p2824[0...1] **BI: XOR 2 / XOR 2**

Access level: 3 **P-Group:** Technology **Data type:** U32 / Binary

Quick comm. NO **Active:** NO **Data set:** -

Can be changed: U, T **Calculated:** -

Min **Max** **Factory setting**

- - 0

Description: P2824[0], P2824[1] define inputs of XOR 2 element, output is P2825.

Index: [0] = Binector input 0 (BI 0)
[1] = Binector input 1 (BI 1)

Dependency: P2801[7] assigns the XOR element to the processing sequence.

r2825.0 **BO: XOR 2 / XOR 2**

Access level: 3 **P-Group:** Technology **Data type:** Unsigned16

Unit: - **Calculated:** - **Data set:** -

Description: Output of XOR 2 element.
Displays exclusive-or logic of bits defined in P2824[0], P2824[1].

Bit field:

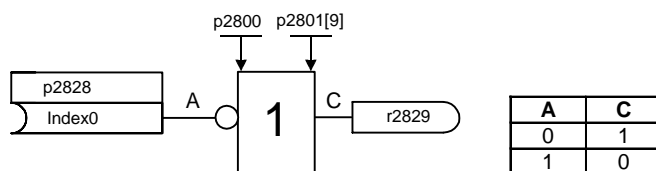
Bit	Signal name	1 signal	0 signal	FP
00	Output of BO	Yes	No	-

Dependency: P2801[7] assigns the XOR element to the processing sequence.

p2826[0...1]	BI: XOR 3 / XOR 3		
	Access level: 3	P-Group: Technology	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	P2826[0], P2826[1] define inputs of XOR 3 element, output is P2827.		
Index:	[0] = Binector input 0 (BI 0) [1] = Binector input 1 (BI 1)		
Dependency:	P2801[8] assigns the XOR element to the processing sequence.		

r2827.0	BO: XOR 3 / XOR 3		
	Access level: 3	P-Group: Technology	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Output of XOR 3 element. Displays exclusive-or logic of bits defined in P2826[0], P2826[1].		
Bit field:	Bit	Signal name	1 signal
	00	Output of BO	Yes
			0 signal
			No
			FP
			-
Dependency:	P2801[8] assigns the XOR element to the processing sequence.		

p2828	BI: NOT 1 / NOT 1		
	Access level: 3	P-Group: Technology	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	P2828 defines input of NOT 1 element, output is P2829.		



Dependency: P2801[9] assigns the NOT element to the processing sequence.

r2829.0	BO: NOT 1 / NOT 1		
	Access level: 3	P-Group: Technology	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Output of NOT 1 element. Displays not logic of bit defined in P2828.		
Bit field:	Bit	Signal name	1 signal
	00	Output of BO	Yes
			0 signal
			No
			FP
			-
Dependency:	P2801[9] assigns the NOT element to the processing sequence.		

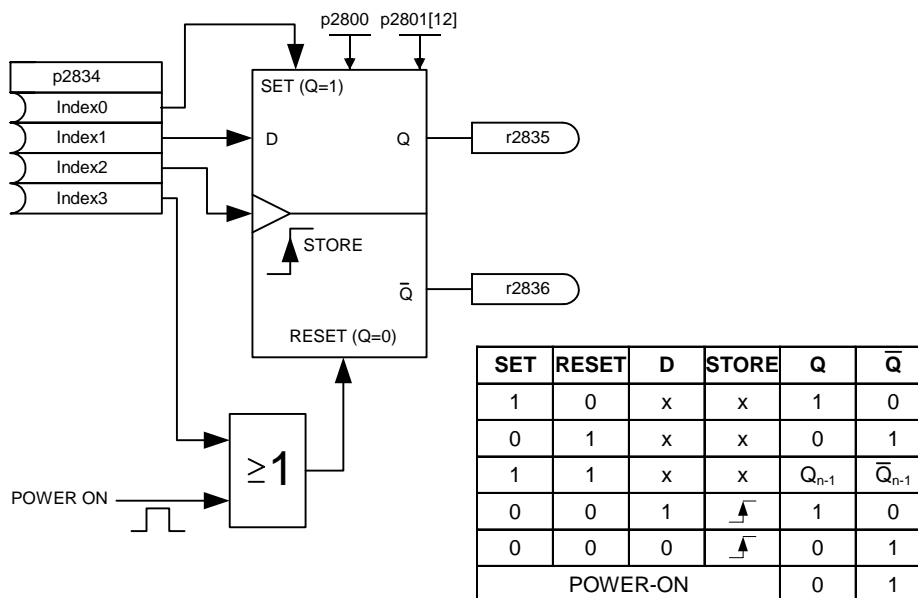
p2830	BI: NOT 2 / NOT 2			
	Access level: 3	P-Group: Technology	Data type: U32 / Binary	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	-	-	0	
Description:	P2830 defines input of NOT 2 element, output is P2831.			
Dependency:	P2801[10] assigns the NOT element to the processing sequence.			
r2831.0	BO: NOT 2 / NOT 2			
	Access level: 3	P-Group: Technology	Data type: Unsigned16	
	Unit: -	Calculated: -	Data set: -	
Description:	Output of NOT 2 element. Displays not logic of bit defined in P2830.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Output of BO	Yes	No
Dependency:	P2801[10] assigns the NOT element to the processing sequence.			
p2832	BI: NOT 3 / NOT 3			
	Access level: 3	P-Group: Technology	Data type: U32 / Binary	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	-	-	0	
Description:	P2832 defines input of NOT 3 element, output is P2833.			
Dependency:	P2801[11] assigns the NOT element to the processing sequence.			
r2833.0	BO: NOT 3 / NOT 3			
	Access level: 3	P-Group: Technology	Data type: Unsigned16	
	Unit: -	Calculated: -	Data set: -	
Description:	Output of NOT 3 element. Displays not logic of bit defined in P2832.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Output of BO	Yes	No
Dependency:	P2801[11] assigns the NOT element to the processing sequence.			

p2834[0...3]

BI: D-FF 1 / D-FF 1

Access level: 3 **P-Group:** Technology **Data type:** U32 / Binary
Quick comm. NO **Active:** NO **Data set:** -
Can be changed: U, T **Calculated:** -
Min **Max** **Factory setting**
 - - 0

Description: P2834[0], P2834[1], P2834[2], P2834[3] define inputs of D-FlipFlop 1, outputs are P2835, P2836.



Index: [0] = Binector input: Set
 [1] = Binector input: D input
 [2] = Binector input: Store pulse
 [3] = Binector input: Reset

Dependency: P2801[12] assigns the D-FlipFlop to the processing sequence.

r2835.0

BO: Q D-FF 1 / Q D-FF 1

Access level: 3 **P-Group:** Technology **Data type:** Unsigned16
Unit: - **Calculated:** - **Data set:** -

Description: Displays output of D-FlipFlop 1, inputs are defined in P2834[0], P2834[1], P2834[2], P2834[3]

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Output of BO	Yes	No	-

Dependency: P2801[12] assigns the D-FlipFlop to the processing sequence.

r2836.0

BO: NOT-Q D-FF 1 / NOT-Q D-FF 1

Access level: 3 **P-Group:** Technology **Data type:** Unsigned16
Unit: - **Calculated:** - **Data set:** -

Description: Displays Not-output of D-FlipFlop 1, inputs are defined in P2834[0], P2834[1], P2834[2], P2834[3]

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Output of BO	Yes	No	-

Dependency: P2801[12] assigns the D-FlipFlop to the processing sequence.

p2837[0...3] **BI: D-FF 2 / D-FF 2**

Access level: 3 **P-Group:** Technology **Data type:** U32 / Binary
Quick comm. NO **Active:** NO **Data set:** -
Can be changed: U, T **Calculated:** -

Min **Max** **Factory setting**
 - - 0

Description: P2837[0], P2837[1], P2837[2], P2837[3] define inputs of D-FlipFlop 2, outputs are P2838, 2839.
Index: [0] = Binector input: Set
 [1] = Binector input: D input
 [2] = Binector input: Store pulse
 [3] = Binector input: Reset
Dependency: P2801[13] assigns the D-FlipFlop to the processing sequence.

r2838.0 **BO: Q D-FF 2 / Q D-FF 2**

Access level: 3 **P-Group:** Technology **Data type:** Unsigned16
Unit: - **Calculated:** - **Data set:** -

Description: Displays output of D-FlipFlop 2, inputs are defined in P2837[0], P2837[1], P2837[2], P2837[3]
Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Output of BO	Yes	No	-

Dependency: P2801[13] assigns the D-FlipFlop to the processing sequence.

r2839.0 **BO: NOT-Q D-FF 2 / NOT-Q D-FF 2**

Access level: 3 **P-Group:** Technology **Data type:** Unsigned16
Unit: - **Calculated:** - **Data set:** -

Description: Displays Not-output of D-FlipFlop 2, inputs are defined in P2837[0], P2837[1], P2837[2], P2837[3]
Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Output of BO	Yes	No	-

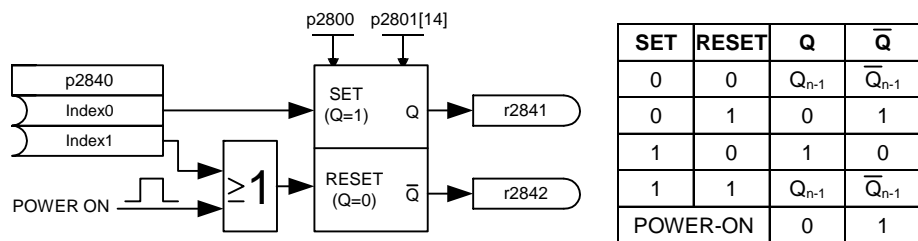
Dependency: P2801[13] assigns the D-FlipFlop to the processing sequence.

p2840[0...1] **BI: RS-FF 1 / RS-FF 1**

Access level: 3 **P-Group:** Technology **Data type:** U32 / Binary
Quick comm. NO **Active:** NO **Data set:** -
Can be changed: U, T **Calculated:** -

Min **Max** **Factory setting**
 - - 0

Description: P2840[0], P2840[1] define inputs of RS-FlipFlop 1, outputs are P2841, P2842.



Index: [0] = Binector input: Set
 [1] = Binector input: Reset
Dependency: P2801[14] assigns the RS-FlipFlop to the processing sequence.

r2841.0	BO: Q RS-FF 1 / Q RS-FF 1			
	Access level: 3	P-Group: Technology	Data type: Unsigned16	
	Unit: -	Calculated: -	Data set: -	
Description:	Displays output of RS-FlipFlop 1, inputs are defined in P2840[0], P2840[1]			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Output of BO	Yes	No
Dependency:	P2801[14] assigns the RS-FlipFlop to the processing sequence.			
r2842.0	BO: NOT-Q RS-FF 1 / NOT-Q RS-FF 1			
	Access level: 3	P-Group: Technology	Data type: Unsigned16	
	Unit: -	Calculated: -	Data set: -	
Description:	Displays Not-output of RS-FlipFlop 1, inputs are defined in P2840[0], P2840[1]			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Output of BO	Yes	No
Dependency:	P2801[14] assigns the RS-FlipFlop to the processing sequence.			
p2843[0...1]	BI: RS-FF 2 / RS-FF 2			
	Access level: 3	P-Group: Technology	Data type: U32 / Binary	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	-	-	0	
Description:	P2843[0], P2843[1] define inputs of RS-FlipFlop 2, outputs are P2844, P2845.			
Index:	[0] = Binector input: Set [1] = Binector input: Reset			
Dependency:	P2801[15] assigns the RS-FlipFlop to the processing sequence.			
r2844.0	BO: Q RS-FF 2 / Q RS-FF 2			
	Access level: 3	P-Group: Technology	Data type: Unsigned16	
	Unit: -	Calculated: -	Data set: -	
Description:	Displays output of RS-FlipFlop 2, inputs are defined in P2843[0], P2843[1]			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Output of BO	Yes	No
Dependency:	P2801[15] assigns the RS-FlipFlop to the processing sequence.			
r2845.0	BO: NOT-Q RS-FF 2 / NOT-Q RS-FF 2			
	Access level: 3	P-Group: Technology	Data type: Unsigned16	
	Unit: -	Calculated: -	Data set: -	
Description:	Displays Not-output of RS-FlipFlop 2, inputs are defined in P2843[0], P2843[1]			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Output of BO	Yes	No
Dependency:	P2801[15] assigns the RS-FlipFlop to the processing sequence.			

p2846[0...1]	BI: RS-FF 3 / RS-FF 3			
	Access level: 3	P-Group: Technology	Data type: U32 / Binary	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	-	-	0	
Description:	P2846[0], P2846[1] define inputs of RS-FlipFlop 3, outputs are P2847, P2848.			
Index:	[0] = Binector input: Set [1] = Binector input: Reset			
Dependency:	P2801[16] assigns the RS-FlipFlop to the processing sequence.			
r2847.0	BO: Q RS-FF 3 / Q RS-FF 3			
	Access level: 3	P-Group: Technology	Data type: Unsigned16	
	Unit: -	Calculated: -	Data set: -	
Description:	Displays output of RS-FlipFlop 3, inputs are defined in P2846[0], P2846[1]			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Output of BO	Yes	No
Dependency:	P2801[16] assigns the RS-FlipFlop to the processing sequence.			
r2848.0	BO: NOT-Q RS-FF 3 / NOT-Q RS-FF 3			
	Access level: 3	P-Group: Technology	Data type: Unsigned16	
	Unit: -	Calculated: -	Data set: -	
Description:	Displays Not-output of RS-FlipFlop 3, inputs are defined in P2846[0], P2846[1]			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Output of BO	Yes	No
Dependency:	P2801[16] assigns the RS-FlipFlop to the processing sequence.			

p2849**BI: Timer 1 / Timer 1**

Access level: 3

P-Group: Technology

Data type: U32 / Binary

Quick comm. NO

Active: NO

Data set: -

Can be changed: U, T

Calculated: -

Min

Max

Factory setting

-

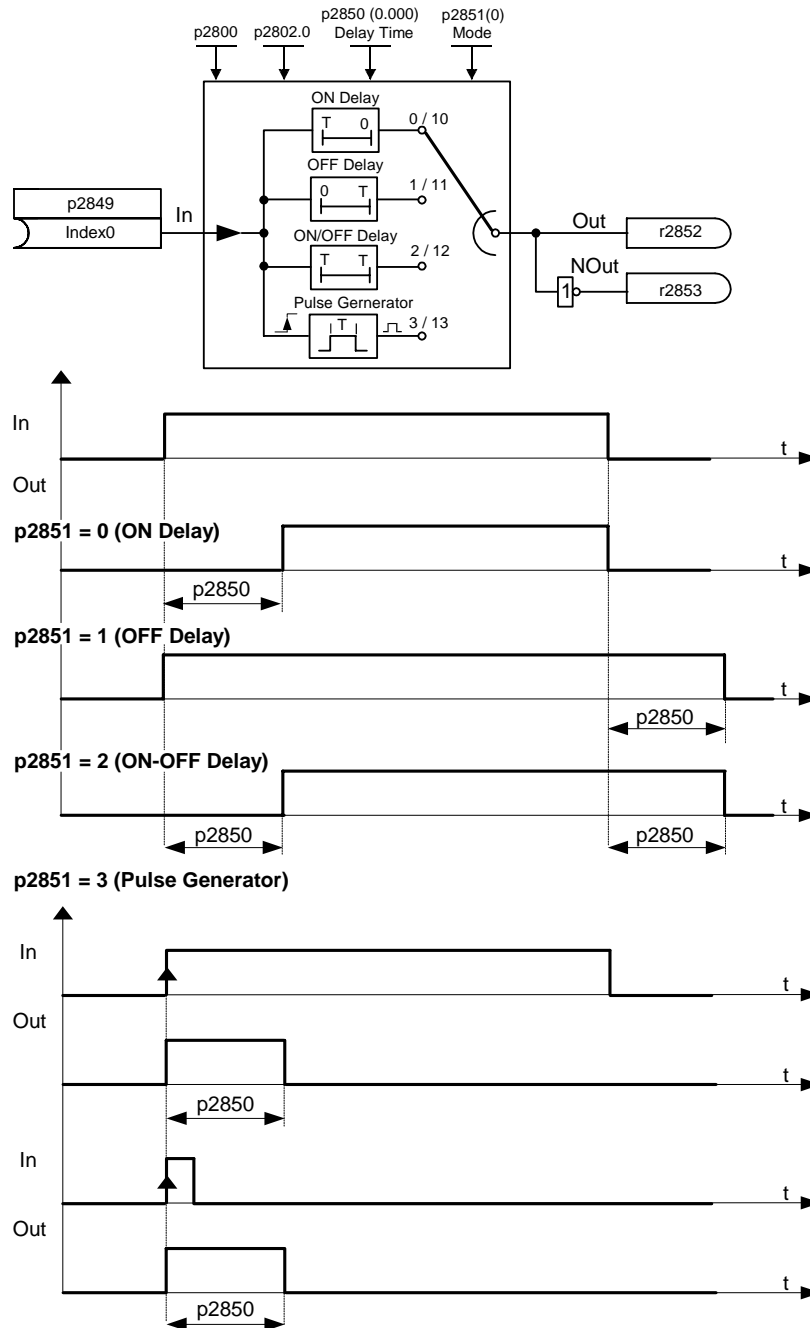
-

0

Description:

Define input signal of timer 1.

P2849, P2850, P2851 are the inputs of the timer, outputs are P2852, P2853.

**Dependency:**

P2802[0] assigns the timer to the processing sequence.

p2850	Delay time of timer 1 / Delay time timer 1				
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32		
	Quick comm. NO	Active: NO	Data set: -		
	Can be changed: U, T	Calculated: -			
	Min 0.0 [s]	Max 9999.9 [s]	Factory setting 0.0 [s]		
Description:	Defines delay time of timer 1. P2849, P2850, P2851 are the inputs of the timer, outputs are P2852, P2853.				
Dependency:	P2802[0] assigns the timer to the processing sequence.				
p2851	Mode timer 1 / Mode timer 1				
	Access level: 3	P-Group: Technology	Data type: Unsigned16		
	Quick comm. NO	Active: NO	Data set: -		
	Can be changed: U, T	Calculated: -			
	Min 0	Max 13	Factory setting 0		
Description:	Selects mode of timer 1. P2849, P2850, P2851 are the inputs of the timer, outputs are P2852, P2853.				
Value:	0: ON delay (seconds) 1: OFF delay (seconds) 2: ON/OFF delay (seconds) 3: Pulse generator (seconds) 10: ON delay (minutes) 11: OFF delay (minutes) 12: ON/OFF delay (minutes) 13: Pulse generator (minutes)				
Dependency:	P2802[0] assigns the timer to the processing sequence.				
r2852.0	BO: Timer 1 / Timer 1				
	Access level: 3	P-Group: Technology	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays output of timer 1. P2849, P2850, P2851 are the inputs of the timer, outputs are P2852, P2853.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Output of BO	Yes	No	-
Dependency:	P2802[0] assigns the timer to the processing sequence.				
r2853.0	BO: Nout timer 1 / Nout timer 1				
	Access level: 3	P-Group: Technology	Data type: Unsigned16		
	Unit: -	Calculated: -	Data set: -		
Description:	Displays Not-output of timer 1. P2849, P2850, P2851 are the inputs of the timer, outputs are P2852, P2853.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Output of BO	Yes	No	-
Dependency:	P2802[0] assigns the timer to the processing sequence.				

p2854	BI: Timer 2 / Timer 2		
	Access level: 3	P-Group: Technology	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Define input signal of timer 2. P2854, P2855, P2856 are the inputs of the timer, outputs are P2857, P2858.		
Dependency:	P2802[1] assigns the timer to the processing sequence.		
p2855	Delay time of timer 2 / Delay time timer 2		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	0.0 [s]	9999.9 [s]	0.0 [s]
Description:	Defines delay time of timer 2. P2854, P2855, P2856 are the inputs of the timer, outputs are P2857, P2858.		
Dependency:	P2802[1] assigns the timer to the processing sequence.		
p2856	Mode timer 2 / Mode timer 2		
	Access level: 3	P-Group: Technology	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	0	13	0
Description:	Selects mode of timer 2. P2854, P2855, P2856 are the inputs of the timer, outputs are P2857, P2858.		
Value:	0: ON delay (seconds) 1: OFF delay (seconds) 2: ON/OFF delay (seconds) 3: Pulse generator (seconds) 10: ON delay (minutes) 11: OFF delay (minutes) 12: ON/OFF delay (minutes) 13: Pulse generator (minutes)		
Dependency:	P2802[1] assigns the timer to the processing sequence.		
r2857.0	BO: Timer 2 / Timer 2		
	Access level: 3	P-Group: Technology	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays output of timer 2. P2854, P2855, P2856 are the inputs of the timer, outputs are P2857, P2858.		
Bit field:	Bit	Signal name	1 signal 0 signal FP
	00	Output of BO	Yes No -
Dependency:	P2802[1] assigns the timer to the processing sequence.		

r2858.0	BO: Nout timer 2 / Nout timer 2			
	Access level: 3	P-Group: Technology	Data type: Unsigned16	
	Unit: -	Calculated: -	Data set: -	
Description:	Displays Not-output of timer 2 P2854, P2855, P2856 are the inputs of the timer, outputs are P2857, P2858.			
Bit field:	Bit	Signal name	1 signal	0 signal
	00	Output of BO	Yes	No
				FP
				-
Dependency:	P2802[1] assigns the timer to the processing sequence.			
p2859	BI: Timer 3 / Timer 3			
	Access level: 3	P-Group: Technology	Data type: U32 / Binary	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	-	-	0	
Description:	Define input signal of timer 3. P2859, P2860, P2861 are the inputs of the timer, outputs are P2862, P2863.			
Dependency:	P2802[2] assigns the timer to the processing sequence.			
p2860	Delay time of timer 3 / Delay time timer 3			
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	0.0 [s]	9999.9 [s]	0.0 [s]	
Description:	Defines delay time of timer 3. P2859, P2860, P2861 are the inputs of the timer, outputs are P2862, P2863.			
Dependency:	P2802[2] assigns the timer to the processing sequence.			
p2861	Mode timer 3 / Mode timer 3			
	Access level: 3	P-Group: Technology	Data type: Unsigned16	
	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: U, T	Calculated: -		
	Min	Max	Factory setting	
	0	13	0	
Description:	Selects mode of timer 3. P2859, P2860, P2861 are the inputs of the timer, outputs are P2862, P2863.			
Value:	0: ON delay (seconds) 1: OFF delay (seconds) 2: ON/OFF delay (seconds) 3: Pulse generator (seconds) 10: ON delay (minutes) 11: OFF delay (minutes) 12: ON/OFF delay (minutes) 13: Pulse generator (minutes)			
Dependency:	P2802[2] assigns the timer to the processing sequence.			

r2862.0	BO: Timer 3 / Timer 3		
	Access level: 3	P-Group: Technology	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays output of timer 3. P2859, P2860, P2861 are the inputs of the timer, outputs are P2862, P2863.		
Bit field:	Bit	Signal name	1 signal 0 signal FP
	00	Output of BO	Yes No -
Dependency:	P2802[2] assigns the timer to the processing sequence.		
r2863.0	BO: Nout timer 3 / Nout timer 3		
	Access level: 3	P-Group: Technology	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays Not-output of timer 3. P2859, P2860, P2861 are the inputs of the timer, outputs are P2862, P2863.		
Bit field:	Bit	Signal name	1 signal 0 signal FP
	00	Output of BO	Yes No -
Dependency:	P2802[2] assigns the timer to the processing sequence.		
p2864	BI: Timer 4 / Timer 4		
	Access level: 3	P-Group: Technology	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	0
Description:	Define input signal of timer 4. P2864, P2865, P2866 are the inputs of the timer, outputs are P2867, P2868.		
Dependency:	P2802[3] assigns the timer to the processing sequence.		
p2865	Delay time of timer 4 / Delay time timer 4		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	0.0 [s]	9999.9 [s]	0.0 [s]
Description:	Defines delay time of timer 4. P2864, P2865, P2866 are the inputs of the timer, outputs are P2867, P2868.		
Dependency:	P2802[3] assigns the timer to the processing sequence.		

p2866	Mode timer 4 / Mode timer 4		
Access level: 3	P-Group: Technology	Data type: Unsigned16	
Quick comm. NO	Active: NO	Data set: -	
Can be changed: U, T	Calculated: -		
Min 0	Max 13	Factory setting 0	
Description:	Selects mode of timer 4. P2864, P2865, P2866 are the inputs of the timer, outputs are P2867, P2868.		
Value:	0: ON delay (seconds) 1: OFF delay (seconds) 2: ON/OFF delay (seconds) 3: Pulse generator (seconds) 10: ON delay (minutes) 11: OFF delay (minutes) 12: ON/OFF delay (minutes) 13: Pulse generator (minutes)		
Dependency:	P2802[3] assigns the timer to the processing sequence.		

r2867.0	BO: Timer 4 / Timer 4				
Access level: 3	P-Group: Technology	Data type: Unsigned16			
Unit: -	Calculated: -	Data set: -			
Description:	Displays output of timer 4. P2864, P2865, P2866 are the inputs of the timer, outputs are P2867, P2868.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Output of BO	Yes	No	-
Dependency:	P2802[3] assigns the timer to the processing sequence.				

r2868.0	BO: Nout timer 4 / Nout timer 4				
Access level: 3	P-Group: Technology	Data type: Unsigned16			
Unit: -	Calculated: -	Data set: -			
Description:	Displays Not-output of timer 4. P2864, P2865, P2866 are the inputs of the timer, outputs are P2867, P2868.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Output of BO	Yes	No	-
Dependency:	P2802[3] assigns the timer to the processing sequence.				

p2869[0...1]	CI: ADD 1 / ADD 1		
Access level: 3	P-Group: Technology	Data type: U32 / Integer16	
Quick comm. NO	Active: NO	Data set: -	
Can be changed: U, T	Calculated: -		
Min -	Max -	Factory setting 755[0]	
Description:	Define inputs of Adder 1, result is in P2870.		
Index:	[0] = Connector input 0 (CI 0) [1] = Connector input 1 (CI 1)		
Dependency:	P2802[4] assigns the Adder to the processing sequence.		

r2870	CO: ADD 1 / ADD 1	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
		Unit: [%]	Calculated: -	Data set: -

Description: Result of Adder 1.
Dependency: P2802[4] assigns the Adder to the processing sequence.

p2871[0...1]	CI: ADD 2 / ADD 2	Access level: 3	P-Group: Technology	Data type: U32 / Integer16
		Quick comm. NO	Active: NO	Data set: -
		Can be changed: U, T	Calculated: -	
		Min	Max	Factory setting
		-	-	755[0]

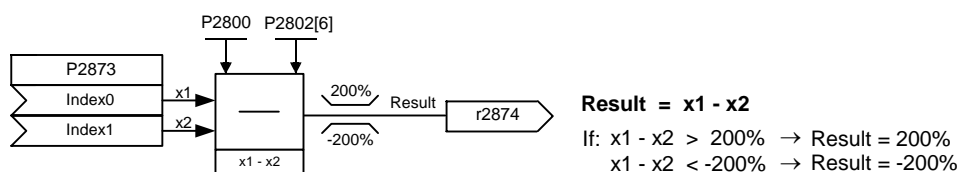
Description: Define inputs of Adder 2, result is in P2872.
Index: [0] = Connector input 0 (CI 0)
 [1] = Connector input 1 (CI 1)
Dependency: P2802[5] assigns the Adder to the processing sequence.

r2872	CO: ADD 2 / ADD 2	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
		Unit: [%]	Calculated: -	Data set: -

Description: Result of Adder 2.
Dependency: P2802[5] assigns the Adder to the processing sequence.

p2873[0...1]	CI: SUB 1 / SUB 1	Access level: 3	P-Group: Technology	Data type: U32 / Integer16
		Quick comm. NO	Active: NO	Data set: -
		Can be changed: U, T	Calculated: -	
		Min	Max	Factory setting
		-	-	755[0]

Description: Define inputs of Subtractor 1, result is in P2874.



Index: [0] = Connector input 0 (CI 0)
 [1] = Connector input 1 (CI 1)
Dependency: P2802[6] assigns the Subtractor to the processing sequence.

r2874	CO: SUB 1 / SUB 1	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
		Unit: [%]	Calculated: -	Data set: -

Description: Result of Subtractor 1.
Dependency: P2802[6] assigns the Subtractor to the processing sequence.

p2875[0...1] **CI: SUB 2 / SUB 2**

Access level: 3	P-Group: Technology	Data type: U32 / Integer16
Quick comm. NO	Active: NO	Data set: -
Can be changed: U, T	Calculated: -	
Min	Max	Factory setting
-	-	755[0]

Description: Define inputs of Subtractor 2, result is in P2876.
Index: [0] = Connector input 0 (CI 0)
 [1] = Connector input 1 (CI 1)
Dependency: P2802[7] assigns the Subtractor to the processing sequence.

r2876 **CO: SUB 2 / SUB 2**

Access level: 3	P-Group: Technology	Data type: FloatingPoint32
Unit: [%]	Calculated: -	Data set: -

Description: Result of Subtractor 2.
Dependency: P2802[7] assigns the Subtractor to the processing sequence.

p2877[0...1] **CI: MUL 1 / MUL 1**

Access level: 3	P-Group: Technology	Data type: U32 / Integer16
Quick comm. NO	Active: NO	Data set: -
Can be changed: U, T	Calculated: -	
Min	Max	Factory setting
-	-	755[0]

Description: Define inputs of Multiplier 1, result is in P2878.



Index: [0] = Connector input 0 (CI 0)
 [1] = Connector input 1 (CI 1)
Dependency: P2802[8] assigns the Multiplier to the processing sequence.

r2878 **CO: MUL 1 / MUL 1**

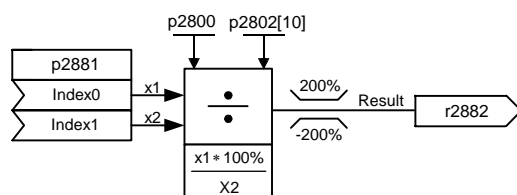
Access level: 3	P-Group: Technology	Data type: FloatingPoint32
Unit: [%]	Calculated: -	Data set: -

Description: Result of Multiplier 1.
Dependency: P2802[8] assigns the Multiplier to the processing sequence.

p2879[0...1]	CI: MUL 2 / MUL 2		
	Access level: 3	P-Group: Technology	Data type: U32 / Integer16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	755[0]
Description:	Define inputs of Multiplier 2, result is in P2880.		
Index:	[0] = Connector input 0 (CI 0) [1] = Connector input 1 (CI 1)		
Dependency:	P2802[9] assigns the Multiplier to the processing sequence.		

r2880	CO: MUL 2 / MUL 2		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Result of Multiplier 2.		
Dependency:	P2802[9] assigns the Multiplier to the processing sequence.		

p2881[0...1]	CI: DIV 1 / DIV 1		
	Access level: 3	P-Group: Technology	Data type: U32 / Integer16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	755[0]
Description:	Define inputs of Divider 1, result is in P2882.		



$$\text{Result} = \frac{x1 * 100\%}{x2}$$

If: $\frac{x1 * 100\%}{x2} > 200\% \rightarrow \text{Result} = 200\%$

If: $\frac{x1 * 100\%}{x2} < -200\% \rightarrow \text{Result} = -200\%$

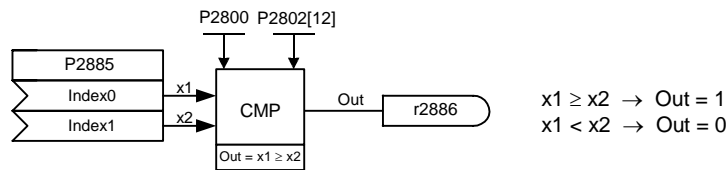
Index:	[0] = Connector input 0 (CI 0) [1] = Connector input 1 (CI 1)
Dependency:	P2802[10] assigns the Divider to the processing sequence.

r2882	CO: DIV 1 / DIV 1		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Result of Divider 1.		
Dependency:	P2802[10] assigns the Divider to the processing sequence.		

p2883[0...1]	CI: DIV 2 / DIV 2		
	Access level: 3	P-Group: Technology	Data type: U32 / Integer16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min	Max	Factory setting
	-	-	755[0]
Description:	Define inputs of Divider 2, result is in P2884.		
Index:	[0] = Connector input 0 (CI 0) [1] = Connector input 1 (CI 1)		
Dependency:	P2802[11] assigns the Divider to the processing sequence.		

r2884 **CO: DIV 2 / DIV 2**
Access level: 3 **P-Group:** Technology **Data type:** FloatingPoint32
Unit: [%] **Calculated:** - **Data set:** -
Description: Result of Divider 2.
Dependency: P2802[11] assigns the Divider to the processing sequence.

p2885[0...1] **CI: CMP 1 / CMP 1**
Access level: 3 **P-Group:** Technology **Data type:** U32 / Integer16
Quick comm. NO **Active:** NO **Data set:** -
Can be changed: U, T **Calculated:** -
Min **Max** **Factory setting**
- - 755[0]
Description: Defines inputs of Comparator 1, output is P2886.



Index: [0] = Connector input 0 (CI 0)
[1] = Connector input 1 (CI 1)
Dependency: P2802[12] assigns the Comparator to the processing sequence.

r2886.0 **BO: CMP 1 / CMP 1**
Access level: 3 **P-Group:** Technology **Data type:** Unsigned16
Unit: - **Calculated:** - **Data set:** -
Description: Displays result bit of Comparator 1.
Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Output of BO	Yes	No	-

Dependency: P2802[12] assigns the Comparator to the processing sequence.

p2887[0...1] **CI: CMP 2 / CMP 2**
Access level: 3 **P-Group:** Technology **Data type:** U32 / Integer16
Quick comm. NO **Active:** NO **Data set:** -
Can be changed: U, T **Calculated:** -
Min **Max** **Factory setting**
- - 755[0]
Description: Defines inputs of Comparator 2, output is P2888.
Index: [0] = Connector input 0 (CI 0)
[1] = Connector input 1 (CI 1)
Dependency: P2802[13] assigns the Comparator to the processing sequence.

r2888.0 **BO: CMP 2 / CMP 2**
Access level: 3 **P-Group:** Technology **Data type:** Unsigned16
Unit: - **Calculated:** - **Data set:** -
Description: Displays result bit of Comparator 2.
Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Output of BO	Yes	No	-

Dependency: P2802[13] assigns the Comparator to the processing sequence.

p2889	CO: Fixed setpoint 1 in [%] / Fixed setp 1 %		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 0.00 [%]
Description:	Fixed percent setting 1.		
	Connector Setting in %		
	Range : -200% ... 200%		
p2890	CO: Fixed setpoint 2 in [%] / Fixed setp 2 %		
	Access level: 3	P-Group: Technology	Data type: FloatingPoint32
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min -200.00 [%]	Max 200.00 [%]	Factory setting 0.00 [%]
Description:	Fixed percent setting 2.		
p2940	BI: Release Wobble function / Rel Wobble		
	Access level: 2	P-Group: Technology	Data type: U32 / Binary
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min -	Max -	Factory setting 0
Description:	Defines the source to release the wobble function.		
p2945	Wobble signal frequency / Wobble sig freq		
	Access level: 2	P-Group: -	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min 0.001 [Hz]	Max 10.000 [Hz]	Factory setting 1.000 [Hz]
Description:	Sets the frequency of the wobble signal.		
p2946	Wobble signal amplitude / Wobble sig amp		
	Access level: 2	P-Group: -	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min 0.000 [%]	Max 0.200 [%]	Factory setting 0.000 [%]
Description:	Sets the value for the amplitude of the wobble-signal as a proportion of the present Ramp Function Generator (RFG) output. The value of P2946 is multiplied by the output value of the RFG then added to RFG output. For example, if the RFG output is 10 Hz, and P2946 has a value of 0.100, the wobble signal amplitude will be 0.100 * 10 = 1 Hz. This means that the RFG output will therefore wobble between 9 Hz and 11 Hz.		

p2947	Wobble signal decrement step / Signal dec step		
	Access level: 2	P-Group: -	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min 0.000	Max 1.000	Factory setting 0.000
Description:	Sets the value for decrement step at the end of the positive signal period. The amplitude of the step is dependant upon the signal amplitude as follows: Amplitude of signal decrement step = P2947 * P2946		
p2948	Wobble signal increment step / Signal inc step		
	Access level: 2	P-Group: -	Data type: FloatingPoint32
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min 0.000	Max 1.000	Factory setting 0.000
Description:	Sets the value for the increment step at the end of the negative signal period. The amplitude of the increment step is dependant upon the signal amplitude as follows: Amplitude of signal increment step = P2948 * P2946		
p2949	Wobble signal pulse width / Wobble pul width		
	Access level: 2	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min 0 [%]	Max 100 [%]	Factory setting 50 [%]
Description:	Sets the relative widths of the rising and falling pulses. The value in P2949 sets the proportion of the wobble period (determined by P2945) allocated to the rising pulse, the remainder of the time is allocation to the falling pulse. A value of 60% in P2949 means that 60% of the wobble period the wobble output will be rising. For the remaining 40% of the wobble period the wobble output will be falling.		
r2955	CO: Wobble signal output / Wobble output		
	Access level: 2	P-Group: Setpoints	Data type: FloatingPoint32
	Unit: [%]	Calculated: -	Data set: -
Description:	Displays the output of the wobble function.		

r3113.0...15	CO/BO: Fault Bit Array / Fault Bit Array		
CU240E	Access level: 1	P-Group: Messages	Data type: Unsigned16
CU240S	Unit: -	Calculated: -	Data set: -
CU240S DP			
CU240S PN			

Description: Gives information about actual fault.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Inverter error	Yes	No	-
	01	Power line failure	Yes	No	-
	02	Intermediate circuit power voltage	Yes	No	-
	03	Error power electronics	Yes	No	-
	04	Convertor over temperature	Yes	No	-
	05	Earth leakage	Yes	No	-
	06	Motor overload	Yes	No	-
	07	Bus fault	Yes	No	-
	09	Fault motor sensor	Yes	No	-
	10	Fault internal communication	Yes	No	-
	11	Motor current limit	Yes	No	-
	12	Supply failure	Yes	No	-
	13	Reserved	Yes	No	-
	14	Reserved	Yes	No	-
	15	Other error	Yes	No	-

r3113.0...15	CO/BO: Fault Bit Array / Fault Bit Array		
CU240S DP-F	Access level: 1	P-Group: Messages	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -

Description: Gives information about actual fault.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Inverter error	Yes	No	-
	01	Power line failure	Yes	No	-
	02	Intermediate circuit power voltage	Yes	No	-
	03	Error power electronics	Yes	No	-
	04	Convertor over temperature	Yes	No	-
	05	Earth leakage	Yes	No	-
	06	Motor overload	Yes	No	-
	07	Bus fault	Yes	No	-
	08	External safety failure	Yes	No	-
	09	Fault motor sensor	Yes	No	-
	10	Fault internal communication	Yes	No	-
	11	Motor current limit	Yes	No	-
	12	Supply failure	Yes	No	-
	13	Reserved	Yes	No	-
	14	Reserved	Yes	No	-
	15	Other error	Yes	No	-

p3900 End of quick commissioning / Quick commiss. end			
CU240E	Access level: 1	P-Group: Safety Integrated	Data type: Unsigned16
CU240S	Quick comm. YES	Active: NO	Data set: -
CU240S DP	Can be changed: C(1)	Calculated: -	
CU240S PN			
	Min 0	Max 11	Factory setting 0
Description:	Performs calculations necessary for optimized motor operation. After completion of calculation, P3900 and P0010 (parameter groups for commissioning) are automatically reset to their original value 0.		
Value:	0: No quick commissioning 1: End quick commissioning with factory reset 2: End quick commissioning 3: End quick commissioning only for motor data 10: Accept safety changes (only on safety CU) 11: Cancel safety changes (only on safety CU)		
Dependency:	Changeable only when P0010 = 1 (quick commissioning).		
Note:	P3900 = 1 : When setting 1 is selected, only the parameter settings carried out via the commissioning menu "Quick commissioning", are retained; all other parameter changes, including the I/O settings, are lost. Motor calculations are also performed. P3900 = 2 : When setting 2 is selected, only those parameters, which depend on the parameters in the commissioning menu "Quick commissioning" (P0010 = 1) are calculated. The I/O settings are also reset to default and the motor calculations performed. P3900 = 3 : When setting 3 is selected, only the motor and controller calculations are performed. Exiting quick commissioning with this setting saves time (for example, if only motor rating plate data have been changed). Calculates a variety of motor parameters, overwriting previous values. These include P0344 (motor weight), P0350 (demagnetization time), P2000 (reference frequency), P2002 (reference current). When transferring parameter p3900, the frequency inverter uses its processor to carry-out internal calculations. Communications - both via USS as well as via the Fieldbus - are interrupted for the time that it takes to make these calculations. This can result in the following error messages at the connected SIMATIC S7 control (communications via fieldbus): <ul style="list-style-type: none"> • Parameter fault 30 • Drive fault 70 • Drive fault 75 When using STARTER (USS) to commission the drive system, data cannot be entered while these calculations are being made. The faults can be acknowledged as soon as the calculations have been completed in the frequency inverter. These calculations can take up to one minute to complete.		

p3900		End of quick commissioning / Quick commiss. end	
CU240S DP-F	Access level: 1	P-Group: Safety Integrated	Data type: Unsigned16
CU240S PN-F	Quick comm. YES	Active: NO	Data set: -
	Can be changed: C(1)	Calculated: -	
	Min 0	Max 11	Factory setting 0
Description:	Performs calculations necessary for optimized motor operation. After completion of calculation, P3900 and P0010 (parameter groups for commissioning) are automatically reset to their original value 0.		
Value:	0: No quick commissioning 1: End quick commissioning with factory reset 2: End quick commissioning 3: End quick commissioning only for motor data 10: Accept safety changes (only on safety CU) 11: Cancel safety changes (only on safety CU)		
Dependency:	Changeable only when P0010 = 1 (quick commissioning). Or for safety commissioning P0010 = 95.		
Note:	P3900 = 1 : When setting 1 is selected, only the parameter settings carried out via the commissioning menu "Quick commissioning", are retained; all other parameter changes, including the I/O settings, are lost. Motor calculations are also performed. P3900 = 2 : When setting 2 is selected, only those parameters, which depend on the parameters in the commissioning menu "Quick commissioning" (P0010 = 1) are calculated. The I/O settings are also reset to default and the motor calculations performed. P3900 = 3 : When setting 3 is selected, only the motor and controller calculations are performed. Exiting quick commissioning with this setting saves time (for example, if only motor rating plate data have been changed). Calculates a variety of motor parameters, overwriting previous values. These include P0344 (motor weight), P0350 (demagnetization time), P2000 (reference frequency), P2002 (reference current). P3900 = 10 Finishes the safety commissioning by accepting the safety changes. The safety commissioning including safety dynamization will take about 5 s. P3900 = 11 Finishes the safety commissioning by discarding the safety changes. The safety settings that were active before the safety commissioning are reloaded. The safety commissioning including safety dynamization will take about 5 s. When transferring parameter p3900, the frequency inverter uses its processor to carry-out internal calculations. Communications - both via USS as well as via the Fieldbus - are interrupted for the time that it takes to make these calculations. This can result in the following error messages at the connected SIMATIC S7 control (communications via fieldbus): <ul style="list-style-type: none"> • Parameter fault 30 • Drive fault 70 • Drive fault 75 When using STARTER (USS) to commission the drive system, data cannot be entered while these calculations are being made. The faults can be acknowledged as soon as the calculations have been completed in the frequency inverter. These calculations can take up to one minute to complete.		

r3930[0...4]	PS Data version / PS Data version		
	Access level: 3	P-Group: -	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays the A5E number and the ps data versions		
Index:	[0] = A5E 1st 4 digits [1] = A5E 2nd 4 digits [2] = Logistic Version [3] = Fixed Data Version [4] = Calib Data Version		
p3950	Access of hidden parameters / Access hidden par		
	Access level: 4	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: U, T	Calculated: -	
	Min 0	Max 255	Factory setting 0
Description:	Accesses special parameters for development (expert only) and factory functionality (calibration parameter).		
r3954[0...12]	CM info and GUI ID / CC info GUI ID		
	Access level: 4	P-Group: -	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Used to classify firmware (only for SIEMENS internal purposes).		
Index:	[0] = CM label (increment/branch) [1] = CM label (counter) [2] = CM label [3] = GUI ID [4] = GUI ID [5] = GUI ID [6] = GUI ID [7] = GUI ID [8] = GUI ID [9] = GUI ID [10] = GUI ID [11] = GUI ID major release [12] = GUI ID minor release		
r3955	Version for DriveMonitor / DriveMon. version		
	Access level: 3	P-Group: -	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Displays the version for DriveMonitor.		
r3978	BICO counter / BICO counter		
	Access level: 4	P-Group: -	Data type: Unsigned32
	Unit: -	Calculated: -	Data set: -
Description:	Counts the number of changed BICO links		

p3981	Reset active fault / Reset active fault		
	Access level: 4	P-Group: Messages	Data type: Unsigned16
	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min 0	Max 1	Factory setting 0
Description:	Resets active faults when changed from 0 to 1.		
Value:	0: No fault reset 1: Reset fault		
Note:	See P0947 (last fault code) Automatically reset to 0.		
p3984	Client telegram off time / Client tel. off ti		
	Access level: 3	P-Group: Communications	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min 100 [ms]	Max 10000 [ms]	Factory setting 1000 [ms]
Description:	Defines time after which a fault will be generated (7220) if no telegram is received from the client.		
Dependency:	Setting 0 = watchdog disabled		
r3986[0...1]	Number of parameters / No. of parameters		
	Access level: 4	P-Group: -	Data type: Unsigned16
	Unit: -	Calculated: -	Data set: -
Description:	Number of parameters on the drive.		
Index:	[0] = Read only [1] = Read & write		
p7841[0...5]	PM serial no hot swap check / PM Serialno		
	Access level: 3	P-Group: Converter	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min 0	Max 65535	Factory setting 0
Description:	Reads the power module serial number, which is stored in the control unit. At power up these serial number are verified, if any swapping of the CU or the PM had been taken place.		
Index:	[0] = Production site [1] = Production year after 2000 [2] = Production month [3] = Production day [4] = Production number per day [5] = Type - not used on all drives		
Note:	The parameter cannot be changed.		

p7844 Acceptance Test, Confirmation / Ack Accept. Test			
CU240E	Access level: 3	P-Group: -	Data type: Unsigned16
	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min 0	Max 2	Factory setting 0
Description:	After a CU/PM swap this parameter will be automatically set to 1. Also a fault F0395 will be set. With setting to P7844 = 0 you quit F0395 and confirm the parameter settings. Setting this parameter to 2 is not possible with CU240E.		
Value:	0: Acceptance Test / Confirmation ok. 1: Acceptance Test / Confirmation is pending 2: Undo Clone		

p7844 Acceptance Test, Confirmation / Ack Accept. Test			
CU240S	Access level: 3	P-Group: -	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: YES	Data set: -
CU240S DP-F	Can be changed: T	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min 0	Max 2	Factory setting 0
Description:	After a CU/PM swap or after an automatic download from MMC at startup, this parameter will be automatically set to 1. Also a fault F0395 will be set. With setting to P7844 = 0 you quit F0395 and confirm the parameter settings. In case of a fail-safe CU an acceptance test must be performed. Setting this parameter to 2 is only possible if an automatic download has been performed at startup. In this case the download will be undone and the previously stored parameters will be enabled. In case of a fail-safe CU an acceptance test must be performed.		
Value:	0: Acceptance Test / Confirmation ok. 1: Acceptance Test / Confirmation is pending 2: Undo Clone		
Note:	If no automatic download from MMC has been performed during startup the setting 2 is not possible.		

p8458 Clone Control / Clone Control			
CU240S	Access level: 3	P-Group: Factory settings	Data type: Unsigned16
CU240S DP	Quick comm. NO	Active: NO	Data set: -
CU240S DP-F	Can be changed: T	Calculated: -	
CU240S PN			
CU240S PN-F			
	Min 0	Max 2	Factory setting 1
Description:	This parameter specifies whether a cloning at startup will be performed. The File clone00.bin will be used. If no MMC is inserted there will be a normal startup.		
Value:	0: No Startup Clone 1: Once Startup Clone 2: Always Startup Clone		
Note:	Default value is 1. After first cloning the parameter is set to 0. If a MMC is inserted without a valid file the drive will set a fault F0061 / F0063 / F0064 which can only be cleared by a powercycle. The fault is signalled by a flashing RUN LED (Commissioning). The SF LED is not activated.		

p8840	Fieldbus Off-time / FB off-time		
CU240S PN	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min 0 [ms]	Max 65535 [ms]	Factory setting 20 [ms]
Description:	Fieldbus off-time.		
p8841[0...15]	Fieldbus configuration data / FB conf data		
CU240S PN	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min 0000 hex	Max FFFF hex	Factory setting 0000 hex
Description:	Fieldbus configuration data.		
Index:	[0] = FB Parameter 0 [1] = FB Parameter 1 [2] = FB Parameter 2 [3] = FB Parameter 3 [4] = FB Parameter 4 [5] = FB Parameter 5 [6] = FB Parameter 6 [7] = FB Parameter 7 [8] = FB Parameter 8 [9] = FB Parameter 9 [10] = FB Parameter 10 [11] = FB Parameter 11 [12] = FB Parameter 12 [13] = FB Parameter 13 [14] = FB Parameter 14 [15] = FB Parameter 15		
r8849[0...15]	Fieldbus rev configuration data / FB rev conf data		
CU240S PN	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -
Description:	Fieldbus reverse configuration data display.		
r8850[0...7]	CO: PZD from Fieldbus / PZD from FB		
CU240S PN	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -
Description:	PZD from Fieldbus.		
Index:	[0] = Received word 0 [1] = Received word 1 [2] = Received word 2 [3] = Received word 3 [4] = Received word 4 [5] = Received word 5 [6] = Received word 6 [7] = Received word 7		

p8851[0...7]		CI: PZD to Fieldbus / PZD to FB	
CU240S PN	Access level: 3	P-Group: Communications	Data type: U32 / Integer16
CU240S PN-F	Quick comm. NO	Active: YES	Data set: -
	Can be changed: T	Calculated: -	
	Min	Max	Factory setting
	-	-	52[0]
Description:	PZD to Fieldbus.		
Index:	[0] = Transmitted word 0 [1] = Transmitted word 1 [2] = Transmitted word 2 [3] = Transmitted word 3 [4] = Transmitted word 4 [5] = Transmitted word 5 [6] = Transmitted word 6 [7] = Transmitted word 7		

r8858[0...15]		Fieldbus diagnostic data display / FB diag data displ	
CU240S PN	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -
Description:	Fieldbus diagnostic data display.		
Index:	[0] = FB Diag. 0 [1] = FB Diag. 1 [2] = FB Diag. 2 [3] = FB Diag. 3 [4] = FB Diag. 4 [5] = FB Diag. 5 [6] = FB Diag. 6 [7] = FB Diag. 7 [8] = FB Diag. 8 [9] = FB Diag. 9 [10] = FB Diag. 10 [11] = FB Diag. 11 [12] = FB Diag. 12 [13] = FB Diag. 13 [14] = FB Diag. 14 [15] = FB Diag. 15		

r8859[0...7]	Fieldbus identification data display / FB id data display		
CU240S PN	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -

Description: Fieldbus identification data display.
The different Fieldbus types (r8859[0]) are given below:
0 = No additional Fieldbus option available
1 = PROFIBUS DP
2 = DeviceNet
3 = CAN
4 = AS-i
5 = LON
6 = Modbus
10 = PROFINet IO
11 = ES bus (ET 200pro)
4660 = ES bus (ET 200S)
65535 = not defined

Index:
[0] = FB data structure version
[1] = FB driver version
[2] = FB type
[3] = Firmware version
[4] = Firmware version detail
[5] = Firmware date (year)
[6] = Firmware date (day/month)
[7] = unused

r8890.0...15	BO: Control word 1 from Fieldbus / CtrlWd1 <- FB		
CU240S PN	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -

Description: Displays control word 1 received from Fieldbus.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	ON/OFF1	Yes	No	-
	01	OFF2: Electrical stop	No	Yes	-
	02	OFF3: Fast stop	No	Yes	-
	03	Pulse enable	Yes	No	-
	04	RFG enable	Yes	No	-
	05	RFG start	Yes	No	-
	06	Setpoint enable	Yes	No	-
	07	Fault acknowledge	Yes	No	-
	08	JOG right	Yes	No	-
	09	JOG left	Yes	No	-
	10	Control from PLC	Yes	No	-
	11	Reverse (setpoint inversion)	Yes	No	-
	13	Motor potentiometer MOP up	Yes	No	-
	14	Motor potentiometer MOP down	Yes	No	-
	15	CDS Bit 0 (Hand/Auto)	Yes	No	-

Note: If P0700 = 6 (Fieldbus) then P0810 must be set to 2090.15 for correct operation.
This will not be cleared automatically when P0700 is no longer equal to 6.

r8891.0...15	BO: Control word 2 from Fieldbus / CtrlWd2 <- FB		
CU240S PN	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -
PM240			

Description: Displays control word 2 received from Fieldbus.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fixed frequency Bit 0	Yes	No	-
	01	Fixed frequency Bit 1	Yes	No	-
	02	Fixed frequency Bit 2	Yes	No	-
	03	Fixed frequency Bit 3	Yes	No	-
	04	Drive Dataset (DDS) Bit 0	Yes	No	-
	05	Drive Dataset (DDS) Bit 1	Yes	No	-
	08	Enable PID	Yes	No	-
	09	Enable DC brake	Yes	No	-
	11	Enable Droop	Yes	No	-
	12	Torque control	Yes	No	-
	13	External fault 1	No	Yes	-
	15	Command Dataset (CDS) Bit 1	Yes	No	-

r8891.0...15	BO: Control word 2 from Fieldbus / CtrlWd2 <- FB		
CU240S PN	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -
PM250, PM260			

Description: Displays control word 2 received from Fieldbus.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Fixed frequency Bit 0	Yes	No	-
	01	Fixed frequency Bit 1	Yes	No	-
	02	Fixed frequency Bit 2	Yes	No	-
	03	Fixed frequency Bit 3	Yes	No	-
	04	Drive Dataset (DDS) Bit 0	Yes	No	-
	05	Drive Dataset (DDS) Bit 1	Yes	No	-
	08	Enable PID	Yes	No	-
	11	Enable Droop	Yes	No	-
	12	Torque control	Yes	No	-
	13	External fault 1	No	Yes	-
	15	Command Dataset (CDS) Bit 1	Yes	No	-

p9601	SI enable parameter / SI enable		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min	Max	Factory setting
	-	-	0010 bin

Description: Safety parameter for enabling the individual safety control functions.

Bit01 activates the forced dynamisation and processor selftest on selection of the STO. Warning A1699 can only be acknowledged when Bit01 is set. The switch-on of pulses is inhibited during the test (i.e. r0052 Bit06 = 1) for approximately 3.1 seconds.

Bit field:	Bit	Signal name	1 signal	0 signal	FP
	01	Enable forced dynamisation (self test) after STO	Yes	No	-

Notice: The switch-off circuitry of the mechanical brake is tested during the forced dynamisation. For short periods (2 ms - 16 ms) the brake is controlled to open. In general the mechanical brake will require command signals longer than 20 ms. Care should be taken if a brake is used that has a reaction time of less than 20 ms.

p9602		SI enable safe brake monitoring / SI brake mon. ena		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16	
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -	
	Can be changed: -	Calculated: -		
	Min	Max	Factory setting	
	0	1	0	
Description:	As long as P9602 is set to 0, there is no monitoring of the output level but switching on and off is still performed. The ability to shutdown is especially important when no brake is used, otherwise the absence of the brake module or the power contactor for the brake would be interpreted as a cable breakage and result in an alarm message. To enable monitoring of the safe brake control, set P9602 to 1.			
Value:	0: Disable monitoring of safe brake control 1: Enable monitoring of safe brake control			
Note:	The holding brake must be dimensioned so that should a fault occur the complete drive can be braked to zero from any possible operational frequency.			

p9603		SI Selection of Safety Source / SI Source select			
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16		
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -		
	Can be changed: -	Calculated: -			
	Min	Max	Factory setting		
	-	-	0000 bin		
Description:	Safety parameter for selection of the safety input signals. The safety input signals can be taken either from PROFIsafe and or from the safe digital inputs. Two digital inputs form one safety input. The first safety input consists of FDI0A and FDI0B, the second safety input consists of FDI1A and FDI1B. Using digital inputs, each safety input can be assigned to the safety functions "safe torque off (STO)", "safe stop 1 (SS1)" or "safely-limited speed (SLS)".				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	SLS activated via FDI1A and FDI1B	Yes	No	-
	01	SLS activated via FDI0A and FDI0B	Yes	No	-
	02	SS1 activated via FDI1A and FDI1B	Yes	No	-
	03	SS1 activated via FDI0A and FDI0B	Yes	No	-
	04	STO activated via FDI1A and FDI1B	Yes	No	-
	05	STO activated via FDI0A and FDI0B	Yes	No	-
	06	STO, SS1, SLS activated via PROFIsafe, alternate SLS	Yes	No	-
	07	STO, SS1, SLS activated via PROFIsafe	Yes	No	-

r9620.0...13**CO/BO: SI status word / SI StatWd**CU240S DP-F
CU240S PN-F**Access level:** 3**P-Group:** Safety Integrated**Data type:** Unsigned16**Unit:** -**Calculated:** -**Data set:** -**Description:**

Displays the status of safety integrated. This status word is cross compared with r9820, if any differences are detected for more than 100ms a fault will be generated (F1611.105)

Bit field:

Bit	Signal name	1 signal	0 signal	FP
00	Safe torque off (STO) selected	Yes	No	-
01	Safe torque off (STO) activated	Yes	No	-
02	Safe stop 1 (SS1) selected	Yes	No	-
03	Safety monitoring ramp active	Yes	No	-
04	Safely limited speed (SLS) selected	Yes	No	-
05	SLS limit reached	Yes	No	-
06	reserved	Yes	No	-
07	reserved	Yes	No	-
08	Passivated STO active, drive fault	Yes	No	-
09	Safe Digital Input 0 active	Yes	No	-
10	Safe Digital Input 1 active	Yes	No	-
13	1 Freq Channel monitoring	Yes	No	-

Note:

For further information on the meaning of the bits see the descriptions of the safety functions STO, SS1 and SLS in the manual.

p9650**SI Safe Digital Input debounce delay time / SI Debounce FDI**CU240S DP-F
CU240S PN-F**Access level:** 3**P-Group:** Safety Integrated**Data type:** Unsigned32**Quick comm.:** NO**Active:** NO**Data set:** -**Can be changed:** -**Calculated:** -**Min**

0 [ms]

Max

2000 [ms]

Factory setting

50 [ms]

Description:

Defines the maximum allowed debounce delay between the two safe digital input pins. If both safe digital inputs are not consistent after this time a fault will be generated (F1601.108).

p9651**SI Safe Digital Input filter delay time / SI Filt. delay FDI**CU240S DP-F
CU240S PN-F**Access level:** 3**P-Group:** Safety Integrated**Data type:** Unsigned32**Quick comm.:** NO**Active:** NO**Data set:** -**Can be changed:** -**Calculated:** -**Min**

0 [ms]

Max

100 [ms]

Factory setting

5 [ms]

Description:

Defines the response time delay of the safe digital inputs. Signals that are shorter than the specified time are not processed as safety signals but ignored.

Any noise occurs shorter than filter time has no effect to level of safe digital inputs.

Note:

Increasing/decreasing of the filter delay time has direct impact to the reaction time between triggering and activating the safety function.

p9659	SI max time until forced dynam. / SI forc dynam time		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: FloatingPoint32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 0.1 [h]	Max 8760.0 [h]	Factory setting 8.0 [h]
Description:	<p>The time interval between forced dynamisation procedures is specified. The remaining time until a forced dynamisation is required is shown in r9660. When r9660 reaches zero, the time interval has expired and warning A1699 is activated.</p> <p>The warning solely informs that a forced dynamisation is required. The user should activate a forced dynamisation on the next occasion. The drive functionality will not be affected by the warning.</p> <p>The forced dynamisation is activated in the following cases:</p> <ul style="list-style-type: none"> • after each power-up, • on de-selecting the STO when p9601 = p9801 = 2, • when leaving the passivated safe torque off (passivated STO). • when leaving safety commissioning, <p>During forced dynamisation all shutdown paths are tested and a processor selftest is carried out.</p> <p>The timer for the forced dynamisation (see r9660) is reset to the value in p9659 and warning A1699 is cleared if the forced dynamisation was carried out successfully.</p>		
r9660	CO: SI remain time until forc dynam / SI remaining time		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: FloatingPoint32
CU240S PN-F	Unit: [h]	Calculated: -	Data set: -
Description:	<p>Parameter r9660 displays the remaining time until a forced dynamisation is required. When r9660 reaches zero, warning A1699 is issued and a status bit in parameter r9772 is set.</p>		
Note:	<p>The warning A1699 and status bit of r9772 are only cleared when the dynamisation has been completed (see description of p9659).</p> <p>The resetting of r9660 to the value in p9659 will take place once the dynamisation has finished.</p> <p>The resolution of r9660 is 0.1 hour or 6 minutes.</p>		
p9680	SI braking ramp delay / SI braking delay		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 10 [ms]	Max 99000 [ms]	Factory setting 250 [ms]
Description:	<p>Time [in ms] between selecting the safe stop 1 and the activation of the monitoring ramp. The actual frequency is compared to the frequency of the monitoring ramp when the SS1 is active. If the actual frequency exceeds that of the monitoring ramp, a passivated safe torque off (passivated STO) is generated.</p> <p>For applications with changing loads, an increase of p9680/p9880 or p9691/p9891 is recommended. A larger deviation of the actual frequency from the reference is then acceptable.</p>		
Note:	<p>A value of 99000 deactivates the SS1 monitoring. Set p9880 accordingly. The ramping on selection of SLS or SS1 will however still follow the ramping time in p9681/p9881.</p>		

p9681	SI braking ramp down time / SI ramp down time		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 100 [ms]	Max 99000 [ms]	Factory setting 10000 [ms]
Description:	<p>Defines the braking ramp down time for the safe stop 1 (SS1) in milliseconds. The ramp down time is used for the SS1 and the monitoring ramp.</p> <p>The total braking time Tx can be derived where fx is the current frequency according to the following formulas:</p> <p>a) For activation of the SLS: $Tx = p9681 * (fx - p9690) / 200 \text{ Hz}$</p> <p>b) For activation of SS1: $Tx = p9681 * (fx - p9682) / 200 \text{ Hz}$</p>		
Note:	In contrast to other ramping times (e.g. p1120, p1121), the safety braking time is referred to 200 Hz and not to p1082. See formulas above.		
p9682	SI minimum frequency for standstill detection / SI min standstill		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: FloatingPoint32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 2.0 [Hz]	Max 20.0 [Hz]	Factory setting 5.0 [Hz]
Description:	<p>A frequency below the threshold of p9682/p9882 is considered standstill.</p> <p>If the SS1 has been selected, the safe torque off (STO) will be activated.</p>		
p9690	SI setpoint for SLS / SI setpoint SLS		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: FloatingPoint32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 2.0 [Hz]	Max 300.0 [Hz]	Factory setting 10.0 [Hz]
Description:	<p>Frequency setpoint that is used when the safely limited speed (SLS) is selected.</p> <p>Depending on the setting in p9692/p9892 the frequency of p9690/p9890 may also serve as a frequency threshold instead of a setpoint (see p9692).</p>		
Note:	<p>For applications with changing loads, an increase of p9680/p9880 or p9691/p9891 is recommended.</p> <p>If the "safely limited speed" (SLS) is selected while the output frequency is below the setpoint value, Bit04 and Bit05 will be set simultaneously in r9772.</p>		
p9691	SI tolerance for SLS / SI tolerance SLS		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: FloatingPoint32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 5.0 [Hz]	Max 303.0 [Hz]	Factory setting 13.0 [Hz]
Description:	<p>Upper tolerance margin for the SLS. If the actual frequency at initiation of the safely limited speed lies below the value of p9691/p9891 and later on exceeds that value a passivated safe torque off (passivated STO) is generated. The tolerance defined by the difference p9691 - p9690 (or p9891 - p9890) is also used for the monitoring ramp when the SS1 is active.</p> <p>For applications with changing loads it is recommended to increase p9691/p9891.</p>		
Note:	The value in p9691 needs to be larger than the value in p9690. This condition is checked when leaving the safety commissioning.		

p9692 SI response to selecting SLS / SI SLS response			
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 0	Max 3	Factory setting 1
Description:	<p>Defines the response after the initiation of the safely limited speed (SLS).</p> <ul style="list-style-type: none"> p9692 = p9892 = 0 (mode 0): The fact that the output frequency at initiation of the safely limited speed exceeds the safe limit value parameterised in p9691/p9891 is interpreted as fault, wherefore a safe stop 1 followed by a passivated safe torque off is initiated. If, however, the output frequency at initiation of the safely limited speed lies below the upper limit parameterised in p9691/p9891 the drives frequency control channel is blocked, wherefore the actual drive frequency cannot be controlled by an external control (e.g. PLC, MotorPoti, USS, etc.) anymore. The drive will then be locked at the current frequency. p9692 = p9892 = 1 (mode 1): The fact that the output frequency at initiation of the safely limited speed exceeds the safe limit value is not interpreted as fault, wherefore the safe stop 1 function is initiated automatically. The target frequency is not zero (as it usually is at SS1) but rather a parameterisable value (p9690/p9890) just below the tolerance value parameterised in p9691/p9891. If the output frequency lies below the parameterised frequency (p9690/p9890) the brake ramp does not need to be activated and the output frequency does not need to be changed, thus the behaviour would be the same as safely limited speed mode 0. After initiating the function safely limited speed and braking the drive down to the parameterised frequency (p9690/p9890) by using the safe stop 1 the drives frequency control channel is blocked, wherefore the actual drive frequency cannot be controlled by an external control (e.g. PLC, MotorPoti, USS, etc.) anymore. The drive will then be locked at a constant frequency, which is parameterised in p9690/p9890. p9692 = p9892 = 2 (mode 2): After initiating the safely limited speed function only the monitoring ramp will be activated. The safe stop 1 will not be activated, therefore, it would be the responsibility of the customer to ramp the drive down to or below the SLS setpoint (p9690/9890), before activating SLS. The drive frequency is then controlled by the external control (e.g. PLC, MotorPoti, USS, etc.). Now, setting the control channel to a frequency, which exceeds the parameterised limit in p9691/p9891, is interpreted as fault condition, wherefore a passivated safe torque off is initiated immediately. p9692 = p9892 = 3 (mode 3): Mode 3 is similar to mode 2. Contrary to mode 2 reversing of direction is possible as well as starting with an ON command while SLS Mode 3 monitoring is active. In mode 3 the safe brake ramp is not activated. Therefore it is the users responsibility to ensure that the motor is ramped down to or below the SLS setpoint. 		
Value:	<p>0: Initiate STO with braking ramp and drive fault when $f > f_{SLS}$</p> <p>1: Activate braking ramp while $f > f_{SLS}$</p> <p>2: STO without braking ramp and with drive fault while $f > f_{SLS}$</p> <p>3: SLS with Ramping from 0Hz</p>		

r9760 SI internal password / SI intern password			
CU240S DP-F	Access level: 4	P-Group: Safety Integrated	Data type: Unsigned32
CU240S PN-F	Unit: -	Calculated: -	Data set: -
Description:	<p>Contains the current safety password. For safety commissioning or safety reset the value of r9760 has to be entered into p9761.</p> <p>If the password in p9761 is not set correctly to the value in r9760, none of the safety parameters can be written and a fault F1659 is generated.</p> <p>This parameter is changed automatically to the password in p9763 when the new value of p9762 is identical to the confirmation password in p9763.</p>		

p9761	SI input password / SI input password		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 1000	Max 99999	Factory setting 1000
Description:	The safety password of r9760 is entered in this parameter to get access to changing the safety parameters. If p9761 is not identical to r9760 a fault F1659 is generated.		
Note:	The default value of this parameter is 0. This indicates that no password has been set. The range of the password values are 1000 to 99999.		
p9762	SI change password / SI change password		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 1001	Max 99999	Factory setting 12345
Description:	Parameter to change the safety password. The new safety password is entered in p9762 and then confirmed by entering same value in p9763.		
Note:	The default value of this parameter is 0. This indicates that no password has been set. The range of the password values are 1000 to 99999. The values in p9762 and p9763 are set to zero automatically when the new password is accepted.		
p9763	SI change password confirmation / SI passwd. confirm		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 1001	Max 99999	Factory setting 12345
Description:	Confirm a safety password change. Parameter needs to be set to the same value as p9762. Only then password change of p9762 is stored in r9760. If p9763 is not identical to p9762, both values are cleared and r9760 is not updated.		
Note:	The default value of this parameter is 0. This indicates that no password has been set. The range of the password values are 1000 to 99999. The values in p9762 and p9763 are set to zero automatically when the new password is accepted.		
r9770[0...5]	SI Firmware version / SI FW version		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -
Description:	Displays the Safety Integrated and PROFIsafe version.		
Example:	r9770[0] = 2, r9770[1] = 1, r9770[2] = 3 is for safety version V02.01.0003 r9770[3] = 2, r9770[4] = 1, r9770[5] = 3 is for PROFIsafe version V02.01.0003		
Index:	[0] = Safety major release [1] = Safety minor release [2] = Safety baselevel (patch) [3] = PROFIsafe major release [4] = PROFIsafe minor release [5] = PROFIsafe baselevel (patch)		

r9771.0...1		CO/BO: SI hardware functions / SI hw functions			
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16		
CU240S PN-F	Unit: -	Calculated: -	Data set: -		
Description:	Displays the available safety functions of the drive (bit coded).				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Safe shutdown path available	Yes	No	-
	01	Sensorless safety speed monitoring available	Yes	No	-

Note:

r9772.0...15		CO/BO: SI status word / SI StatWd			
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16		
CU240S PN-F	Unit: -	Calculated: -	Data set: -		
Description:	Displays the status of safety integrated.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Safe torque off (STO) selected	Yes	No	-
	01	Safe torque off (STO) activated	Yes	No	-
	02	Safe stop 1 (SS1) selected	Yes	No	-
	03	Safety monitoring ramp active	Yes	No	-
	04	Safely limited speed (SLS) selected	Yes	No	-
	05	SLS limit reached	Yes	No	-
	06	reserved	Yes	No	-
	07	reserved	Yes	No	-
	08	Passivated STO active, drive fault	Yes	No	-
	09	Safe Digital Input 0 active	Yes	No	-
	10	Safe Digital Input 1 active	Yes	No	-
	13	1 Freq Channel monitoring	Yes	No	-
	14	Safe Brake closed	Yes	No	-
	15	Dynamisation required	Yes	No	-

Note: For further informations to the meaning of the bits see the descriptions of the safety functions STO, SS1 and SLS in the manual.

r9798		SI display checksum / SI act. checksum			
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16		
CU240S PN-F	Unit: -	Calculated: -	Data set: -		
Description:	Display of safety checksum for P1. The checksum changes when CRC-relevant safety parameters of P1 are changed (parameter range p9600 - p9699, except p9659).				
Note:	This checksum must be identical to the value in r9898 before the safety commissioning can be finished via p3900 = 10. If r9798 differs from r9898 the CRC-relevant safety parameters of P1 differ from that of P2. Check the parameters of P1 against that of P2 and correct the mistake. When r9798 and r9898 differ, the safety commissioning can always be left via p3900 = 11, thus discarding the last changes.				

p9799		SI parameter checksum / SI checksum			
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16		
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -		
	Can be changed: -	Calculated: -			
	Min 0000 hex	Max FFFF hex	Factory setting 8AFD hex		
Description:	Confirm checksum of the P1 safety parameters. The correct value has to be entered before leaving the safety commissioning with p3900 = 10.				
	Only if r9798, r9898, p9799 and p9899 are all identical, the commissioning can be finished.				
Note:	Enter the reading of r9798 or r9898 into p9799 once no more safety parameters need to be changed.				
p9801		SI enable parameter / SI enable param.			
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16		
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -		
	Can be changed: -	Calculated: -			
	Min -	Max -	Factory setting 0010 bin		
Description:	Double of parameter p9601. See there.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	01	Enable forced dynamisation (self test) after STO	Yes	No	-
Note:	On non-safety hardware units, p9801 is zero by default.				
p9802		SI enable safe brake monitoring / SI brake mon. ena			
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16		
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -		
	Can be changed: -	Calculated: -			
	Min 0	Max 1	Factory setting 0		
Description:	Double of parameter p9602. See there.				
Value:	0: Disable monitoring of safe brake control 1: Enable monitoring of safe brake control				
p9803		SI Selection of Safety Source / SI Source select			
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16		
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -		
	Can be changed: -	Calculated: -			
	Min -	Max -	Factory setting 0000 bin		
Description:	Double of parameter p9603. See there.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	SLS activated via FDI1A and FDI1B	Yes	No	-
	01	SLS activated via FDI0A and FDI0B	Yes	No	-
	02	SS1 activated via FDI1A and FDI1B	Yes	No	-
	03	SS1 activated via FDI0A and FDI0B	Yes	No	-
	04	STO activated via FDI1A and FDI1B	Yes	No	-
	05	STO activated via FDI0A and FDI0B	Yes	No	-
	06	STO, SS1, SLS activated via PROFIsafe, alternate SLS	Yes	No	-
	07	STO, SS1, SLS activated via PROFIsafe	Yes	No	-

p9810		PROFIsafe destination address / F dest address	
CU240S DP-F	Access level: 2	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: T	Calculated: -	
	Min 0	Max 65534	Factory setting 0
Description:	Defines the PROFIsafe destination address for the communication. This parameter can be changed via a user-entered value.		
Note:	Valid PROFIsafe address settings: 1 ... 65534 0: default, inverter generates a fault F1640.107/207.		

r9820.0...13		CO/BO: SI status word / SI StatWd			
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16		
CU240S PN-F	Unit: -	Calculated: -	Data set: -		
Description:	Double of parameter p9620. See there. Fault (F1611.205) will be generated.				
Bit field:	Bit	Signal name	1 signal	0 signal	FP
	00	Safe torque off (STO) selected	Yes	No	-
	01	Safe torque off (STO) activated	Yes	No	-
	02	Safe stop 1 (SS1) selected	Yes	No	-
	03	Safety monitoring ramp active	Yes	No	-
	04	Safely limited speed (SLS) selected	Yes	No	-
	05	SLS limit reached	Yes	No	-
	06	reserved	Yes	No	-
	07	reserved	Yes	No	-
	08	Passivated STO active, drive fault	Yes	No	-
	09	Safe Digital Input 0 active	Yes	No	-
	10	Safe Digital Input 1 active	Yes	No	-
	13	1 Freq Channel monitoring	Yes	No	-

p9850		SI Safe Digital Input debounce delay time / SI Debounce FDI	
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: FloatingPoint32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 0.000 [s]	Max 2.000 [s]	Factory setting 0.050 [s]
Description:	Double of parameter p9650. See there.		
Note:	The debounce delay time in p9850 is entered in seconds!		

p9851		SI Safe Digital Input filter delay time / SI Filt. time FDI	
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: FloatingPoint32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 0.000 [s]	Max 0.100 [s]	Factory setting 0.005 [s]
Description:	Double of parameter p9651. See there.		
Note:	The filter delay time in p9851 is entered in seconds!		

p9880	SI braking ramp delay / SI braking delay		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: FloatingPoint32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 0.010 [s]	Max 99.000 [s]	Factory setting 0.250 [s]
Description:	Double of parameter p9680. See there.		
Note:	The delay time in p9880 is entered in seconds!		
p9881	SI braking ramp down time / SI ramp down time		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: FloatingPoint32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 0.100 [s]	Max 99.000 [s]	Factory setting 10.000 [s]
Description:	Double of parameter p9681. See there.		
Note:	The ramp down time in p9881 is entered in seconds!		
p9882	SI minimum frequency for standstill detection / SI min standstill		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: FloatingPoint32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 0.0020 [kHz]	Max 0.0200 [kHz]	Factory setting 0.0050 [kHz]
Description:	Double of parameter p9682. See there.		
Note:	The standstill detection frequency in p9882 is entered in kHz!		
p9890	SI setpoint for SLS / SI setpoint SLS		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: FloatingPoint32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 0.0020 [kHz]	Max 0.3000 [kHz]	Factory setting 0.0100 [kHz]
Description:	Double of parameter p9690. See there.		
Note:	The setpoint in p9890 is entered in kHz!		
p9891	SI tolerance for SLS / SI tolerance SLS		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: FloatingPoint32
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 0.0050 [kHz]	Max 0.303 [kHz]	Factory setting 0.0130 [kHz]
Description:	Double of parameter p9691. See there.		
Note:	The tolerance in p9891 is entered in kHz!		

p9892	SI response to selecting SLS / SI SLS response		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 0	Max 3	Factory setting 1
Description:	Double of parameter p9692. See there.		
Value:	0: Initiate STO with braking ramp and drive fault when f > f_SLS 1: Activate braking ramp while f > f_SLS 2: STO without braking ramp and with drive fault while f > f_SLS 3: SLS with Ramping from 0Hz		
r9898	SI display checksum / SI act. checksum		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -
Description:	Display of safety checksum for P2 parameters. The checksum changes when safety parameters for P2 are changed (parameter range p9800 - p9892).		
Note:	This checksum must be identical to the value in r9798 before the safety commissioning can be finished via p3900 = 10. If r9898 differs from r9798, the safety parameters on P2 differ from the safety parameters on P1. Check the safety parameters and correct the mistake. The safety commissioning can always be left via p3900 = 11, thus discarding the last changes.		
p9899	SI parameter checksum / SI checksum		
CU240S DP-F	Access level: 3	P-Group: Safety Integrated	Data type: Unsigned16
CU240S PN-F	Quick comm. NO	Active: NO	Data set: -
	Can be changed: -	Calculated: -	
	Min 0000 hex	Max FFFF hex	Factory setting 8AFD hex
Description:	Confirm checksum of the safety parameters.		
Note:	Enter the reading of r9798 or r9898 into p9899 once the safety parametrisation is complete.		
r61000[0...239]	PROFNet Name Of Station / PN name of station		
CU240S PN	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -
Description:	PROFNet name of station. Displays each character in a separate index.		
r61001[0...3]	PROFNet IP Of Station / PN IP adr		
CU240S PN	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -
Description:	PROFNet IP address. Displays e.g. 192.168.0.2 as p61001[0] : 192 p61001[1] : 168 p61001[2] : 0 p61001[3] : 2		

r61002[0...5]	PROFINet MAC Of Station / PN MAC adr		
CU240S PN	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -
Description:	PROFINet MAC address. Displays e.g. 5F-23-AD-F4-5A-22 as p61002[0] : 5F p61002[1] : 23 p61002[2] : AD p61002[3] : F4 p61002[4] : 5A p61002[5] : 22		
r61003[0...3]	PROFINet Default Gateway Of Station / PN Gateway adr		
CU240S PN	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -
Description:	PROFINet default gateway. Displays e.g. 192.168.2.1 as p61003[0] : 192 p61003[1] : 168 p61003[2] : 2 p61003[3] : 1		
r61004[0...3]	PROFINet Subnet Mask Of Station / PN Subnet Mask		
CU240S PN	Access level: 3	P-Group: Communications	Data type: Unsigned16
CU240S PN-F	Unit: -	Calculated: -	Data set: -
Description:	PROFINet subnet mask. Displays e.g. 255.255.255.0 as p61004[0] : 255 p61004[1] : 255 p61004[2] : 255 p61004[3] : 0		

1.3 Command and Drive Data Sets – Overview

1.3.1 Command Data Sets (CDS)

Product: G120, Version: 3202700, Language: eng, Type: CDS

p0700[0...2]	Selection of command source / Command source sel
p0701[0...2]	Function of digital input 0 / Function of DI0
p0702[0...2]	Function of digital input 1 / Function of DI1
p0703[0...2]	Function of digital input 2 / Function of DI2
p0704[0...2]	Function of digital input 3 / Function of DI3
p0705[0...2]	Function of digital input 4 / Function of DI4
p0706[0...2]	Function of digital input 5 / Function of DI5
p0707[0...2]	Function of digital input 6 / Function of DI6
p0708[0...2]	Function of digital input 7 / Function of DI7
p0709[0...2]	Function of digital input 8 / Function of DI8
p0712[0...2]	Analog / digital input 0 / Ana/digi input 0
p0713[0...2]	Analog / digital input 1 / Ana/digi input 1
p0719[0...2]	Selection of cmd. & freq. setp. / Cmd.&freq.setp.sel
p0727[0...2]	Selection of 2/3-wire method / 2/3-wire selection
p0731[0...2]	Bl: Function of digital output 0 / Fct. of DO0
p0732[0...2]	Bl: Function of digital output 1 / Fct. of DO1
p0733[0...2]	Bl: Function of digital output 2 / Fct. of DO2
p0800[0...2]	Bl: Download parameter set 0 / Dwnl.par.set 0
p0801[0...2]	Bl: Download parameter set 1 / Dwnl.par.set 1
p0840[0...2]	Bl: ON/OFF1 / ON/OFF1
p0842[0...2]	Bl: ON reverse/OFF1 / ON reverse/OFF1
p0844[0...2]	Bl: 1. OFF2 / 1. OFF2
p0845[0...2]	Bl: 2. OFF2 / 2. OFF2
p0848[0...2]	Bl: 1. OFF3 / 1. OFF3
p0849[0...2]	Bl: 2. OFF3 / 2. OFF3
p0852[0...2]	Bl: Pulse enable / Pulse enable
p1000[0...2]	Selection of frequency setpoint / Freq setp. select.
p1020[0...2]	Bl: Fixed freq. selection Bit 0 / FF sel. Bit 0
p1021[0...2]	Bl: Fixed freq. selection Bit 1 / FF sel. Bit 1
p1022[0...2]	Bl: Fixed freq. selection Bit 2 / FF sel. Bit 2
p1023[0...2]	Bl: Fixed freq. selection Bit 3 / FF sel. Bit 3
p1035[0...2]	Bl: Enable MOP (UP-command) / Enable MOP(UP)
p1036[0...2]	Bl: Enable MOP (DOWN-command) / Enable MOP(DWN)
p1041[0...2]	Bl: MOP select setpoint automatically/manually / Setp. auto/manu
p1042[0...2]	Cl: MOP auto setpoint / MOP auto setpoint
p1043[0...2]	Bl: MOP accept rampgenerator setpoint / MOP acc RFG setpo
p1044[0...2]	Cl: MOP rampgenerator setpoint / MOP RFG setpoint
p1055[0...2]	Bl: Enable JOG right / Enable JOG ->
p1056[0...2]	Bl: Enable JOG left / Enable JOG <-
p1070[0...2]	Cl: Main setpoint / Main setpoint
p1071[0...2]	Cl: Main setpoint scaling / Main setp scal
p1074[0...2]	Bl: Disable additional setpoint / Disab.add.setp
p1075[0...2]	Cl: Additional setpoint / Add. setpoint
p1076[0...2]	Cl: Additional setpoint scaling / Add. setp.scal
p1110[0...2]	Bl: Inhibit neg. freq. setpoint / Inh. neg. setp
p1113[0...2]	Bl: Reverse / Reverse

p1124[0...2]	BI: Enable JOG ramp times / Enable JOG ramp
p1140[0...2]	BI: RFG enable / RFG enable
p1141[0...2]	BI: RFG start / RFG start
p1142[0...2]	BI: RFG enable setpoint / RFG enable setp
p1218[0...2]	BI: MHB override / MHB override
p1230[0...2]	BI: Enable DC braking / Enable DC brk.
p1330[0...2]	CI: Voltage setpoint / Voltage setp.
p1477[0...2]	BI: Set integrator of n-ctrl. / Set integrator
p1478[0...2]	CI: Set integrator value n-ctrl. / Set int. value
p1492[0...2]	BI: Enable droop / Enable droop
p1500[0...2]	Selection of torque setpoint / Torque setp. sel.
p1501[0...2]	BI: Change to torque control / Change > torq ctrl
p1503[0...2]	CI: Torque setpoint / Torque setp.
p1511[0...2]	CI: Additional torque setpoint / Add. trq. setp
p1522[0...2]	CI: Upper torque limit / Upper trq. lim
p1523[0...2]	CI: Lower torque limit / Lower trq. lim
p2103[0...2]	BI: 1. Faults acknowledgement / 1. Faults ackn
p2104[0...2]	BI: 2. Faults acknowledgement / 2. Faults ackn
p2106[0...2]	BI: External fault / External fault
p2200[0...2]	BI: Enable PID controller / Enab. PID ctrl
p2220[0...2]	BI: Fixed PID setp. select Bit 0 / PID setp->Bit 0
p2221[0...2]	BI: Fixed PID setp. select Bit 1 / PID setp->Bit 1
p2222[0...2]	BI: Fixed PID setp. select Bit 2 / PID setp->Bit 2
p2223[0...2]	BI: Fixed PID setp. select Bit 3 / PID setp->Bit 3
p2235[0...2]	BI: Enable PID-MOP (UP-cmd) / PID-MOP (UP)
p2236[0...2]	BI: Enable PID-MOP (DOWN-cmd) / PID-MOP (DWN)
p2241[0...2]	BI: PID-MOP select setpoint auto/manu / Setp. auto/manu
p2242[0...2]	CI: PID-MOP auto setpoint / PMOP auto setpoint
p2243[0...2]	BI: PID-MOP accept rampgenerator setpoint / PMOP acc RFG setpo
p2244[0...2]	CI: PID-MOP rampgenerator setpoint / PMOP RFG setpoint
p2253[0...2]	CI: PID setpoint / PID setpoint
p2254[0...2]	CI: PID trim source / PID trim source
p2264[0...2]	CI: PID feedback / PID feedback
p2480[0...2]	BI: Enable positioning ramp down / Enable positioning
p2803[0...2]	Enable FastFFBs / Enable FastFFBs

Parameters P0800, P0801, P1522, P1523, P2200 will be altered in the state "Ready" only, all other parameters will be altered during data set switchover (CDS) in the state "Run".

1.3.2 Drive Data Sets (DDS)

Product: G120, Version: 3202700, Language: eng, Type: DDS

p0005[0...2]	Display selection / Display selection
r0035[0...2]	CO: Act. motor temperature / Act. mot.temp.
p0291[0...2]	Inverter protection / Inverter protect.
p0300[0...2]	Select motor type / Select motor type
p0304[0...2]	Rated motor voltage / Rated mot. voltage
p0305[0...2]	Rated motor current / Rated mot. current
p0307[0...2]	Rated motor power / Rated motor power
p0308[0...2]	Rated motor cosPhi / Rated mot. cosPhi
p0309[0...2]	Rated motor efficiency / Rated efficiency
p0310[0...2]	Rated motor frequency / Rated motor freq.
p0311[0...2]	Rated motor speed / Rated motor speed
r0313[0...2]	Motor pole pairs / Motor pole pairs
p0314[0...2]	Motor pole pair number / Motor pole pair no
p0320[0...2]	Motor magnetizing current / Motor magnet. cur.
r0330[0...2]	Rated motor slip / Rated motor slip
r0331[0...2]	Rated magnetization current / Rated magnet. cur.
r0332[0...2]	Rated power factor / Rated power factor
r0333[0...2]	Rated motor torque / Rated motor torque
p0335[0...2]	Motor cooling / Motor cooling
p0340[0...2]	Calculation of motor parameters / Calc of mot.params
p0341[0...2]	Motor inertia [kg*m^2] / Inertia [kg*m^2]
p0342[0...2]	Total/motor inertia ratio / Tot/mot inert.rat.
p0344[0...2]	Motor weight / Motor weight
r0345[0...2]	Motor start-up time / Mot. start-up time
p0346[0...2]	Magnetization time / Magnetization time
p0347[0...2]	Demagnetization time / Demagnet. time
p0350[0...2]	Stator resistance (line) / Stator res. (L)
p0352[0...2]	Cable resistance / Cable resistance
p0354[0...2]	Rotor resistance / Rotor resistance
p0356[0...2]	Stator leakage inductance / Stator leak.induct
p0358[0...2]	Rotor leakage inductance / Rotor leak.induct.
p0360[0...2]	Main inductance / Main inductance
p0362[0...2]	Magnetizing curve flux 1 / Magnet.curve flux1
p0363[0...2]	Magnetizing curve flux 2 / Magnet.curve flux2
p0364[0...2]	Magnetizing curve flux 3 / Magnet.curve flux3
p0365[0...2]	Magnetizing curve flux 4 / Magnet.curve flux4
p0366[0...2]	Magnetizing curve imag 1 / Magnet.curve imag1
p0367[0...2]	Magnetizing curve imag 2 / Magnet.curve imag2
p0368[0...2]	Magnetizing curve imag 3 / Magnet.curve imag3
p0369[0...2]	Magnetizing curve imag 4 / Magnet.curve imag4
r0370[0...2]	Stator resistance [%] / Stator res. [%]
r0372[0...2]	Cable resistance [%] / Cable res. [%]
r0373[0...2]	Rated stator resistance [%] / Rated stat.res.[%]
r0374[0...2]	Rotor resistance [%] / Rotor res. [%]
r0376[0...2]	Rated rotor resistance [%] / Rated rot. res.[%]
r0377[0...2]	Total leakage reactance [%] / Tot.leak.react.[%]
r0382[0...2]	Main reactance [%] / Main reactance [%]
r0384[0...2]	Rotor time constant / Rotor time const.
r0386[0...2]	Total leakage time constant / Total leak. Tconst
p0400[0...2]	Select encoder type / Select enc. type

p0405[0...2]	Enables selection of pulse types / Enables pulse type
p0408[0...2]	Encoder pulses per revolution / Enc pulses per rev
p0410[0...2]	Reverses internal direction sense / Rev dir sense
p0491[0...2]	Reaction on speed signal loss / Select enc. type
p0492[0...2]	Allowed speed difference / Allowed speed dif
p0494[0...2]	Delay speed loss reaction / Dly speed loss rec
p0500[0...2]	Technological application / Techn. application
p0601[0...2]	Motor temperature sensor / Motor temp. sensor
p0604[0...2]	Threshold motor temperature / Thresh. mot. temp.
p0610[0...2]	Motor I2t temperature reaction / I2t temp. reaction
p0621[0...2]	Motor temp. ident after restart / Mot.temp ident.
p0622[0...2]	Magnetizing time for temp id after start up / Magnet. t temp id
r0623[0...2]	CO: Display for the identified stator resistance / Act. stator resist
p0625[0...2]	Ambient motor temperature / Ambient mot. temp.
p0626[0...2]	Overtemperature stator iron / Overtemp.stat.iron
p0627[0...2]	Overtemperature stator winding / Overtemp.stat.wind
p0628[0...2]	Overtemperature rotor winding / Overtemp.rot. wind
r0630[0...2]	CO: Motor model ambient temperature / Mot. model amb. te
r0631[0...2]	CO: Stator iron temperature / Stat.iron temp
r0632[0...2]	CO: Stator winding temperature / Stat.wind.temp
r0633[0...2]	CO: Rotor winding temperature / Rot. wind.temp
p0640[0...2]	Motor overload factor [%] / Motor ovl fact [%]
p1001[0...2]	Fixed frequency 1 / Fixed frequency 1
p1002[0...2]	Fixed frequency 2 / Fixed frequency 2
p1003[0...2]	Fixed frequency 3 / Fixed frequency 3
p1004[0...2]	Fixed frequency 4 / Fixed frequency 4
p1005[0...2]	Fixed frequency 5 / Fixed frequency 5
p1006[0...2]	Fixed frequency 6 / Fixed frequency 6
p1007[0...2]	Fixed frequency 7 / Fixed frequency 7
p1008[0...2]	Fixed frequency 8 / Fixed frequency 8
p1009[0...2]	Fixed frequency 9 / Fixed frequency 9
p1010[0...2]	Fixed frequency 10 / Fixed frequency 10
p1011[0...2]	Fixed frequency 11 / Fixed frequency 11
p1012[0...2]	Fixed frequency 12 / Fixed frequency 12
p1013[0...2]	Fixed frequency 13 / Fixed frequency 13
p1014[0...2]	Fixed frequency 14 / Fixed frequency 14
p1015[0...2]	Fixed frequency 15 / Fixed frequency 15
p1016[0...2]	Fixed frequency mode / FF mode
p1031[0...2]	MOP mode / MOP mode
p1040[0...2]	Setpoint of the MOP / MOP setpoint
p1047[0...2]	MOP ramp-up time of the RFG / MOP ramp-up time
p1048[0...2]	MOP ramp-down time of the RFG / MOP rampdown time
p1058[0...2]	JOG frequency / JOG frequency
p1059[0...2]	JOG frequency left / JOG frequency <-
p1060[0...2]	JOG ramp-up time / JOG ramp-up time
p1061[0...2]	JOG ramp-down time / JOG ramp-down time
p1080[0...2]	Min. frequency / Min. frequency
p1082[0...2]	Max. frequency / Max. frequency
p1091[0...2]	Skip frequency / Skip frequency
p1092[0...2]	Skip frequency 2 / Skip frequency 2
p1093[0...2]	Skip frequency 3 / Skip frequency 3
p1094[0...2]	Skip frequency 4 / Skip frequency 4
p1101[0...2]	Skip frequency bandwidth / Skipfreq bandwidth

p1120[0...2]	Ramp-up time / Ramp-up time
p1121[0...2]	Ramp-down time / Ramp-down time
p1130[0...2]	Ramp-up initial rounding time / Ramp-up ini. Trnd
p1131[0...2]	Ramp-up final rounding time / Ramp-up final Trnd
p1132[0...2]	Ramp-down initial rounding time / Ramp-dwn ini. Trnd
p1133[0...2]	Ramp-down final rounding time / Ramp-dwn fin. Trnd
p1134[0...2]	Rounding type / Rounding type
p1135[0...2]	OFF3 ramp-down time / OFF3 ramp-dwn time
p1202[0...2]	Motor-current: Flying start / Mot. cur: Flystart
p1203[0...2]	Search rate: Flying start / SrchRate: Flystart
p1227[0...2]	Zero speed detection monitoring time / Zero speed time
p1232[0...2]	DC braking current / DC braking current
p1233[0...2]	Duration of DC braking / DC brak. duration
p1234[0...2]	DC braking start frequency / DC brk. start freq
p1236[0...2]	Compound braking current / Compound brk. cur.
p1240[0...2]	Configuration of Vdc controller / Vdc controller
p1243[0...2]	Dynamic factor of Vdc-max / Vdc-max dyn. fact.
p1245[0...2]	Switch on level kin. buffering / KIB ON level
r1246[0...2]	CO: Switch-on level kin buffering / KIB ON level
p1247[0...2]	Dyn. factor of kinetic buffering / Dyn. factor of KIB
p1250[0...2]	Gain of Vdc-controller / Gain of Vdc ctrl.
p1251[0...2]	Integration time Vdc-controller / Int. time Vdc ctrl
p1252[0...2]	Differential time Vdc-controller / Diff.time Vdc ctrl
p1253[0...2]	Vdc-controller output limitation / Vdc ctrl outp. lim
p1256[0...2]	Reaction of kinetic buffering / Reaction of KIB
p1257[0...2]	Freq limit for kinetic buffering / Freq limit for KIB
p1300[0...2]	Control mode / Control mode
p1310[0...2]	Continuous boost / Continuous boost
p1311[0...2]	Acceleration boost / Acceleration boost
p1312[0...2]	Starting boost / Starting boost
p1316[0...2]	Boost end frequency / Boost end freq.
p1320[0...2]	Programmable V/f freq. coord. 1 / V/f freq. coord. 1
p1321[0...2]	Programmable V/f volt. coord. 1 / V/f volt. coord. 1
p1322[0...2]	Programmable V/f freq. coord. 2 / V/f freq. coord. 2
p1323[0...2]	Programmable V/f volt. coord. 2 / V/f volt. coord. 2
p1324[0...2]	Programmable V/f freq. coord. 3 / V/f freq. coord. 3
p1325[0...2]	Programmable V/f volt. coord. 3 / V/f volt. coord. 3
p1333[0...2]	Start frequency for FCC / Start freq for FCC
p1334[0...2]	Slip compensation activation range / Slip c. act. range
p1335[0...2]	Slip compensation / Slip compensation
p1336[0...2]	Slip limit / Slip limit
p1338[0...2]	Resonance damping gain V/f / Res.damp. gain V/f
p1340[0...2]	I _{max} controller prop. gain / I _{max} ctrl prp gain
p1341[0...2]	I _{max} controller integral time / I _{max} ctrl int time
p1345[0...2]	I _{max} voltage ctrl. prop. gain / I _{max} volt prp gain
p1346[0...2]	I _{max} voltage ctrl. integral time / I _{max} volt int time
p1350[0...2]	Voltage soft start / Voltage soft start
p1400[0...2]	Configuration of speed control / Config. of n-ctrl.
p1442[0...2]	Filter time for act. speed / Filter time n_act.
p1452[0...2]	Filter time for act.speed (SLVC) / Act.spd.filt. SLVC
p1460[0...2]	Gain speed controller / Gain of n-ctrl.
p1462[0...2]	Integral time speed controller / T _n of n-ctrl.
p1470[0...2]	Gain speed controller (SLVC) / Gain n-ctrl (SLVC)

p1472[0...2]	Integral time n-ctrl. (SLVC) / Tn of n-ctrl. SLVC
p1488[0...2]	Droop input source / Droop input source
p1489[0...2]	Droop scaling / Droop scaling
p1496[0...2]	Scaling accel. precontrol / Scal acc. prectrl.
p1499[0...2]	Scaling accel. torque control / Scal acc. trq ctrl
p1520[0...2]	CO: Upper torque limit / Upper trq. lim
p1521[0...2]	CO: Lower torque limit / Lower trq. lim
p1525[0...2]	Scaling lower torque limit / Scal. low trq. lim
p1530[0...2]	Motoring power limitation / Motoring power lim
p1531[0...2]	Regenerative power limitation / Regener. power lim
p1570[0...2]	CO: Fixed value flux setpoint / Fval flux setp
p1574[0...2]	Dynamic voltage headroom / Dyn. volt headroom
p1580[0...2]	Efficiency optimization / Efficiency optimiz
p1582[0...2]	Smooth time for flux setpoint / Flux setp. Tsmooth
p1596[0...2]	Int. time field weak. controller / Int.time weak.ctrl
p1610[0...2]	Continuous torque boost (SLVC) / Cont. torque boost
p1611[0...2]	Acc. torque boost (SLVC) / Acc trq boost SLVC
p1654[0...2]	Smooth time for Isq setpoint / Isq setp. Tsmooth
p1715[0...2]	Gain current controller / Gain current ctrl.
p1717[0...2]	Integral time current controller / Int.time cur. ctrl
p1745[0...2]	Flux variance limit in stall / Flux var.lim.stall
p1750[0...2]	Control word of motor model / Motor model CtrlWd
p1752[0...2]	Start-freq. speed adaption (VC with encoder) / Start-freq. (VC)
p1755[0...2]	Start-freq. motor model (SLVC) / Start-freq. (SLVC)
p1756[0...2]	Hyst.-freq. motor model (SLVC) / Hyst. freq. (SLVC)
p1758[0...2]	T(wait) transit to open-loop / T(wait) trans.->OL
p1759[0...2]	T(wait) transit to closed-loop / T(wait) trans.->CL
p1764[0...2]	Kp of n-adaption (SLVC) / Kp n-adapt. (SLVC)
p1767[0...2]	Tn of n-adaption (SLVC) / Tn n-adapt. (SLVC)
p1780[0...2]	Control word of Rs/Rr-adaption / CtrlWd Rs/Rr adapt
p1781[0...2]	Tn of Rs-adaption / Tn of Rs-adaption
p1786[0...2]	Tn of Xm-adaption / Tn of Xm-adaption
p1800[0...2]	Pulse frequency / Pulse frequency
p1803[0...2]	Max. modulation / Max. modulation
p1820[0...2]	Reverse output phase sequence / Rev.outp.phase seq
p1909[0...2]	Ctrl. word of motor data ident. / Ctrl.mot.data id.
p2000[0...2]	Reference frequency / Reference freq.
p2001[0...2]	Reference voltage / Reference voltage
p2002[0...2]	Reference current / Reference current
p2003[0...2]	Reference torque / Reference torque
p2004[0...2]	Reference power / Reference power
p2150[0...2]	Hysteresis frequency f_hys / Hyst. freq. f_hys
p2151[0...2]	Cl: Speed setpoint for messages / n-Set for msg
p2152[0...2]	Delay time of f>fmax / Delay f>fmax
p2153[0...2]	Time-constant speed filter / Tconst. speed filt
p2155[0...2]	Threshold frequency f_1 / Threshold freq f_1
p2156[0...2]	Delay time of threshold freq f_1 / Delay time of f_1
p2157[0...2]	Threshold frequency f_2 / Threshold freq f_2
p2158[0...2]	Delay time of threshold freq f_2 / Delay time of f_2
p2159[0...2]	Threshold frequency f_3 / Threshold freq f_3
p2160[0...2]	Delay time of threshold freq f_3 / Delay time of f_3
p2161[0...2]	Min. threshold for freq. setp. / Setp.min.threshold
p2162[0...2]	Hysteresis freq. for overspeed / Overspd. hyst.freq

p2163[0...2]	Entry freq. for perm. deviation / Entry freq. deviat
p2164[0...2]	Hysteresis frequency deviation / Hyster freq deviat
p2165[0...2]	Delay time permitted deviation / Delay_T perm. dev.
p2166[0...2]	Delay time ramp up completed / Delay_T rampUpCmpl
p2167[0...2]	Switch-off frequency f_off / SwOff freq. f_off
p2168[0...2]	Delay time T_off / Delay time T_off
p2170[0...2]	Threshold current I_thresh / Threshold current
p2171[0...2]	Delay time current / Delay time current
p2172[0...2]	Threshold DC-link voltage / Vdc threshold
p2173[0...2]	Delay time DC-link voltage / Vdc delay time
p2174[0...2]	Torque threshold M_thresh / Torque threshold
p2176[0...2]	Delay time for torque threshold / Delay time torque
p2177[0...2]	Delay time for motor is blocked / Delay_T MotBlocked
p2178[0...2]	Delay time for motor pulled out / Delay_T MotPullOut
p2181[0...2]	Belt failure detection mode / Belt fail detect
p2182[0...2]	Belt threshold frequency 1 / Belt threshold f_1
p2183[0...2]	Belt threshold frequency 2 / Belt threshold f_2
p2184[0...2]	Belt threshold frequency 3 / Belt threshold f_3
p2185[0...2]	Upper torque threshold 1 / Upper trq. thresh1
p2186[0...2]	Lower torque threshold 1 / Lower trq. thresh1
p2187[0...2]	Upper torque threshold 2 / Upper trq. thresh2
p2188[0...2]	Lower torque threshold 2 / Lower trq. thresh2
p2189[0...2]	Upper torque threshold 3 / Upper trq. thresh3
p2190[0...2]	Lower torque threshold 3 / Lower trq. thresh3
p2192[0...2]	Time delay for belt failure / Belt fail delay_T
p2201[0...2]	Fixed PID setpoint 1 / Fixed PID setp. 1
p2202[0...2]	Fixed PID setpoint 2 / Fixed PID setp. 2
p2203[0...2]	Fixed PID setpoint 3 / Fixed PID setp. 3
p2204[0...2]	Fixed PID setpoint 4 / Fixed PID setp. 4
p2205[0...2]	Fixed PID setpoint 5 / Fixed PID setp. 5
p2206[0...2]	Fixed PID setpoint 6 / Fixed PID setp. 6
p2207[0...2]	Fixed PID setpoint 7 / Fixed PID setp. 7
p2208[0...2]	Fixed PID setpoint 8 / Fixed PID setp. 8
p2209[0...2]	Fixed PID setpoint 9 / Fixed PID setp. 9
p2210[0...2]	Fixed PID setpoint 10 / Fixed PID setp. 10
p2211[0...2]	Fixed PID setpoint 11 / Fixed PID setp. 11
p2212[0...2]	Fixed PID setpoint 12 / Fixed PID setp. 12
p2213[0...2]	Fixed PID setpoint 13 / Fixed PID setp. 13
p2214[0...2]	Fixed PID setpoint 14 / Fixed PID setp. 14
p2215[0...2]	Fixed PID setpoint 15 / Fixed PID setp. 15
p2216[0...2]	Fixed PID setpoint mode / Fix.PID Mode
p2231[0...2]	PID-MOP mode / PID-MOP mode.
p2240[0...2]	Setpoint of PID-MOP / Setp. of PID-MOP
p2247[0...2]	PID-MOP ramp-up time of the RFG / PMOP ramp-up time
p2248[0...2]	PID-MOP ramp-down time of the RFG / PMOP rampdown time
p2470[0...2]	Encoder speed scaling factor / Encod speed scal
p2481[0...2]	Gearbox ratio input / Gearbox ratio in
p2482[0...2]	Gearbox ratio output / Gearbox ratio out
p2484[0...2]	No. of shaft turns = 1 Unit / Position ref. unit
p2487[0...2]	Positional error trim value / Positional trim / Positional error
p2488[0...2]	Distance / No. of revolutions / Distance / No. rev

1.4 Connector/Binector (BICO)-Parameters

1.4.1 Binector Input Parameters

Product: G120, Version: 3202700, Language: eng, Type: BI

p0731[0...2]	BI: Function of digital output 0 / Fct. of DO0
p0732[0...2]	BI: Function of digital output 1 / Fct. of DO1
p0733[0...2]	BI: Function of digital output 2 / Fct. of DO2
p0800[0...2]	BI: Download parameter set 0 / Dwnl.par.set 0
p0801[0...2]	BI: Download parameter set 1 / Dwnl.par.set 1
p0806	BI: Inhibit panel access / Inhibit panel acce
p0810	BI: CDS bit 0 (Hand/Auto) / CDS bit 0
p0811	BI: CDS bit 1 / CDS bit 1
p0820	BI: DDS bit 0 / DDS bit 0
p0821	BI: DDS bit 1 / DDS bit 1
p0840[0...2]	BI: ON/OFF1 / ON/OFF1
p0842[0...2]	BI: ON reverse/OFF1 / ON reverse/OFF1
p0844[0...2]	BI: 1. OFF2 / 1. OFF2
p0845[0...2]	BI: 2. OFF2 / 2. OFF2
p0848[0...2]	BI: 1. OFF3 / 1. OFF3
p0849[0...2]	BI: 2. OFF3 / 2. OFF3
p0852[0...2]	BI: Pulse enable / Pulse enable
p1020[0...2]	BI: Fixed freq. selection Bit 0 / FF sel. Bit 0
p1021[0...2]	BI: Fixed freq. selection Bit 1 / FF sel. Bit 1
p1022[0...2]	BI: Fixed freq. selection Bit 2 / FF sel. Bit 2
p1023[0...2]	BI: Fixed freq. selection Bit 3 / FF sel. Bit 3
p1035[0...2]	BI: Enable MOP (UP-command) / Enable MOP(UP)
p1036[0...2]	BI: Enable MOP (DOWN-command) / Enable MOP(DWN)
p1041[0...2]	BI: MOP select setpoint automatically/manually / Setp. auto/manu
p1043[0...2]	BI: MOP accept rampgenerator setpoint / MOP acc RFG setpo
p1055[0...2]	BI: Enable JOG right / Enable JOG ->
p1056[0...2]	BI: Enable JOG left / Enable JOG <-
p1074[0...2]	BI: Disable additional setpoint / Disab.add.setp
p1110[0...2]	BI: Inhibit neg. freq. setpoint / Inh. neg. setp
p1113[0...2]	BI: Reverse / Reverse
p1124[0...2]	BI: Enable JOG ramp times / Enable JOG ramp
p1140[0...2]	BI: RFG enable / RFG enable
p1141[0...2]	BI: RFG start / RFG start
p1142[0...2]	BI: RFG enable setpoint / RFG enable setp
p1218[0...2]	BI: MHB override / MHB override
p1230[0...2]	BI: Enable DC braking / Enable DC brk.
p1477[0...2]	BI: Set integrator of n-ctrl. / Set integrator
p1492[0...2]	BI: Enable droop / Enable droop
p1501[0...2]	BI: Change to torque control / Change > torq ctrl
p2103[0...2]	BI: 1. Faults acknowledgement / 1. Faults ackn
p2104[0...2]	BI: 2. Faults acknowledgement / 2. Faults ackn
p2106[0...2]	BI: External fault / External fault
p2200[0...2]	BI: Enable PID controller / Enab. PID ctrl
p2220[0...2]	BI: Fixed PID setp. select Bit 0 / PID setp->Bit 0
p2221[0...2]	BI: Fixed PID setp. select Bit 1 / PID setp->Bit 1

p2222[0...2]	BI: Fixed PID setp. select Bit 2 / PID setp->Bit 2
p2223[0...2]	BI: Fixed PID setp. select Bit 3 / PID setp->Bit 3
p2235[0...2]	BI: Enable PID-MOP (UP-cmd) / PID-MOP (UP)
p2236[0...2]	BI: Enable PID-MOP (DOWN-cmd) / PID-MOP (DWN)
p2241[0...2]	BI: PID-MOP select setpoint auto/manu / Setp. auto/manu
p2243[0...2]	BI: PID-MOP accept rampgenerator setpoint / PMOP acc RFG setpo
p2480[0...2]	BI: Enable positioning ramp down / Enable positioning
p2810[0...1]	BI: AND 1 / AND 1
p2812[0...1]	BI: AND 2 / AND 2
p2814[0...1]	BI: AND 3 / AND 3
p2816[0...1]	BI: OR 1 / OR 1
p2818[0...1]	BI: OR 2 / OR 2
p2820[0...1]	BI: OR 3 / OR 3
p2822[0...1]	BI: XOR 1 / XOR 1
p2824[0...1]	BI: XOR 2 / XOR 2
p2826[0...1]	BI: XOR 3 / XOR 3
p2828	BI: NOT 1 / NOT 1
p2830	BI: NOT 2 / NOT 2
p2832	BI: NOT 3 / NOT 3
p2834[0...3]	BI: D-FF 1 / D-FF 1
p2837[0...3]	BI: D-FF 2 / D-FF 2
p2840[0...1]	BI: RS-FF 1 / RS-FF 1
p2843[0...1]	BI: RS-FF 2 / RS-FF 2
p2846[0...1]	BI: RS-FF 3 / RS-FF 3
p2849	BI: Timer 1 / Timer 1
p2854	BI: Timer 2 / Timer 2
p2859	BI: Timer 3 / Timer 3
p2864	BI: Timer 4 / Timer 4
p2940	BI: Release Wobble function / Rel Wobble

1.4.2 Connector Input Parameters

Product: G120, Version: 3202700, Language: eng, Type: CI

p0095[0...9]	CI: Display PZD signals / PZD signals
p0771[0...1]	CI: AO / AO
p1042[0...2]	CI: MOP auto setpoint / MOP auto setpoint
p1044[0...2]	CI: MOP rampgenerator setpoint / MOP RFG setpoint
p1070[0...2]	CI: Main setpoint / Main setpoint
p1071[0...2]	CI: Main setpoint scaling / Main setp scal
p1075[0...2]	CI: Additional setpoint / Add. setpoint
p1076[0...2]	CI: Additional setpoint scaling / Add. setp.scal
p1330[0...2]	CI: Voltage setpoint / Voltage setp.
p1478[0...2]	CI: Set integrator value n-ctrl. / Set int. value
p1503[0...2]	CI: Torque setpoint / Torque setp.
p1511[0...2]	CI: Additional torque setpoint / Add. trq. setp
p1522[0...2]	CI: Upper torque limit / Upper trq. lim
p1523[0...2]	CI: Lower torque limit / Lower trq. lim
p2016[0...7]	CI: PZD to USS on RS232 / PZD->USS
p2019[0...7]	CI: PZD to USS on RS485 (USS) / PZD->COM (USS)
p2051[0...7]	CI: PZD to Fieldbus / PZD to FB
p2151[0...2]	CI: Speed setpoint for messages / n-Set for msg
p2242[0...2]	CI: PID-MOP auto setpoint / PMOP auto setpoint
p2244[0...2]	CI: PID-MOP rampgenerator setpoint / PMOP RFG setpoint
p2253[0...2]	CI: PID setpoint / PID setpoint
p2254[0...2]	CI: PID trim source / PID trim source
p2264[0...2]	CI: PID feedback / PID feedback
p2869[0...1]	CI: ADD 1 / ADD 1
p2871[0...1]	CI: ADD 2 / ADD 2
p2873[0...1]	CI: SUB 1 / SUB 1
p2875[0...1]	CI: SUB 2 / SUB 2
p2877[0...1]	CI: MUL 1 / MUL 1
p2879[0...1]	CI: MUL 2 / MUL 2
p2881[0...1]	CI: DIV 1 / DIV 1
p2883[0...1]	CI: DIV 2 / DIV 2
p2885[0...1]	CI: CMP 1 / CMP 1
p2887[0...1]	CI: CMP 2 / CMP 2
p8851[0...7]	CI: PZD to Fieldbus / PZD to FB

1.4.3 Binector Output Parameters

Product: G120, Version: 3202700, Language: eng, Type: BO

r0807.0	BO: Displays client access / Displays client ac
r1025.0	BO: Fixed frequency status / FF Status
r2032.0...15	BO: CtrlWrd1 from USS on RS232 / CtrlWd1 <- USS
r2033.0...15	BO: CtrlWrd2 from USS on RS232 / CtrlWd2 <- USS
r2036.0...15	BO: CtrlWrd1 from USS on RS485 (USS) / CtrlWd 1 <- COM
r2037.0...15	BO: CtrlWrd2 from USS on RS485 (USS) / CtrlWd2 <- COM
r2090.0...15	BO: Control word 1 from Fieldbus / CtrlWd1 <- FB
r2091.0...15	BO: Control word 2 from Fieldbus / CtrlWd2 <- FB
r2225.0	BO: PID Fixed frequency status / PID FF Status
r2811.0	BO: AND 1 / AND 1
r2813.0	BO: AND 2 / AND 2
r2815.0	BO: AND 3 / AND 3
r2817.0	BO: OR 1 / OR 1
r2819.0	BO: OR 2 / OR 2
r2821.0	BO: OR 3 / OR 3
r2823.0	BO: XOR 1 / XOR 1
r2825.0	BO: XOR 2 / XOR 2
r2827.0	BO: XOR 3 / XOR 3
r2829.0	BO: NOT 1 / NOT 1
r2831.0	BO: NOT 2 / NOT 2
r2833.0	BO: NOT 3 / NOT 3
r2835.0	BO: Q D-FF 1 / Q D-FF 1
r2836.0	BO: NOT-Q D-FF 1 / NOT-Q D-FF 1
r2838.0	BO: Q D-FF 2 / Q D-FF 2
r2839.0	BO: NOT-Q D-FF 2 / NOT-Q D-FF 2
r2841.0	BO: Q RS-FF 1 / Q RS-FF 1
r2842.0	BO: NOT-Q RS-FF 1 / NOT-Q RS-FF 1
r2844.0	BO: Q RS-FF 2 / Q RS-FF 2
r2845.0	BO: NOT-Q RS-FF 2 / NOT-Q RS-FF 2
r2847.0	BO: Q RS-FF 3 / Q RS-FF 3
r2848.0	BO: NOT-Q RS-FF 3 / NOT-Q RS-FF 3
r2852.0	BO: Timer 1 / Timer 1
r2853.0	BO: Nout timer 1 / Nout timer 1
r2857.0	BO: Timer 2 / Timer 2
r2858.0	BO: Nout timer 2 / Nout timer 2
r2862.0	BO: Timer 3 / Timer 3
r2863.0	BO: Nout timer 3 / Nout timer 3
r2867.0	BO: Timer 4 / Timer 4
r2868.0	BO: Nout timer 4 / Nout timer 4
r2886.0	BO: CMP 1 / CMP 1
r2888.0	BO: CMP 2 / CMP 2
r8890.0...15	BO: Control word 1 from Fieldbus / CtrlWd1 <- FB
r8891.0...15	BO: Control word 2 from Fieldbus / CtrlWd2 <- FB

1.4.4 Connector Output Parameters

Product: G120, Version: 3202700, Language: eng, Type: CO

r0020	CO: Freq. setpoint before RFG / Setp before RFG
r0021	CO: Act. filtered frequency / Act. filt. freq.
r0024	CO: Act. filt. output frequency / Act. outp. freq
r0025	CO: Act. output voltage / Act.outp. volt
r0026[0...1]	CO: Act. filtered DC-link volt. / Act. fil. Vdc
r0027	CO: Act. output current / Act. outp. cur
r0029	CO: Flux gen. current / Flux gen. cur.
r0030	CO: Torque gen. current / Torque gen.cur
r0031	CO: Act. filtered torque / Act fil torque
r0032	CO: Act. filtered power / Act fil. power
r0035[0...2]	CO: Act. motor temperature / Act. mot.temp.
r0036	CO: Inverter overload utilization / Invert ovl util
r0037[0...4]	CO: Inverter temperature [°C] / Inverter temp.
r0038	CO: Fil. power factor / Fil.power fact
r0039	CO: Energy consumpt. meter [kWh] / Energy meter
r0051[0...1]	CO: Active Drive Dataset (DDS) / Active DDS
r0061	CO: Act. rotor speed / Act rotor speed
r0062	CO: Freq. setpoint / Freq. setpoint
r0063	CO: Act. frequency / Act. frequency
r0064	CO: Dev. frequency controller / Dev. freq ctrl
r0065	CO: Slip frequency / Slip frequency
r0066	CO: Act. output frequency / Act. outp freq
r0067	CO: Act. output current limit / Outp cur limit
r0068	CO: Output current / Output current
r0069[0...5]	CO: Act. phase currents / Act. phase cur
r0070	CO: Act. DC-link voltage / Act. Vdc
r0071	CO: Max. output voltage / Max. outp.volt
r0072	CO: Act. output voltage / Act. outp.volt
r0074	CO: Act. modulation / Act modulation
r0075	CO: Current setpoint Isd / Cur. setp. Isd
r0076	CO: Act. current Isd / Act. cur. Isd
r0077	CO: Current setpoint Isq / Cur. setp. Isq
r0078	CO: Act. current Isq / Act. cur. Isq
r0079	CO: Torque setpoint (total) / Total trq setp
r0080	CO: Act. torque / Act. torque
r0084	CO: Act. air gap flux / Air gap flux
r0085	CO: Act. re-active current / Act.re-active cur
r0086	CO: Act. active current / Act.active cur
r0087	CO: Act. power factor / Act.power fact
r0090	CO: Act. rotor angle / Act rotor angle
r0094	CO: Transformation angle / Transf. angle
r0394	CO: Stator resistance IGBT [%] / Stat. res.IGBT
r0395	CO: Total stator resistance [%] / Total stat.res
r0396	CO: Act. rotor resistance / Act rotor res.
r0485	CO: Encoder counter value / Encoder count val.
r0623[0...2]	CO: Display for the identified stator resistance / Act. stator resist
r0630[0...2]	CO: Motor model ambient temperature / Mot. model amb. te
r0631[0...2]	CO: Stator iron temperature / Stat.iron temp
r0632[0...2]	CO: Stator winding temperature / Stat.wind.temp

r0633[0...2]	CO: Rotor winding temperature / Rot. wind.temp
r0755[0...1]	CO: Act. AI after scal. [4000h] / CO:AI scal[4000h]
r0947[0...63]	CO: Last fault code / Last fault code
r0949[0...63]	CO: Fault value / Fault value
r1024	CO: Act. fixed frequency / Act. FF
r1045	CO: MOP input frequency of the RFG / MOP RFG input
r1050	CO: Act. Output freq. of the MOP / MOP outp.freq.
r1078	CO: Total frequency setpoint / Tot. freq.setp
r1079	CO: Selected frequency setpoint / Sel. freq.setp
r1114	CO: Freq. setp. after dir. ctrl. / Setp<-dir.ctrl.
r1119	CO: Freq. setpoint before RFG / Setp before RFG
r1170	CO: Frequency setpoint after RFG / Setp. after RFG
r1242	CO: Switch-on level of Vdc-max / Vdc-max ON lev
r1246[0...2]	CO: Switch-on level kin buffering / KIB ON level
r1315	CO: Total boost voltage / Total boost V
r1337	CO: V/f slip frequency / V/f slip freq.
r1343	CO: I _{max} controller freq. output / I _{max} ctrl Foutp
r1344	CO: I _{max} controller volt. output / I _{max} ctrl Voutp
r1438	CO: Freq. setpoint to controller / Freq. setp ctl
r1445	CO: Act. filtered frequency / Act. filt freq
r1482	CO: Integral output of n-ctrl. / Int.outp n-ctrl
r1490	CO: Droop frequency / Droop freq.
r1508	CO: Torque setpoint / Torque setp.
r1515	CO: Additional torque setpoint / Add. trq. setp
r1518	CO: Acceleration torque / Accel. torque
p1520[0...2]	CO: Upper torque limit / Upper trq. lim
p1521[0...2]	CO: Lower torque limit / Lower trq. lim
r1526	CO: Upper torque limitation / Upper trq. lim
r1527	CO: Lower torque limitation / Lower trq. lim
r1536	CO: Max. trq. motoring current / Max trq mot cur
r1537	CO: Max trq regenerative current / Max trq reg cur
r1538	CO: Upper torque limit (total) / Total up TrqLim
r1539	CO: Lower torque limit (total) / Total lw TrqLim
p1570[0...2]	CO: Fixed value flux setpoint / Fval flux setp
r1583	CO: Flux setpoint (smoothed) / Smoothed setp.
r1597	CO: Outp. field weak. controller / Outp.weak. ctrl
r1598	CO: Flux setpoint (total) / Total flux setp
r1718	CO: Output of Isq controller / Outp. Isq ctrl
r1719	CO: Integral output of Isq ctrl. / Int. outp. Isq
r1723	CO: Output of Isd controller / Outp. Isd ctrl
r1724	CO: Integral output of Isd ctrl. / Int. outp. Isd
r1725	CO: Integral limit of Isd ctrl. / Int. limit Isd
r1728	CO: Decoupling voltage / Decoupl. volt
r1746	CO: Actual flux variance / Act. flux variance
r1770	CO: Prop. output of n-adaption / Prop outp n-ad
r1771	CO: Int. output of n-adaption / Int. outp n-ad
r1778	CO: Flux angle difference / Flux angle diff
r1782	CO: Output of Rs-adaptation / Output Rs-adaption
r1787	CO: Output of Xm-adaption / Outp. Xm-adaption
r1801[0...1]	CO: Pulse frequency / Pulse frequency
r2015[0...7]	CO: PZD from USS on RS232 / PZD<-USS
r2018[0...7]	CO: PZD from USS on RS485 / PZD<-COM(USS)
r2050[0...7]	CO: PZD from Fieldbus / PZD from FB

r2059[0...4]	CO: Displays SOL link stats for Sol Master. / Disp SOL stats
r2110[0...3]	CO: Warning number / Warning number
r2131	CO: Last fault number code / Last fault code
r2132	CO: First warning number code / First warning code
r2169	CO: Act. filtered frequency / Act. filt. freq
r2224	CO: Act. fixed PID setpoint / Fixed.PID setp
r2245	CO: PID-MOP input frequency of the RFG / PMOP RFG input
r2250	CO: Output setpoint of PID-MOP / PMOP outp. setp
r2260	CO: PID setpoint after PID-RFG / PID setp <-RFG
r2262	CO: Filtered PID setp. after RFG / Filt. PID setp
r2266	CO: PID filtered feedback / PID filt.fdbck
r2272	CO: PID scaled feedback / PID scal fdbck
r2273	CO: PID error / PID error
r2294	CO: Act. PID output / Act.PID output
r2477	CO: Act. scaled encoder speed / Act scal enc speed
r2478	CO: Act. scaled encoder frequency / Act scal enc freq
r2489[0...2]	CO: Tracking parameter / Track / Tracking parameter
r2870	CO: ADD 1 / ADD 1
r2872	CO: ADD 2 / ADD 2
r2874	CO: SUB 1 / SUB 1
r2876	CO: SUB 2 / SUB 2
r2878	CO: MUL 1 / MUL 1
r2880	CO: MUL 2 / MUL 2
r2882	CO: DIV 1 / DIV 1
r2884	CO: DIV 2 / DIV 2
p2889	CO: Fixed setpoint 1 in [%] / Fixed setp 1 %
p2890	CO: Fixed setpoint 2 in [%] / Fixed setp 2 %
r2955	CO: Wobble signal output / Wobble output
r8850[0...7]	CO: PZD from Fieldbus / PZD from FB
r9660	CO: SI remain time until forc dynam / SI remaining time

1.4.5 Connector/Binector Output Parameters

Product: G120, Version: 3202700, Language: eng, Type: CO/BO

r0019.0...14	CO/BO: BOP control word / BOP CtrlWd
r0050	CO/BO: Active Command Dataset / Active CDS
r0052.0...15	CO/BO: Act. status word 1 / Act StatWd1
r0053.0...15	CO/BO: Act. status word 2 / Act StatWd2
r0053.1...15	CO/BO: Act. status word 2 / Act StatWd2
r0054.0...15	CO/BO: Act. control word 1 / Act CtrlWd1
r0055.0...15	CO/BO: Act. control word 2 / Act CtrlWd2
r0056.0...15	CO/BO: Status of motor control / Stat MotCtrl
r0056.0...13	CO/BO: Status of motor control / Stat MotCtrl
r0403.0...4	CO/BO: Encoder status word / Enc. StatWd
r0722.0...12	CO/BO: Binary input values / Bin.inp.val
r0747.0...2	CO/BO: State of digital outputs / State DOs
r0751.0...9	CO/BO: Status word of AI / AI status Wd
r0785.0...1	CO/BO: Status word of AO / AO stat Wd
r1407.0...15	CO/BO: Status 2 of motor control / Stat 2 ctrl
r1751.0...15	CO/BO: Status word of motor model / Motor model StatWd
r2197.0...12	CO/BO: Monitoring word 1 / Monitor Wd1
r2198.0...12	CO/BO: Monitoring word 2 / Monitor Wd2
r3113.0...15	CO/BO: Fault Bit Array / Fault Bit Array
r9620.0...13	CO/BO: SI status word / SI StatWd
r9771.0...1	CO/BO: SI hardware functions / SI hw functions
r9772.0...15	CO/BO: SI status word / SI StatWd
r9820.0...13	CO/BO: SI status word / SI StatWd

1.5 Quick commissioning (P0010 = 1)

The following parameters are necessary for quick commissioning (P0010 = 1).

Table 1-2 Quick commissioning (P0010 = 1)

Par.-No.	Name	Access level	Can be changed
P0100	Europe / North America	1	C
P0205	Inverter application	3	C
P0230	Output filter	1	C
P0233	Filter inductance	1	C
P0234	Filter capacity	1	C
P0300	Select motor type	2	C
P0304	Rated motor voltage	1	C
P0305	Rated motor current	1	C
P0307	Rated motor power	1	C
P0308	Rated motor cosPhi	1	C
P0309	Rated motor efficiency	1	C
P0310	Rated motor frequency	1	C
P0311	Rated motor speed	1	C
P0314	Motor pole pair number	3	C
P0320	Motor magnetizing current	3	CT
P0335	Motor cooling	2	CT
P0400	Select encoder type	2	CT
P0408	Encoder pulses per revolution	2	CT
P0500	Technological application	3	CT
P0625	Ambiant motor temperature	3	CUT
P0640	Motor overload factor [%]	2	CUT
P0700	Selection of command source	1	CT
P0727	Selection of 2/3-wire method	2	CT
P1000	Selection of frequency setpoint	1	CT

Table 1-2 Quick commissioning (P0010 = 1)

Par.-No.	Name	Access level	Can be changed
P1080	Min. frequency	1	CUT
P1082	Max. frequency	1	CT
P1120	Ramp-up time	1	CUT
P1121	Ramp-down time	1	CUT
P1135	OFF3 ramp-down time	2	CUT
P1300	Control mode	2	CT
P1500	Selection of torque setpoint	2	CT
P1900	Select motor data identification	2	CT
P1960	Speed control optimisation	3	CT
P3900	End of quick commissioning	1	C

When P0010 = 1 is chosen, P0003 (user access level) can be used to select the parameters to be accessed. This parameter also allows selection of a user-defined parameter list.

At the end of the quick commissioning sequence, set P3900 = 1 to carry out the necessary motor calculations and clear all other parameters (not included in P0010 = 1) to their default settings.

Note

This applies only in Quick Commissioning mode.

Function diagrams

2

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2.2 Symbols in function diagrams

Function diagrams

0010 – Symbols in function diagrams

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Explanation of symbols used in the function diagrams

Setting parameters

- Parameter text
- Min ... Max [Dim]
- PNNumber.C/D [3] (Default)

Monitoring parameters

- Parameter text [Unit]
- PNNumber.C/D [3]

BICO parameters

- Binector input (Setting parameter)**
 - Parameter text [Unit]
 - Parameter number.Command/Drive data set (Default)
- Binector output (Monitoring parameter)**
 - Parameter text
 - Parameter number
- Connector input (Setting parameter)**
 - Parameter text
 - PNNum.C/D [3] (Default)
- Connector output (Monitoring parameter)**
 - Parameter text [Unit]
 - Parameter number [Number indexes]
- Connector/Binector output (Monitoring parameter)**
 - Parameter text
 - Parameter number

Sheet 2300 Details refer to sheet 2300

1 Reference signal between function diagrams

1	2	3	4	5	6	7	8
						Function diagram	
						0010_Symbols.vsd	
						10.04.2008	
						V3.2	
						SINAMICS G120	
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Fig. 2-1 0010 – Symbols in function diagrams

2.3 Overview

Function plans

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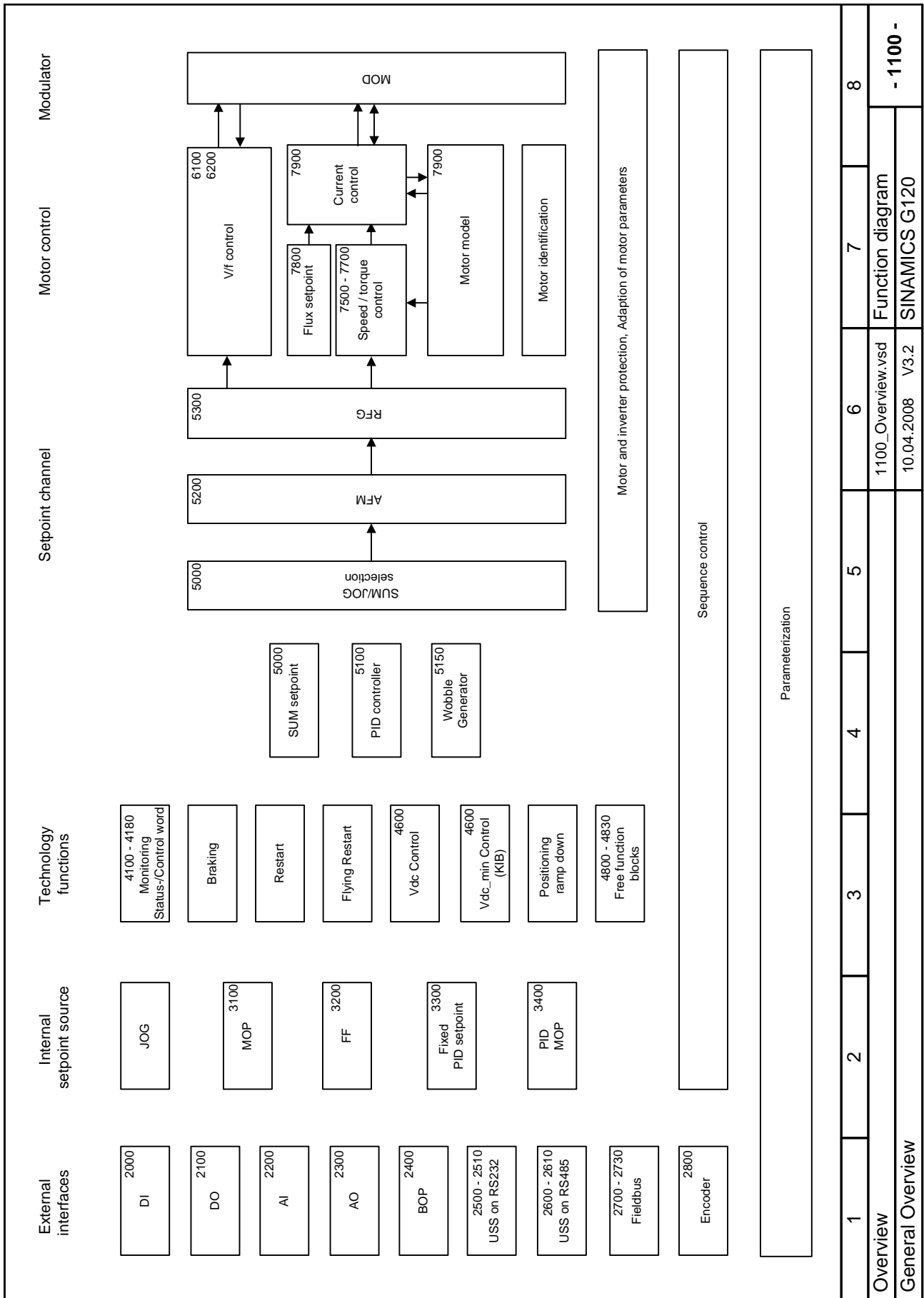


Fig. 2-2 1100 – General Overview

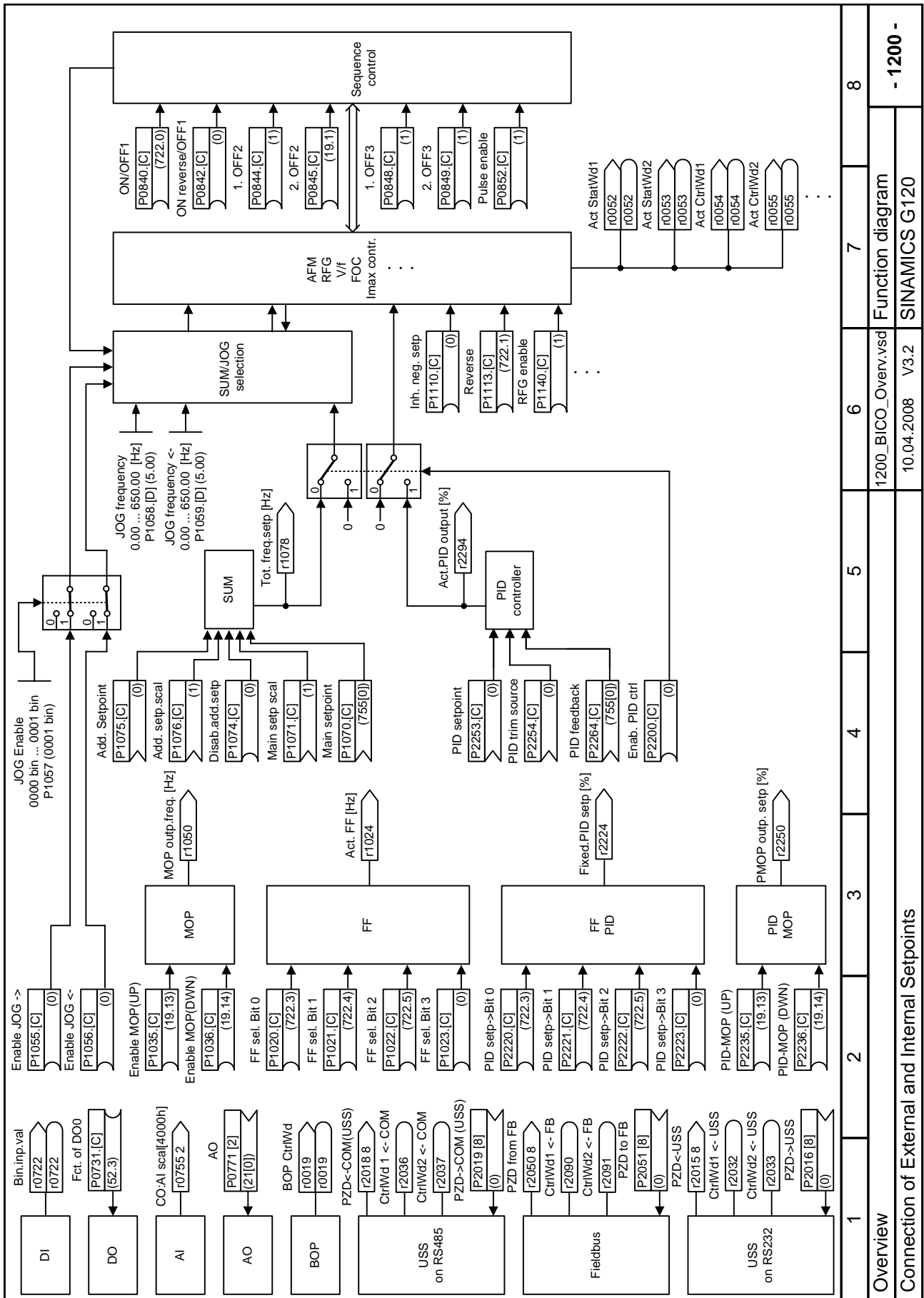


Fig. 2-3 1200 – Connection of External and Internal Setpoints

2.4 External Interfaces

Function diagrams

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2710 – PROFIBUS, Transmitting	2-332
2720 – PROFINet, Receiving	2-333
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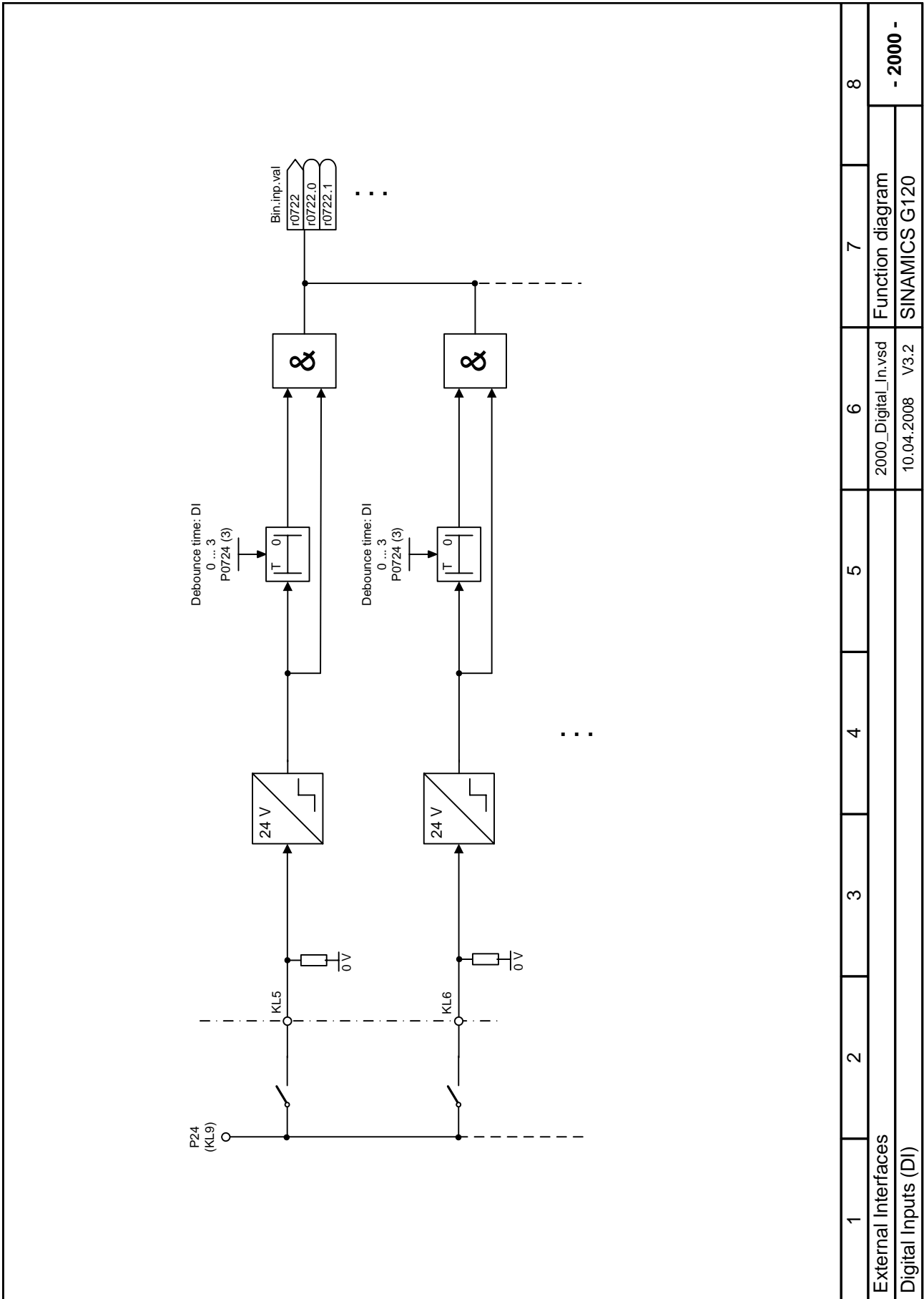


Fig. 2-4 2000 – Digital Inputs (DI)

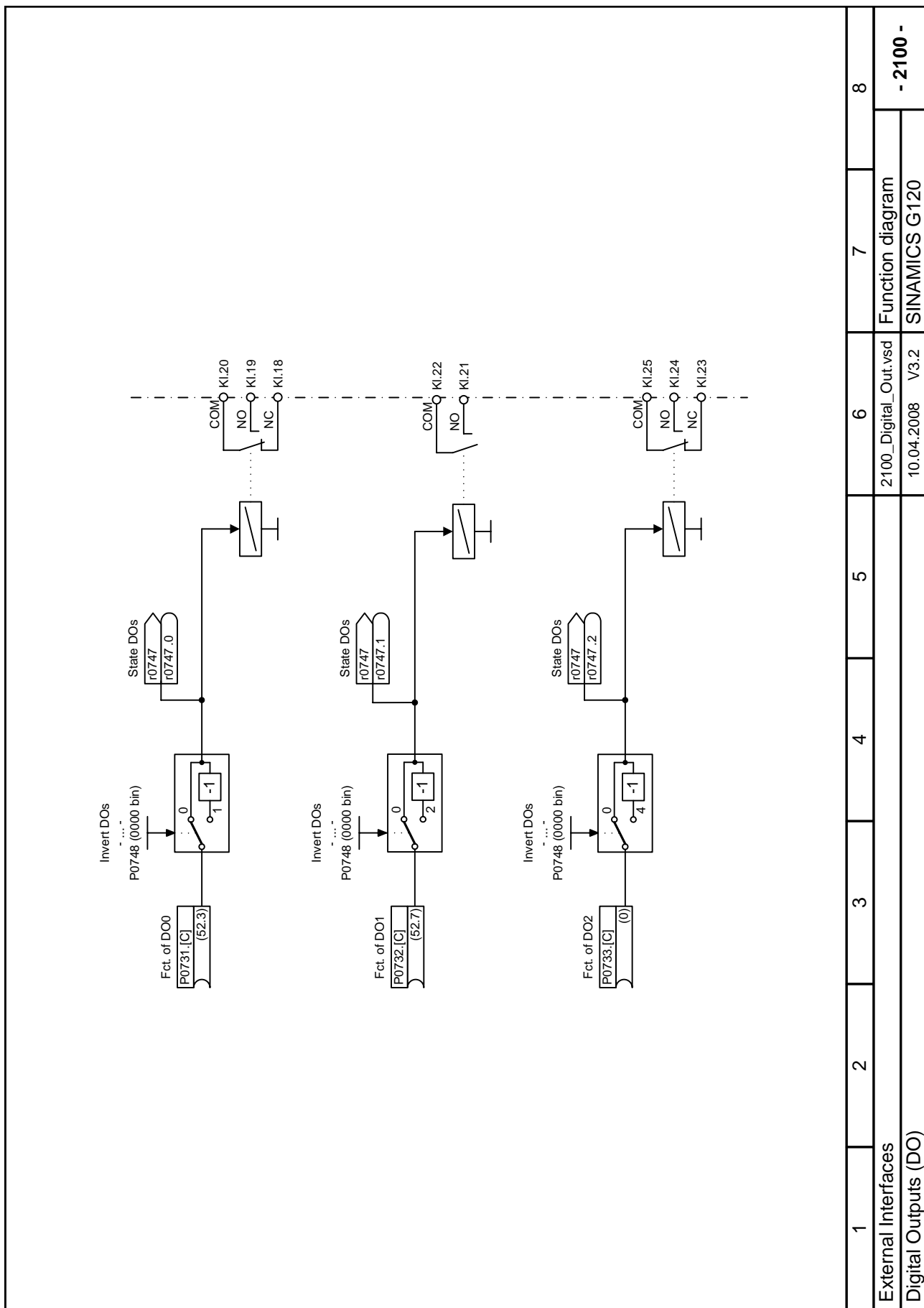


Fig. 2-5 2100 – Digital Outputs (DO)

1	2	3	4	5	6	7	8
External Interfaces					2100_Digital_Out.vsd	Function diagram	
Digital Outputs (DO)					10.04.2008 V3.2	SINAMICS G120	
							- 2100 -

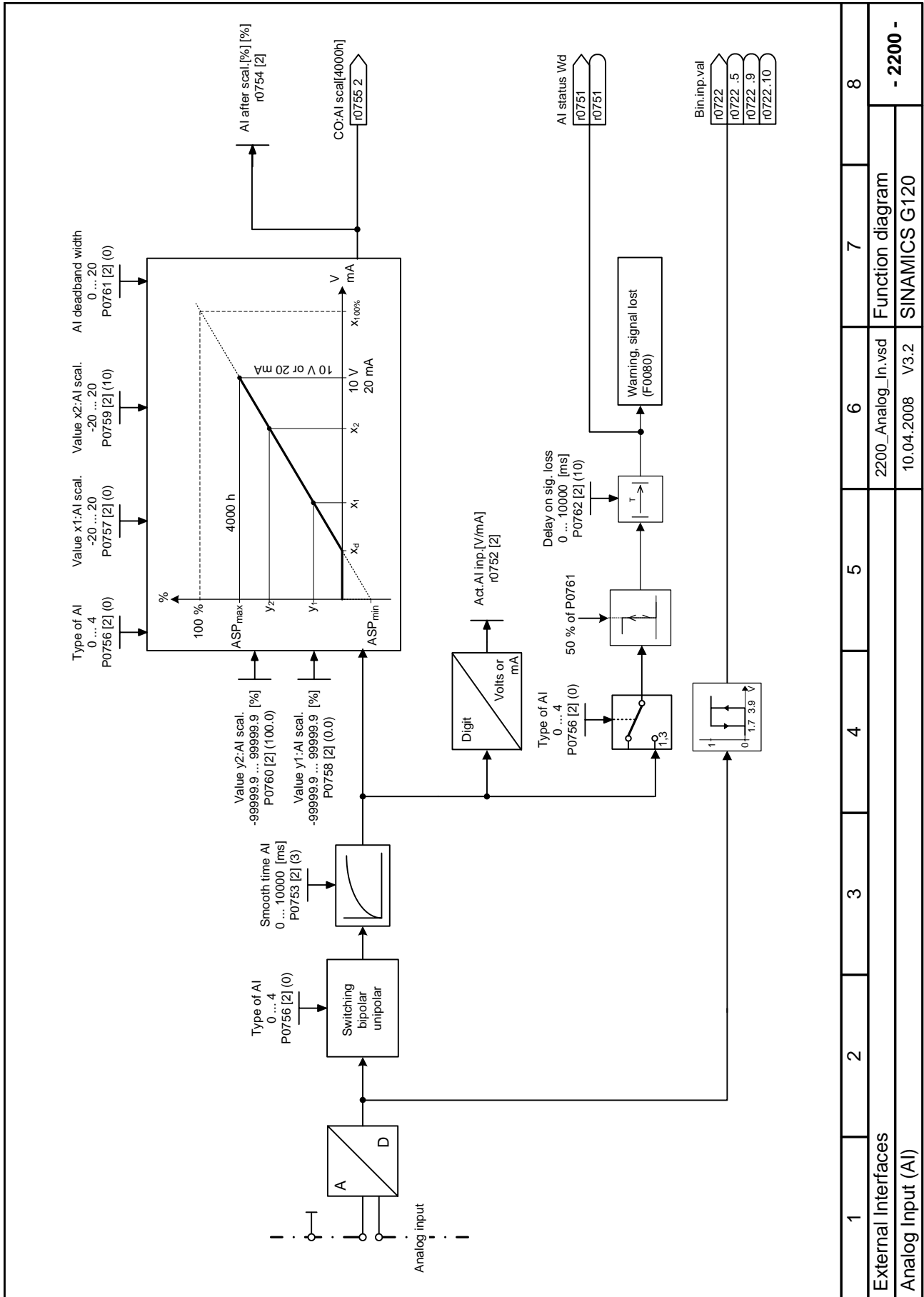


Fig. 2-6 2200 – Analog Input (AI)

1	2	3	4	5	6	7	8
External Interfaces							
Analog Input (AI)							
2200_Analog_in.vsd						Function diagram	
10.04.2008						V3.2	
						- 2200 -	
						SINAMICS G120	

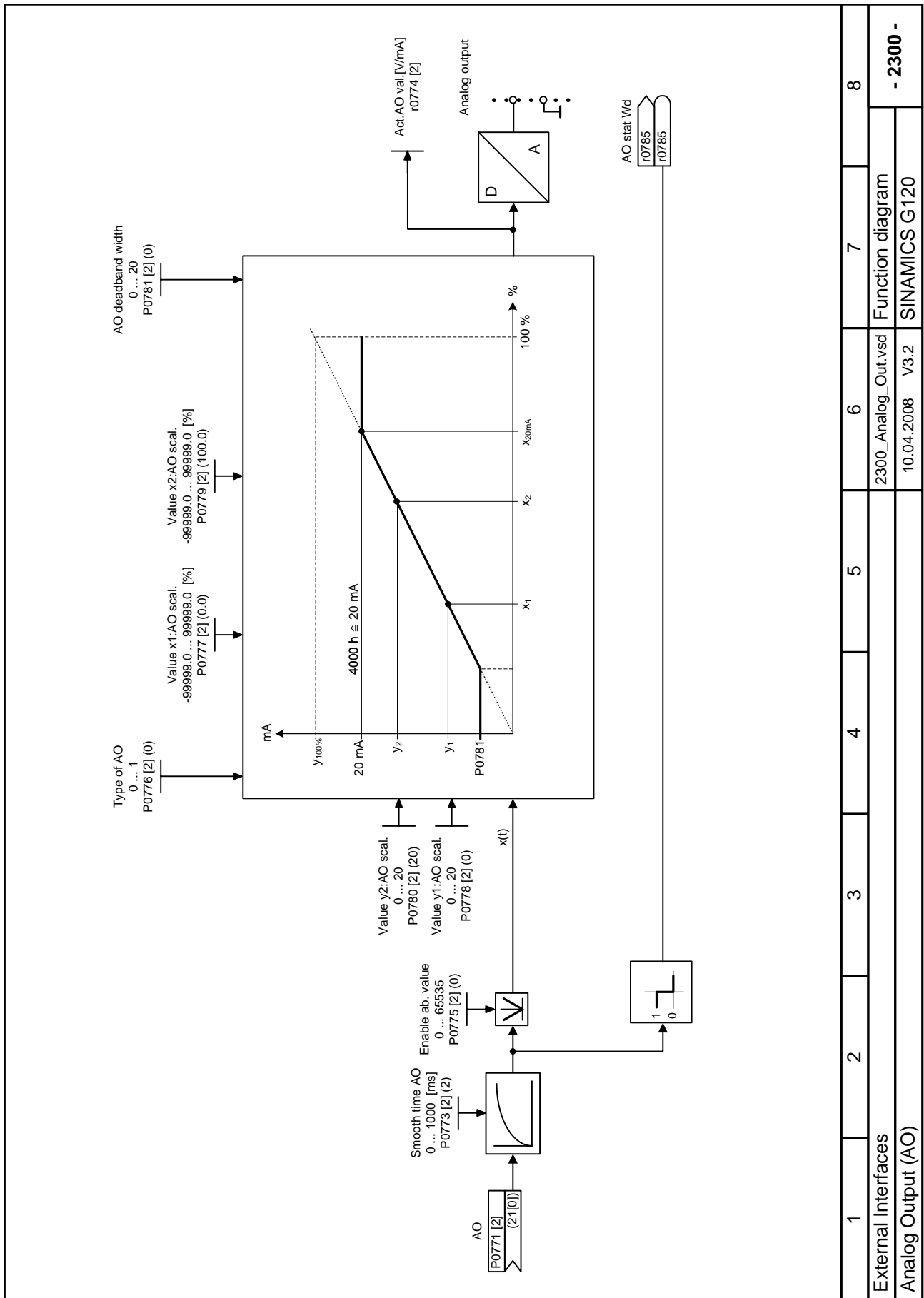


Fig. 2-7 2300 – Analog Output (AO)

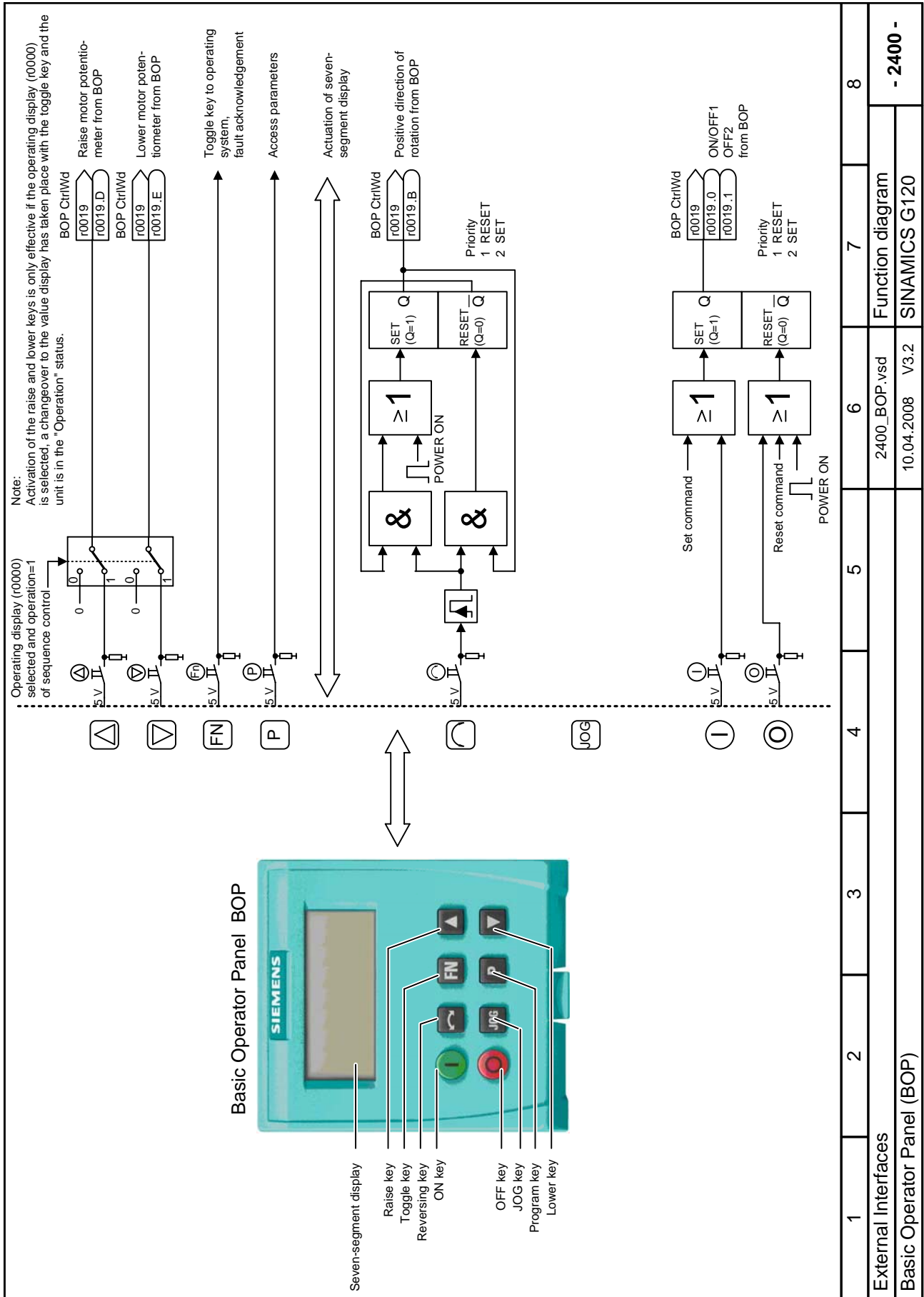


Fig. 2-8 2400 – Basic Operator Panel (BOP)

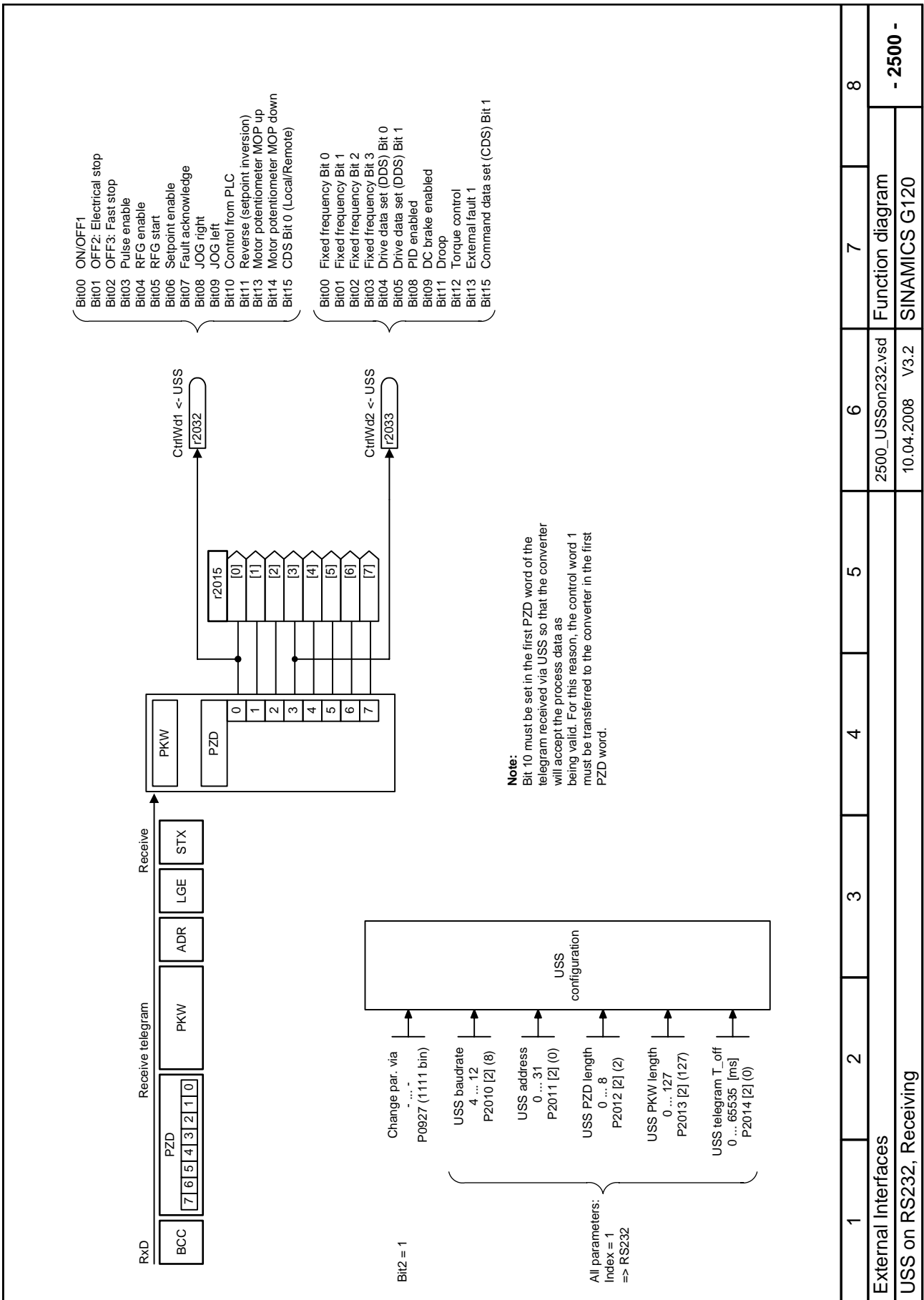


Fig. 2-9 2500 – USS on RS232, Receiving

1	2	3	4	5	6	7	8
External Interfaces							
USS on RS232, Receiving							
2500_USSon232.vsd						Function diagram	
10.04.2008 V3.2						- 2500 -	
SINAMICS G120							

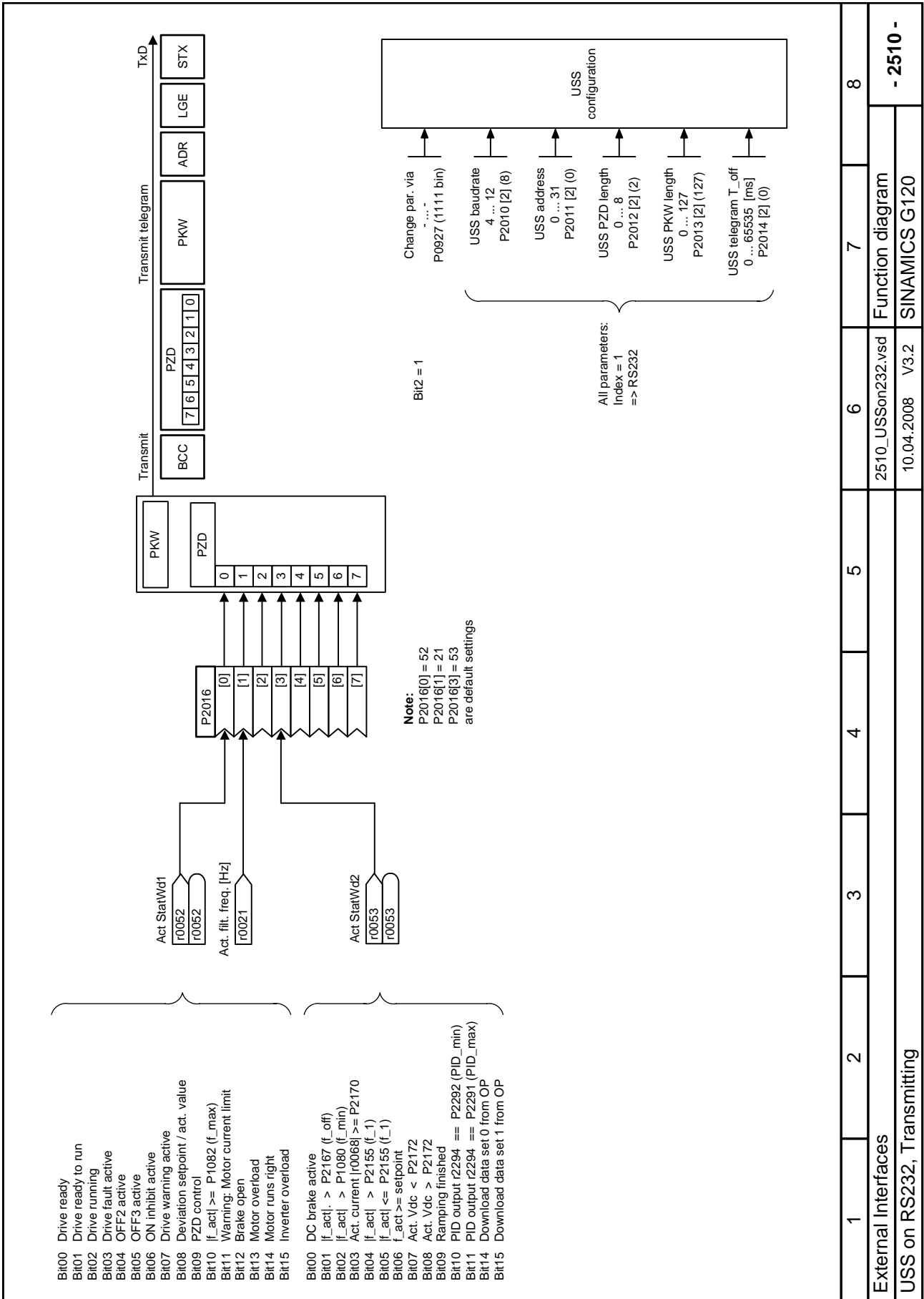


Fig. 2-10 2510 – USS on RS232, Transmitting

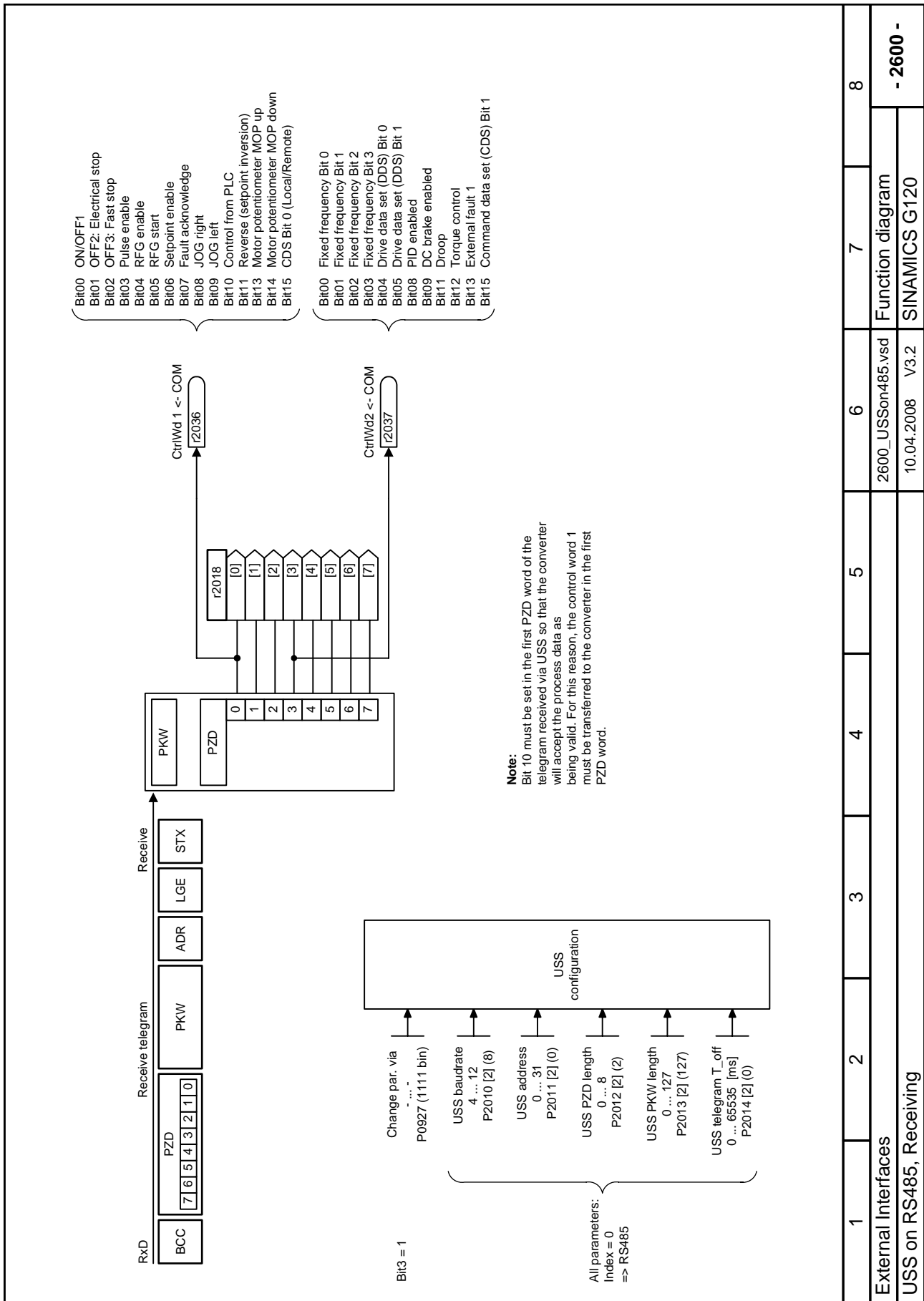


Fig. 2-11 2600 – USS on RS485, Receiving

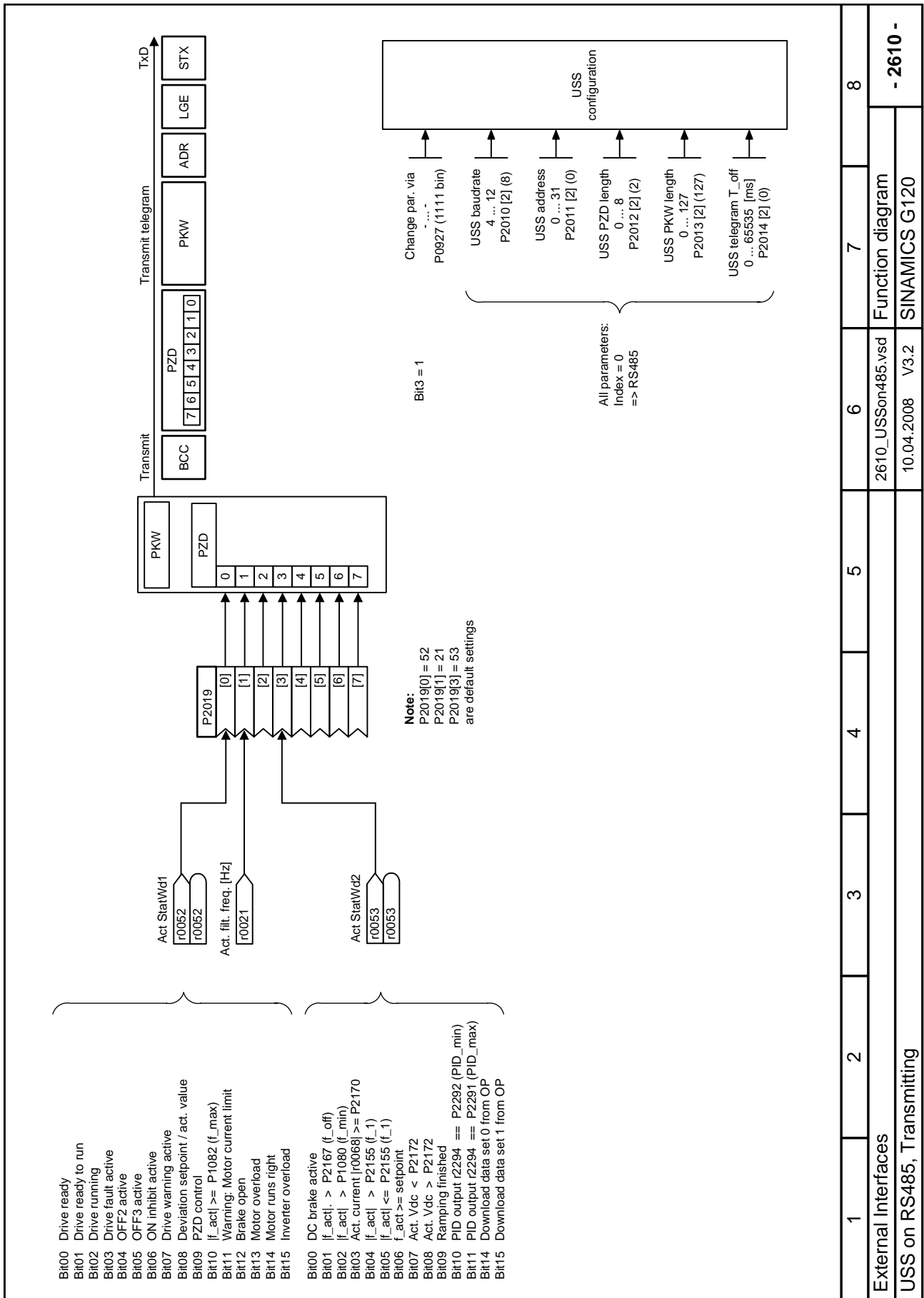


Fig. 2-12 2610 – USS on RS485, Transmitting

1	2	3	4	5	6	7	8
External interfaces							
2610_USSon485.vsd						Function diagram	
10.04.2008 V3.2						SINAMICS G120	
- 2610 -							

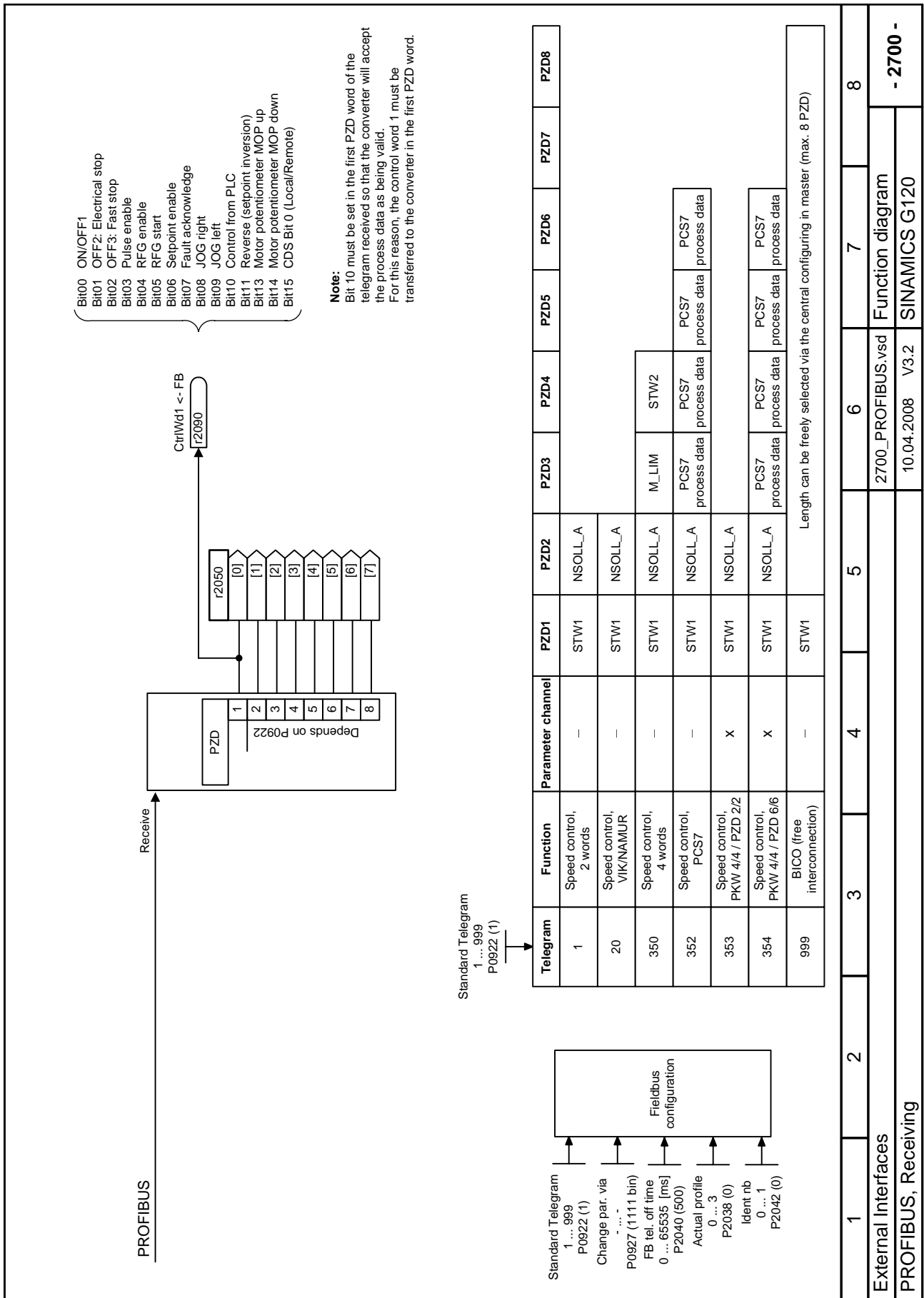


Fig. 2-13 2700 – PROFIBUS, Receiving

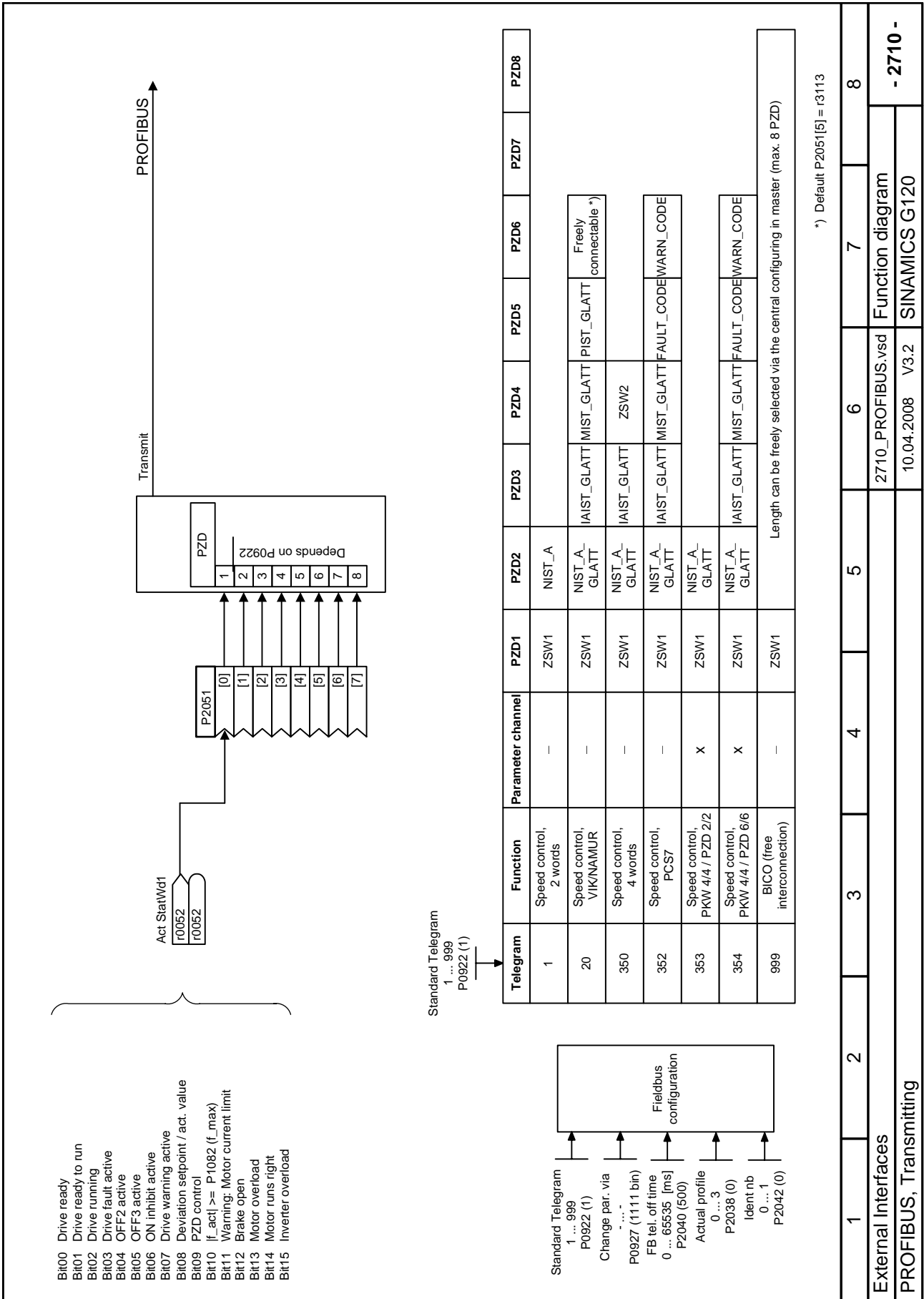


Fig. 2-14 2710 – PROFIBUS, Transmitting

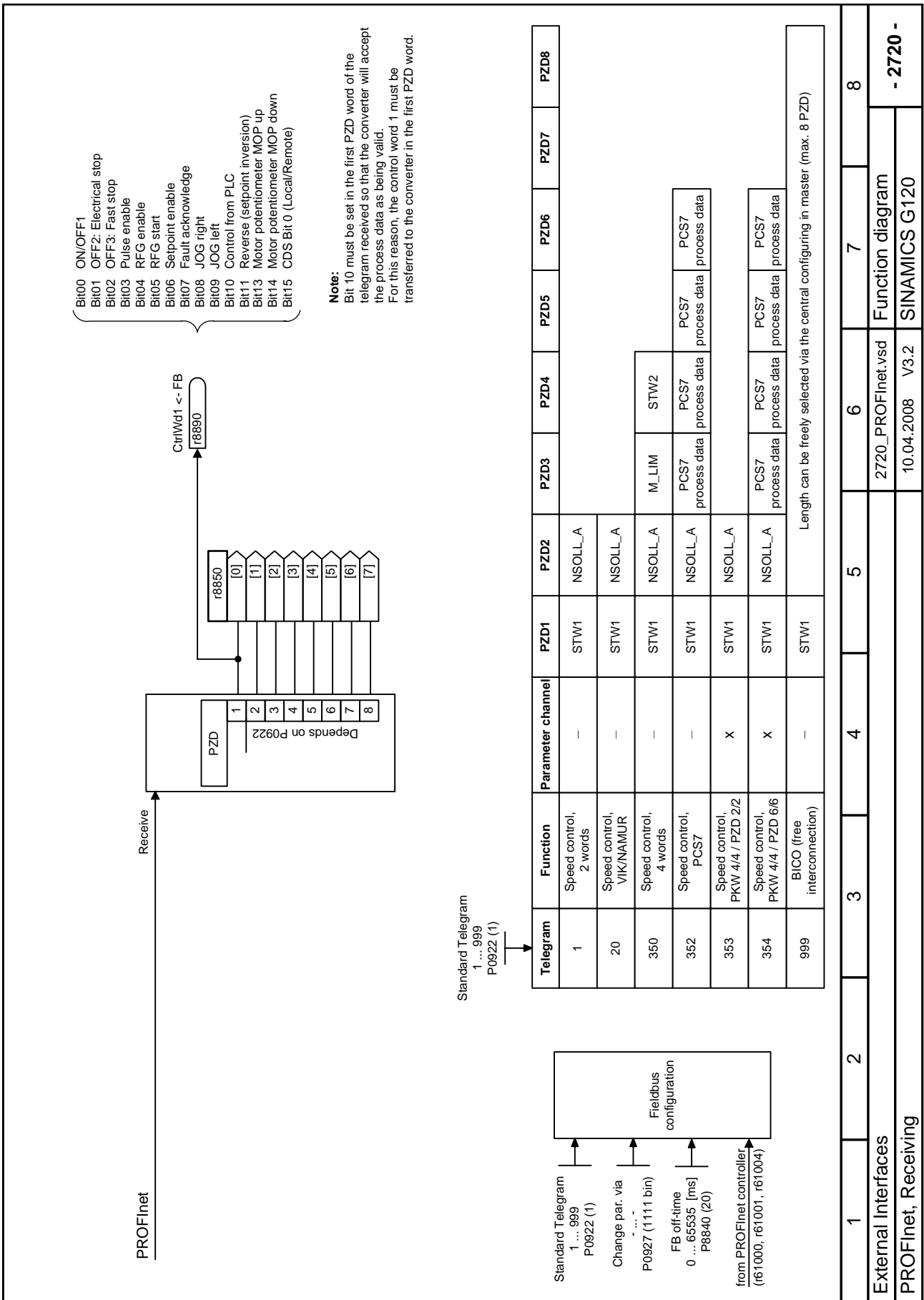


Fig. 2-15 2720 – PROFinet, Receiving

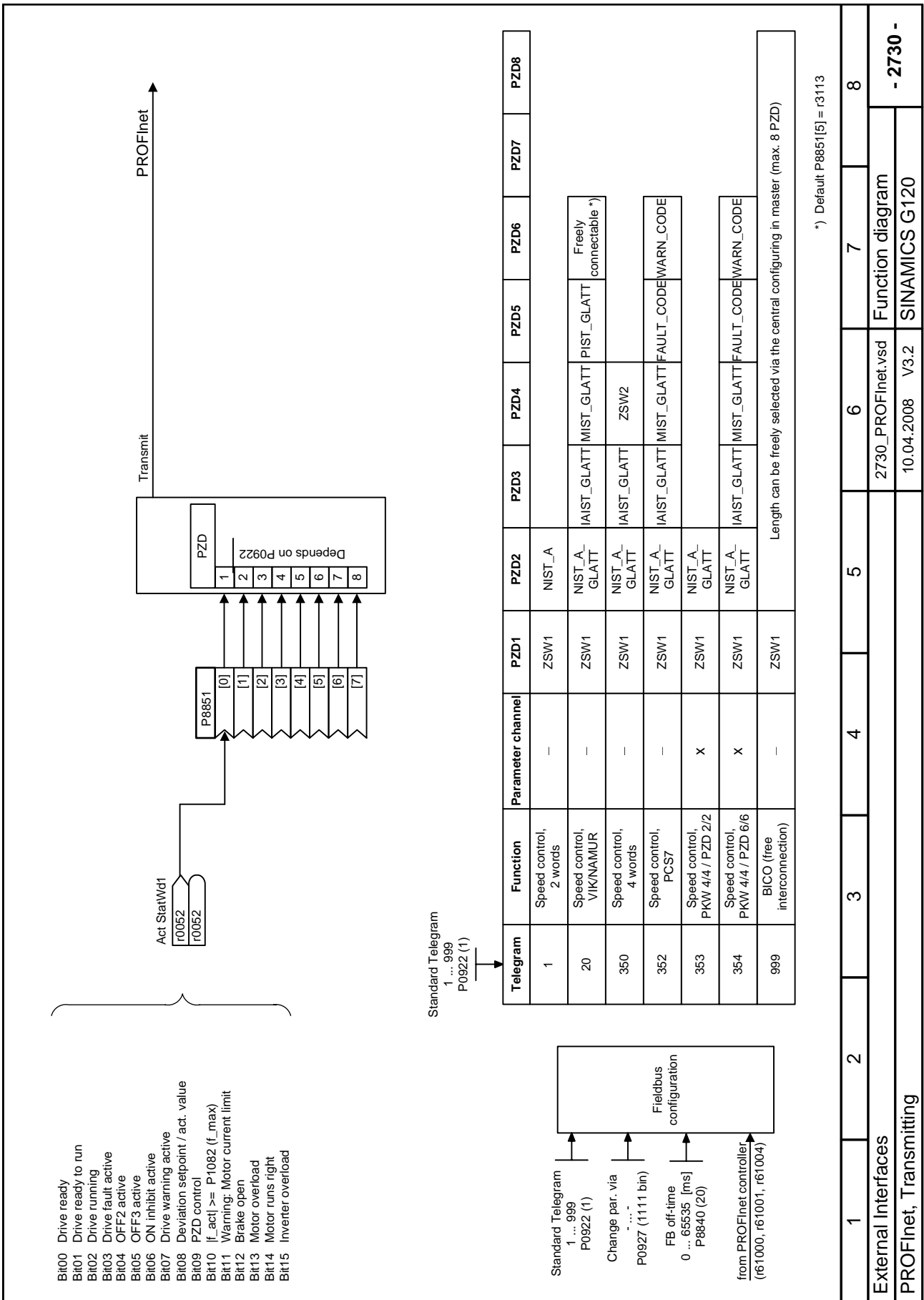


Fig. 2-16 2730 – PROFInet, Transmitting

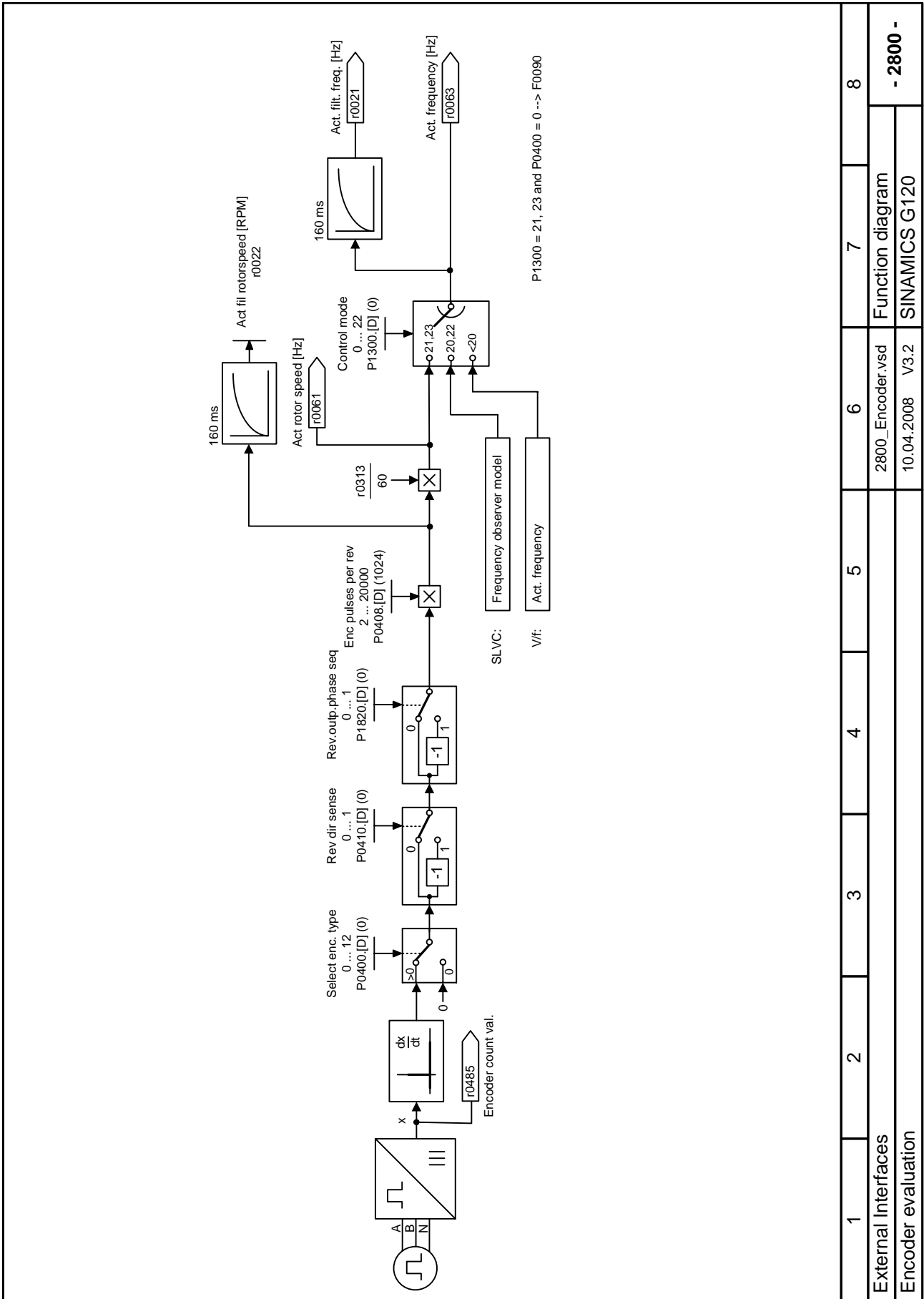


Fig. 2-17 2800 – Encoder evaluation

2.5 Internal Setpoint Source

Function diagrams

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3310 – Fixed PID setpoint, Binary Selection (P2216 = 2)	2-341
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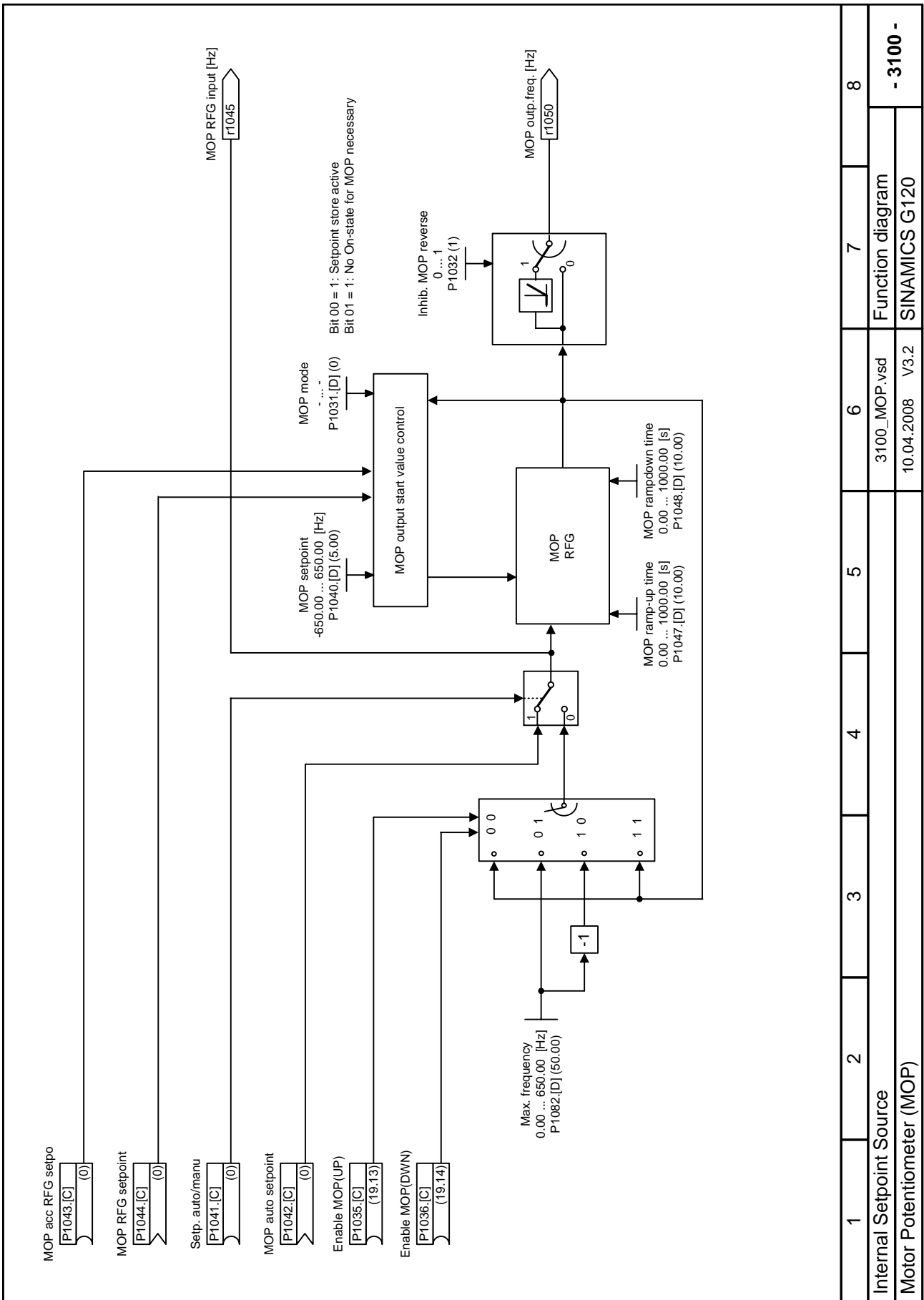


Fig. 2-18 3100 – Motor Potentiometer (MOP)

1	2	3	4	5	6	7	8
Internal Setpoint Source							
Motor Potentiometer (MOP)							
3100_MOP.vsd						Function diagram	
10.04.2008 V3.2						SINAMICS G120	
- 3100 -							

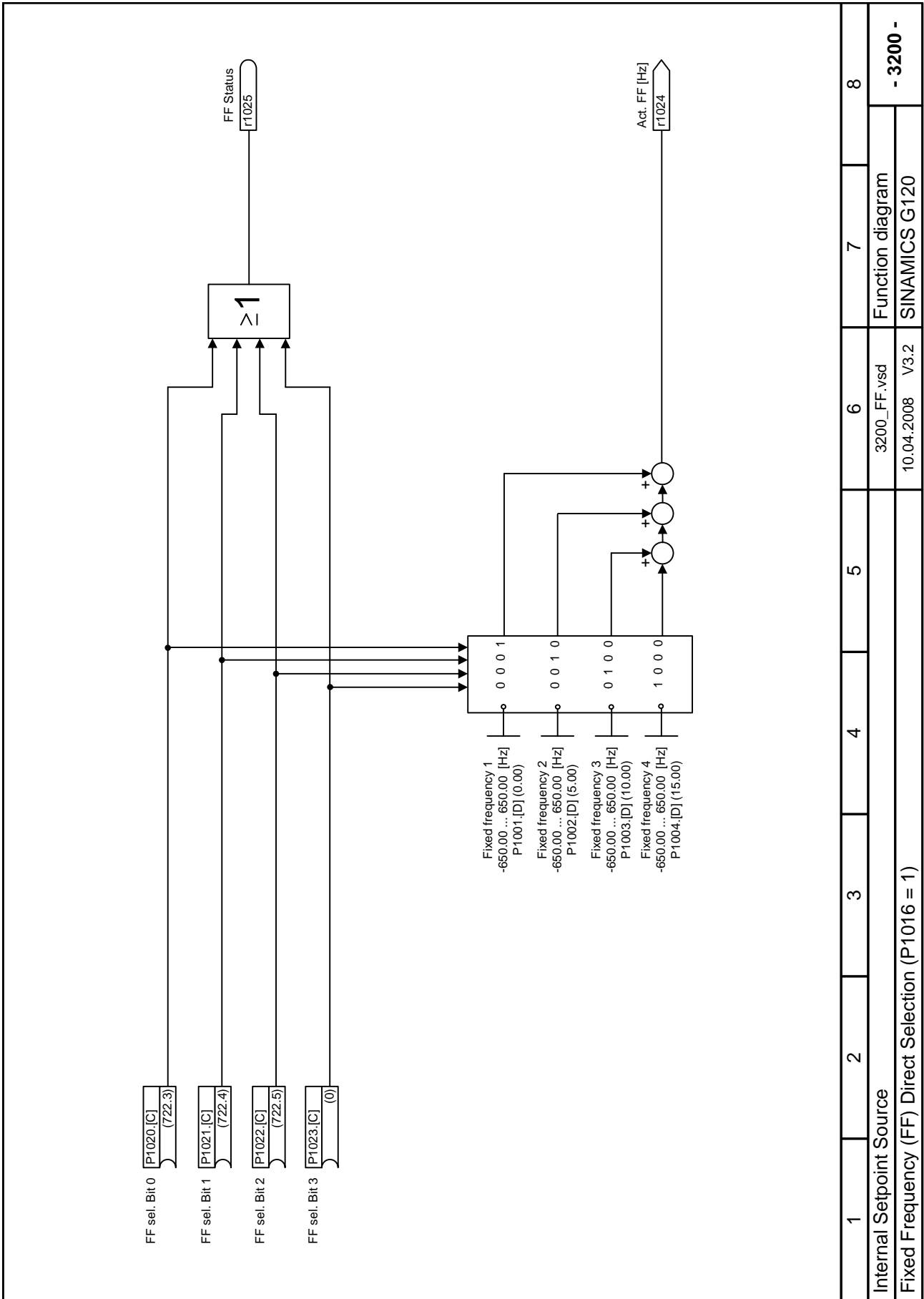


Fig. 2-19 3200 – Fixed Frequency (FF) Direct Selection (P1016 = 1)

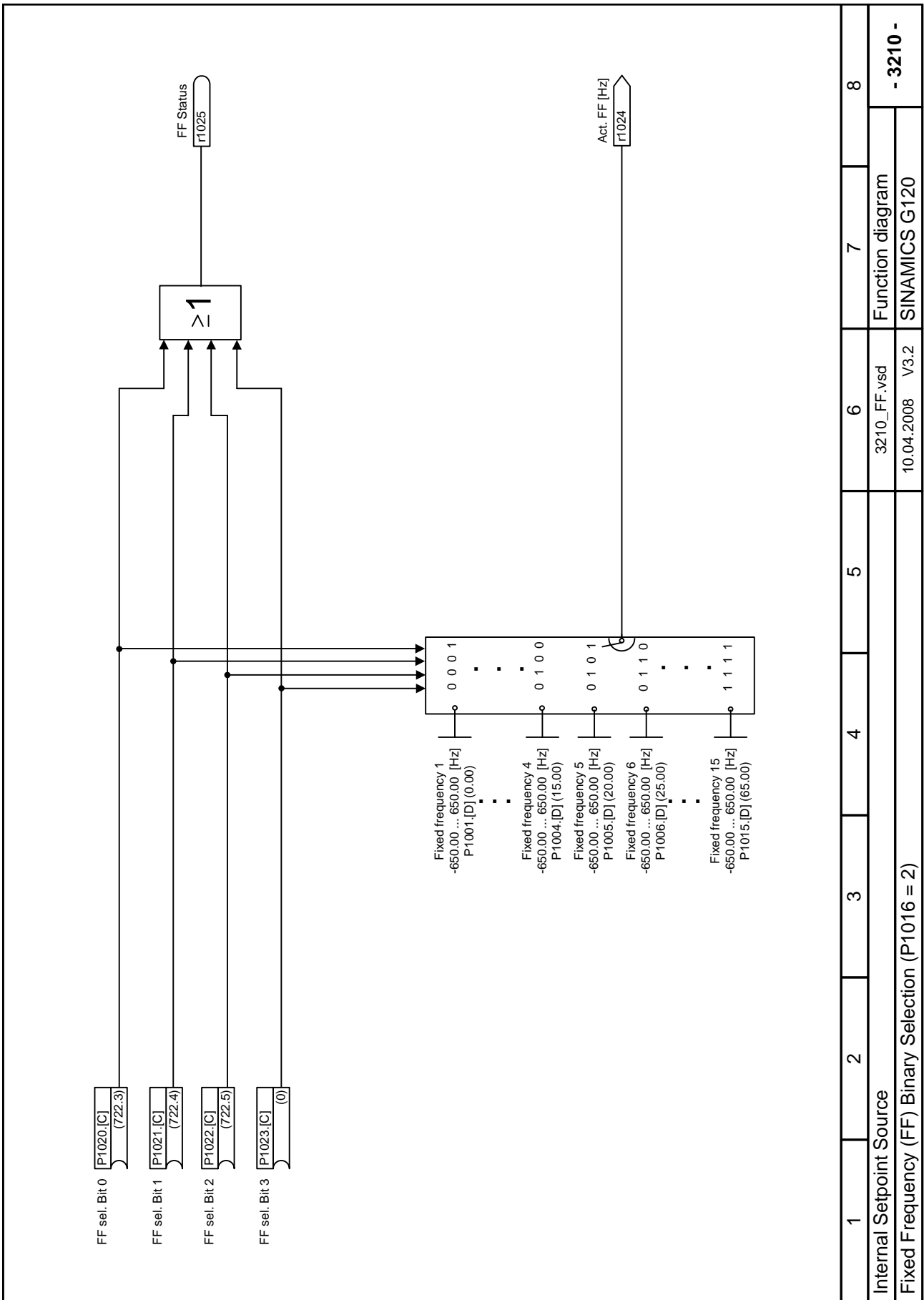


Fig. 2-20 3210 – Fixed Frequency (FF) Binary Selection (P1016 = 2)

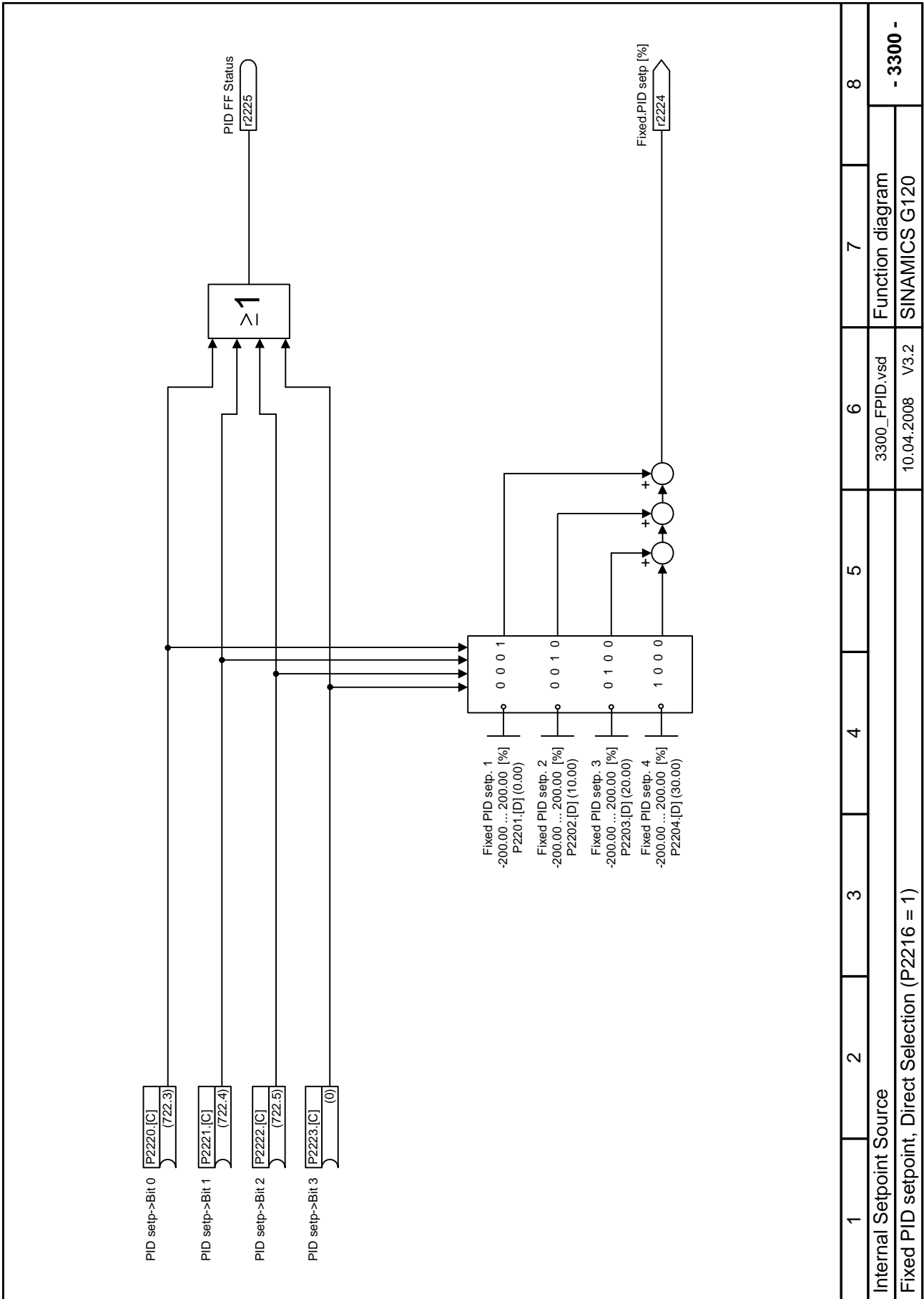


Fig. 2-21 3300 – Fixed PID setpoint, Direct Selection (P2216 = 1)

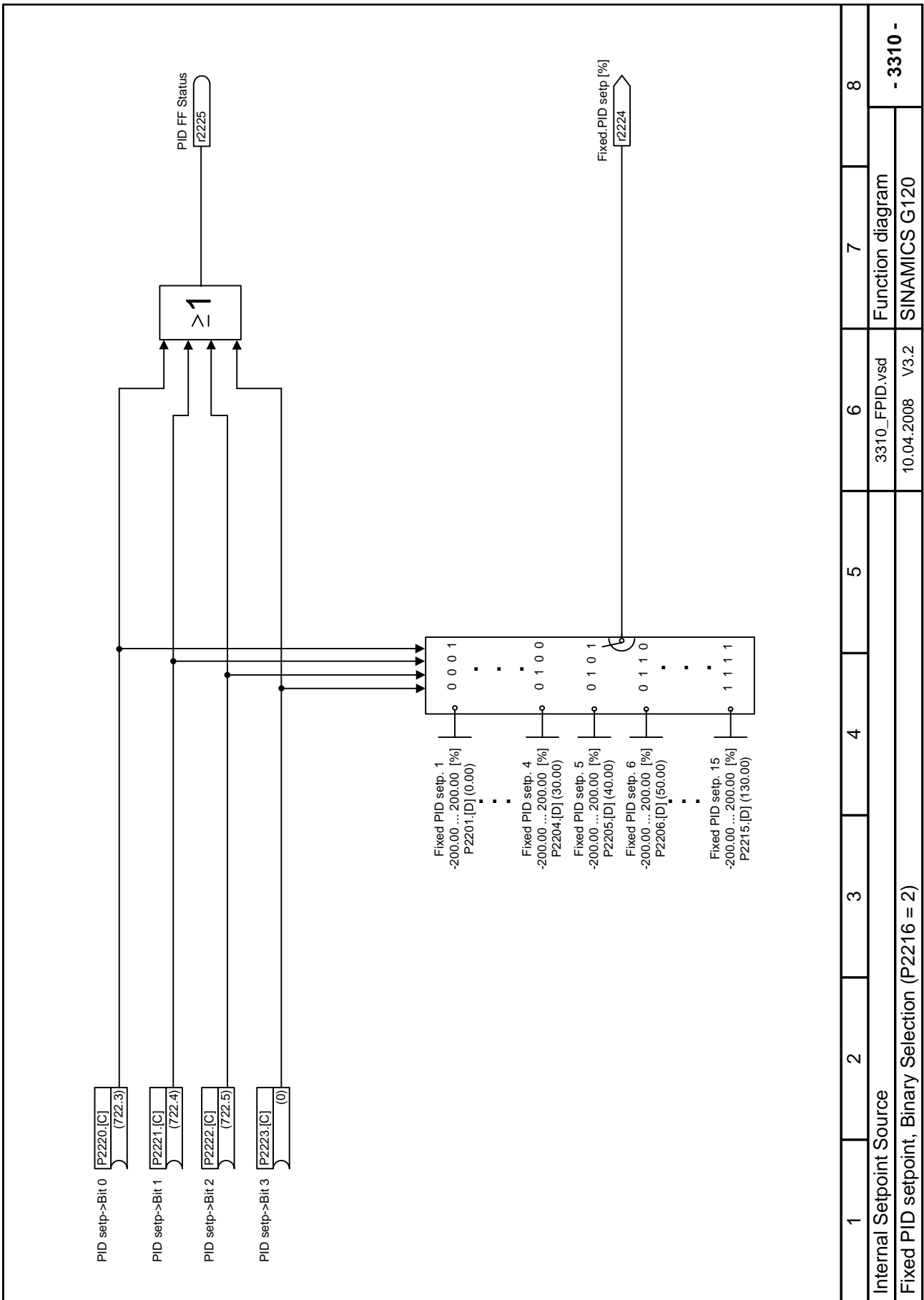


Fig. 2-22 3310 – Fixed PID setpoint, Binary Selection (P2216 = 2)

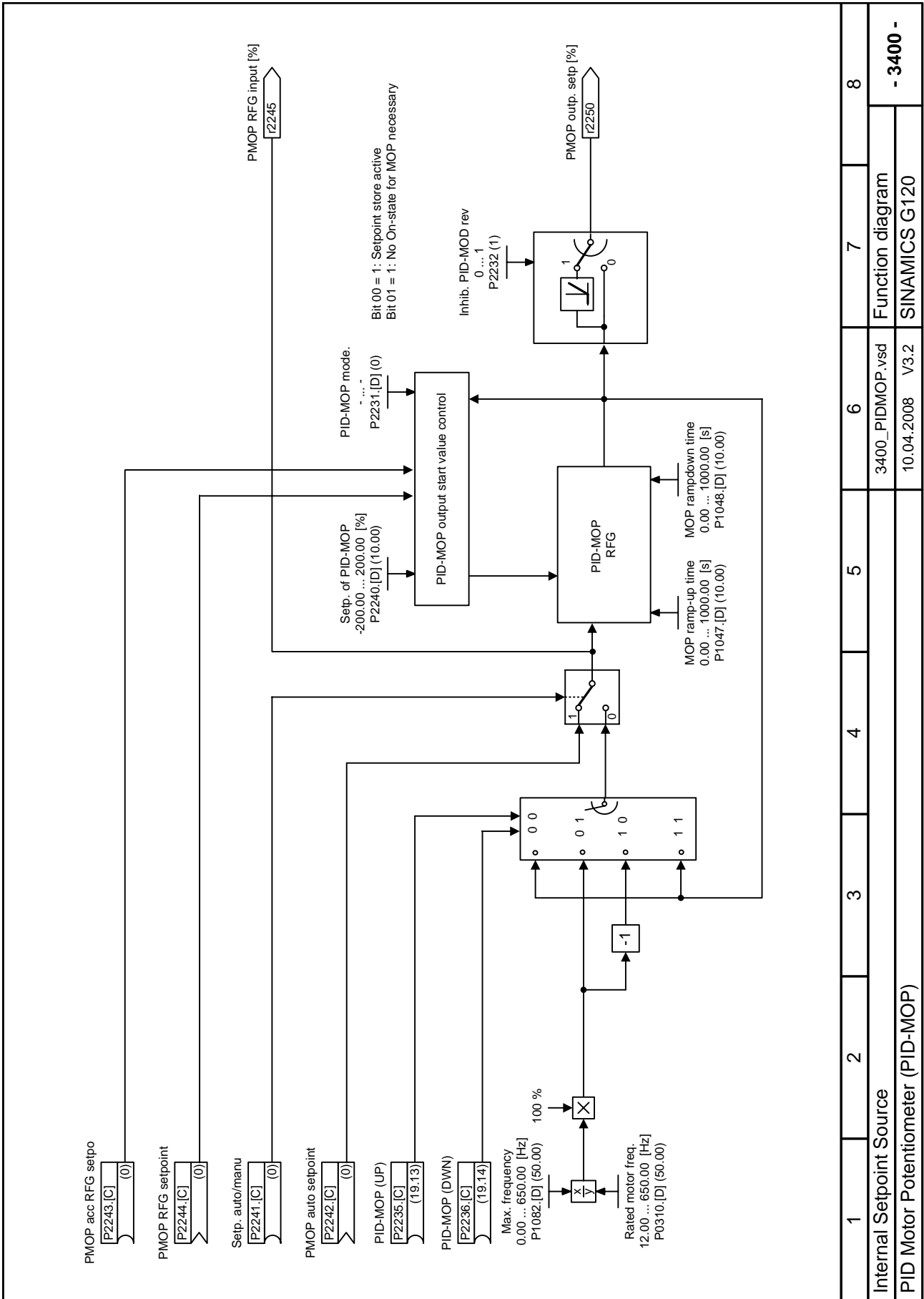


Fig. 2-23 3400 – PID Motor Potentiometer (PID-MOP)

2.6 Technology Functions

Function diagrams

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4600 – Vdc Control (max, min)	2-354

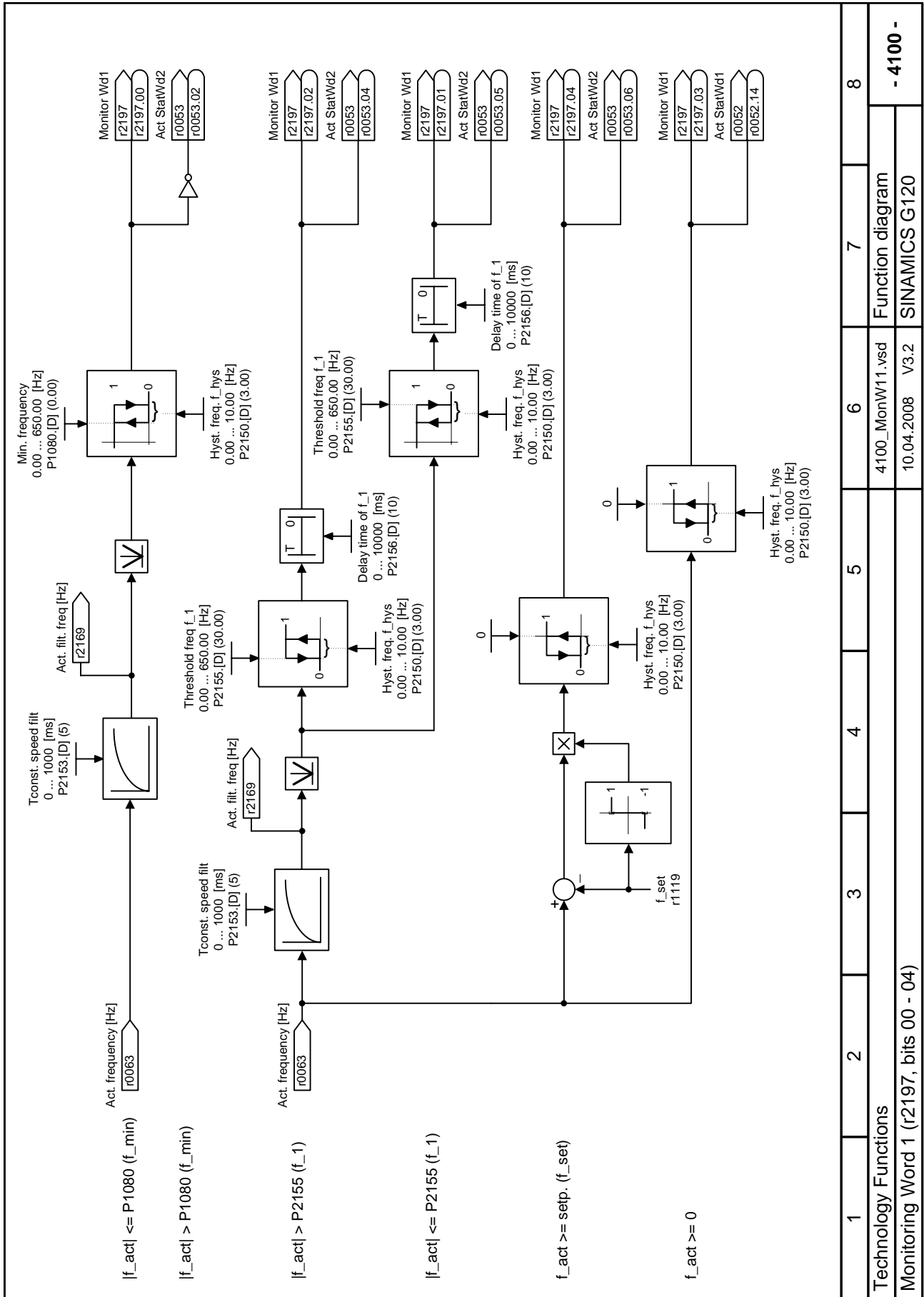


Fig. 2-24 4100 – Monitoring (r2197, bits 00 - 04)

1	2	3	4	5	6	7	8
Technology Functions							
4100_MonWd1.vsd							
10.04.2008 V3.2							
Function diagram							
Monitoring Word 1 (r2197, bits 00 - 04)							
- 4100 -							

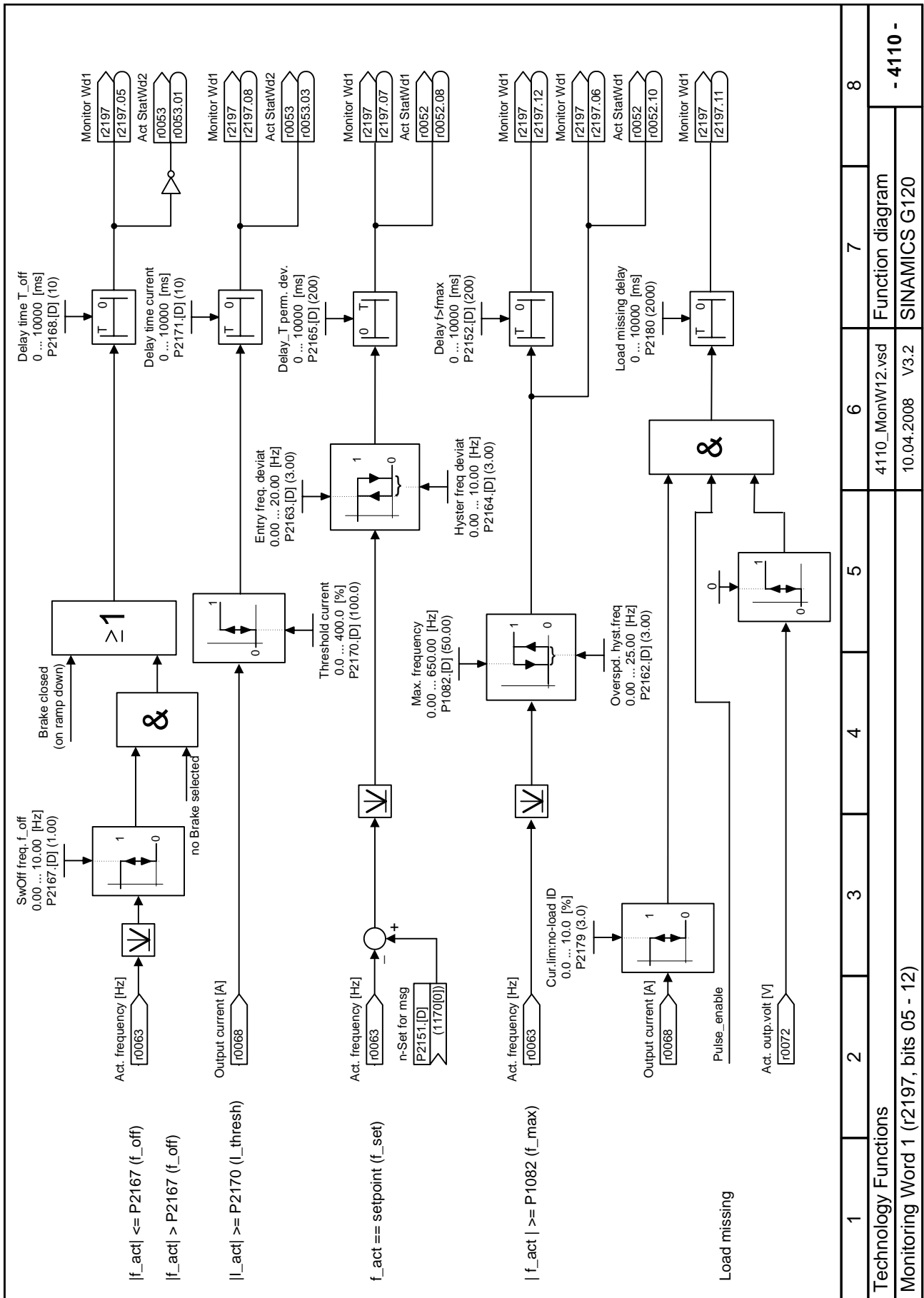


Fig. 2-25 4110 – Monitoring (r2197, bits 05 - 12)

1	2	3	4	5	6	7	8
Technology Functions							
4110_MonW12.vsd							
Function diagram							
Monitoring Word 1 (r2197, bits 05 - 12)							
10.04.2008 V3.2							
SINAMICS G120							
- 4110 -							

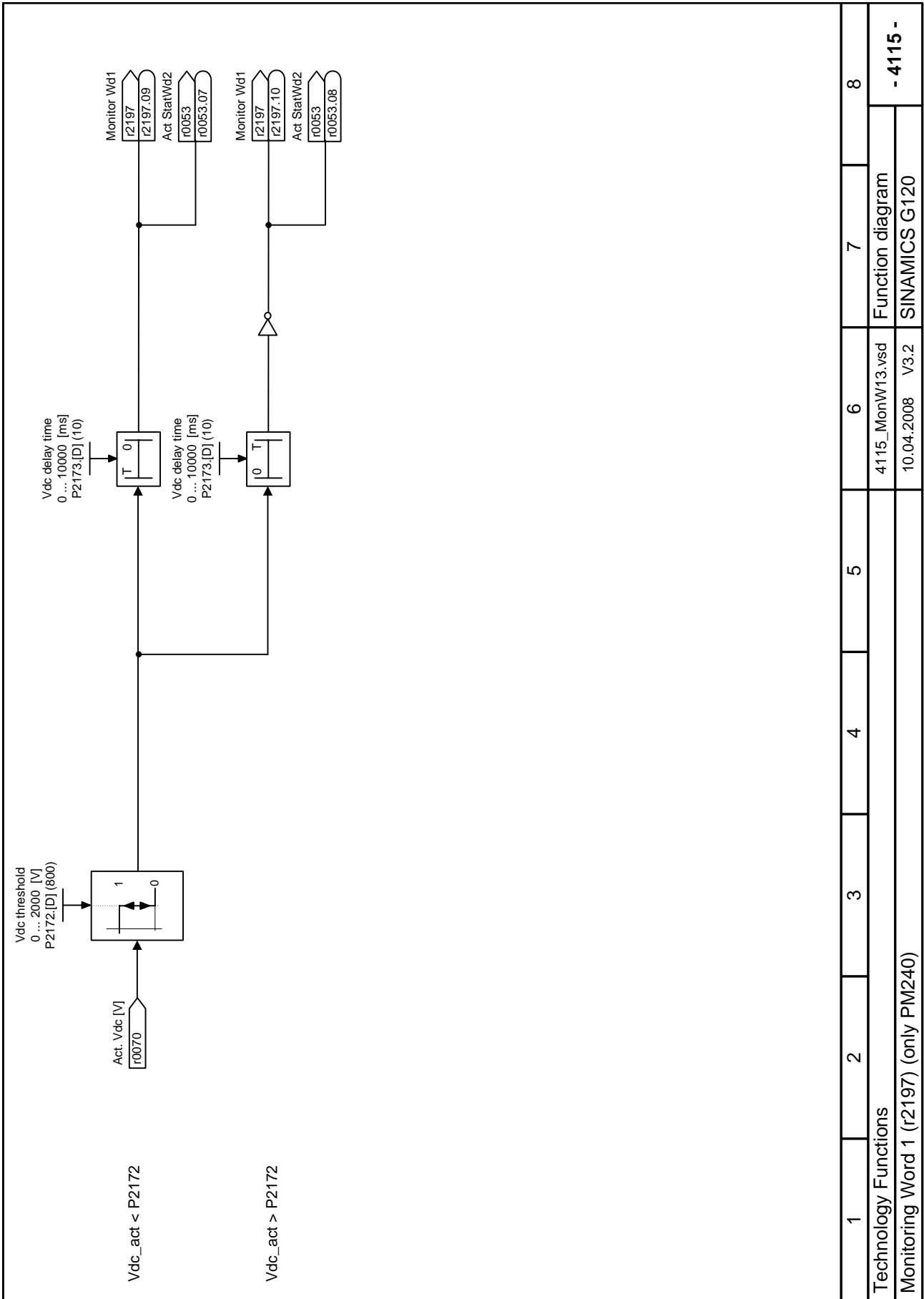


Fig. 2-26 4115 – Monitoring (r2197, bits 09 - 10) (only PM240)

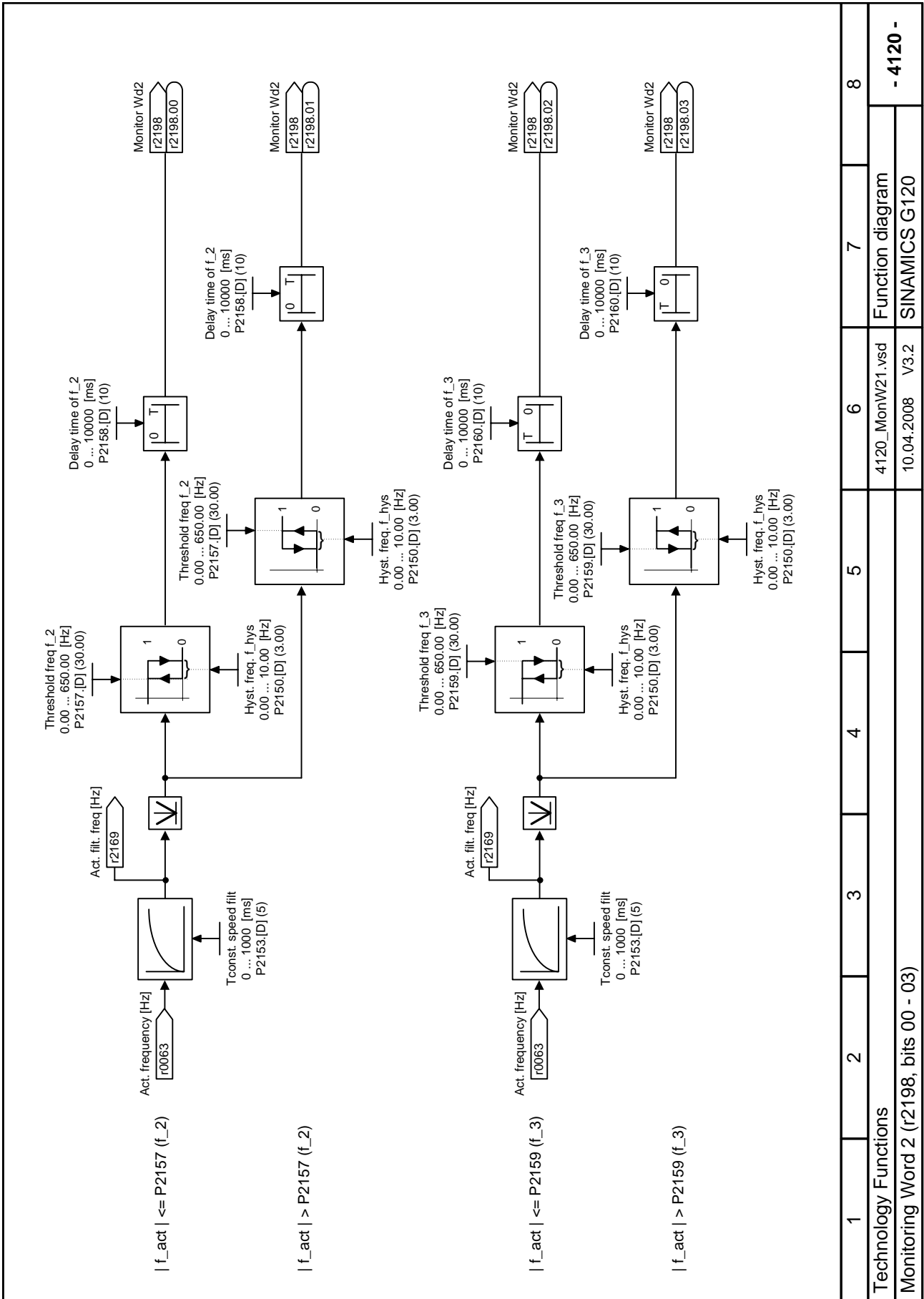


Fig. 2-27 4120 – Monitoring (r2198, bits 00 - 03)

1	2	3	4	5	6	7	8
Technology Functions							
Monitoring Word 2 (r2198, bits 00 - 03)							
4120_MonW21.vsd						Function diagram	
10.04.2008						V3.2	
						- 4120 -	

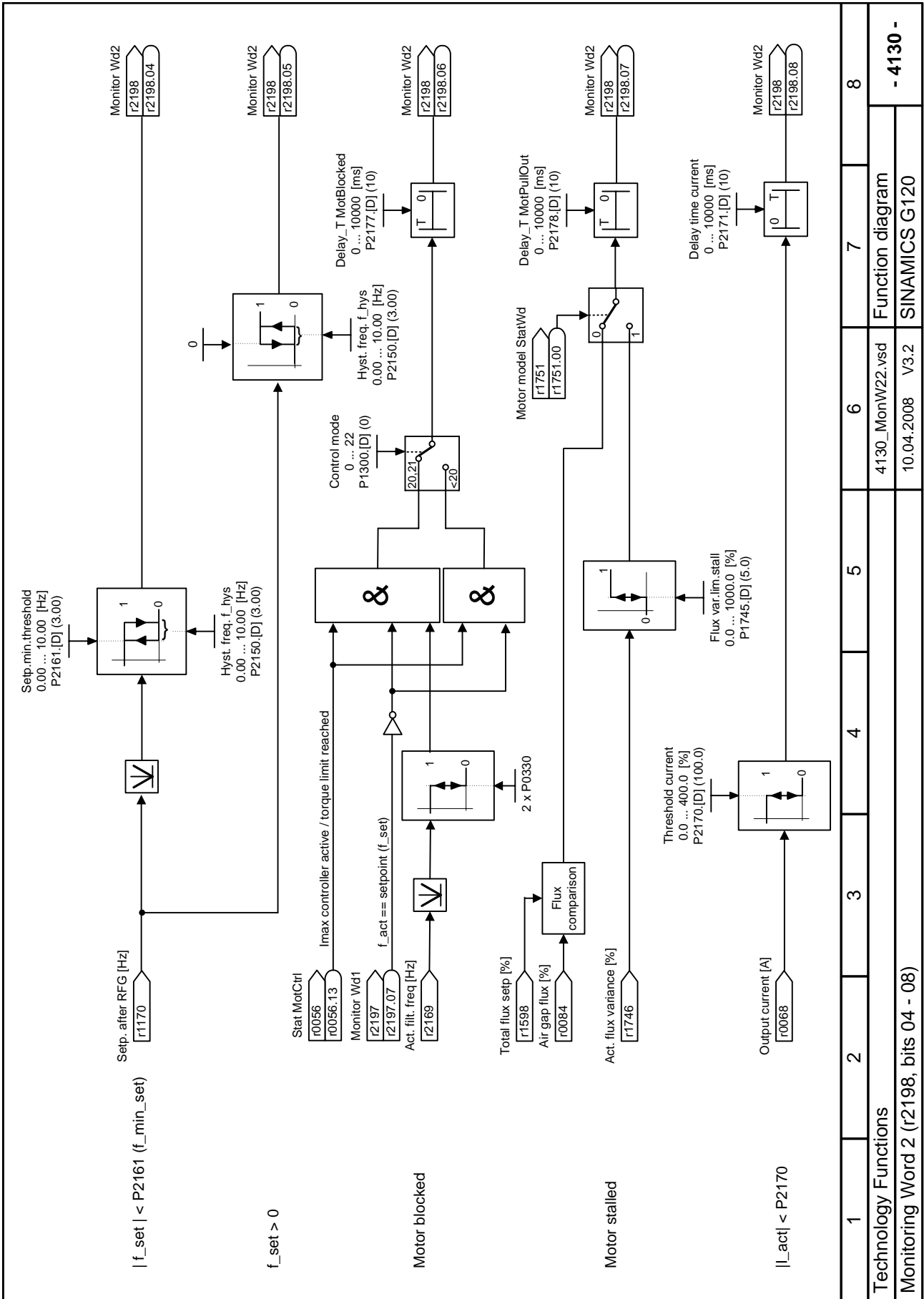


Fig. 2-28 4130 – Monitoring (r2198, bits 04 - 08)

1	2	3	4	5	6	7	8
Technology Functions							
Function diagram							
4130_MonWd2.vsd							
10.04.2008 V3.2							
Monitoring Word 2 (r2198, bits 04 - 08)							
- 4130 -							

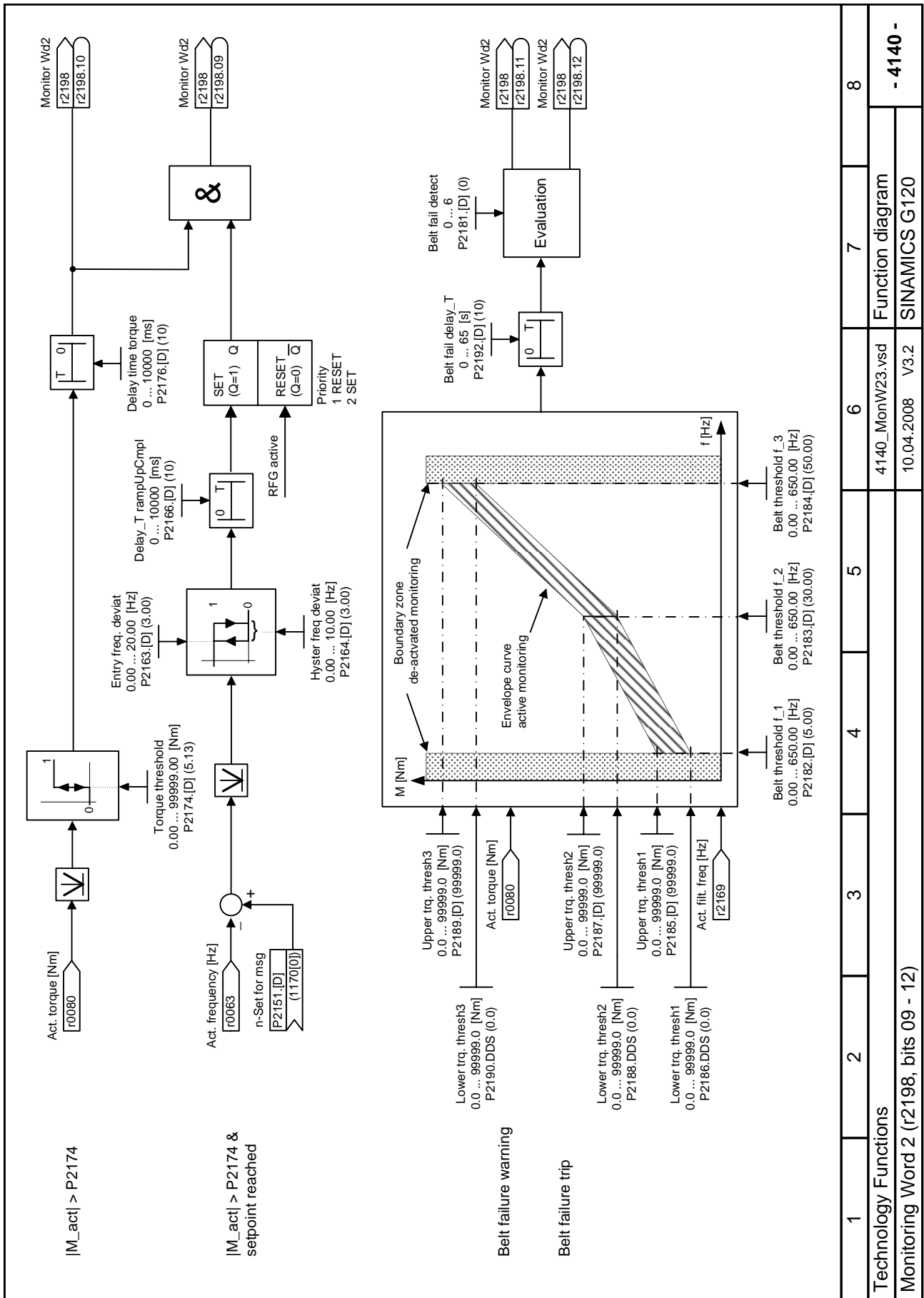


Fig. 2-29 4140 – Monitoring (r2198, bits 09 - 12)

1	2	3	4	5	6	7	8	
Technology Functions							Function diagram	- 4140 -
Monitoring Word 2 (r2198, bits 09 - 12)							SINAMICS G120	

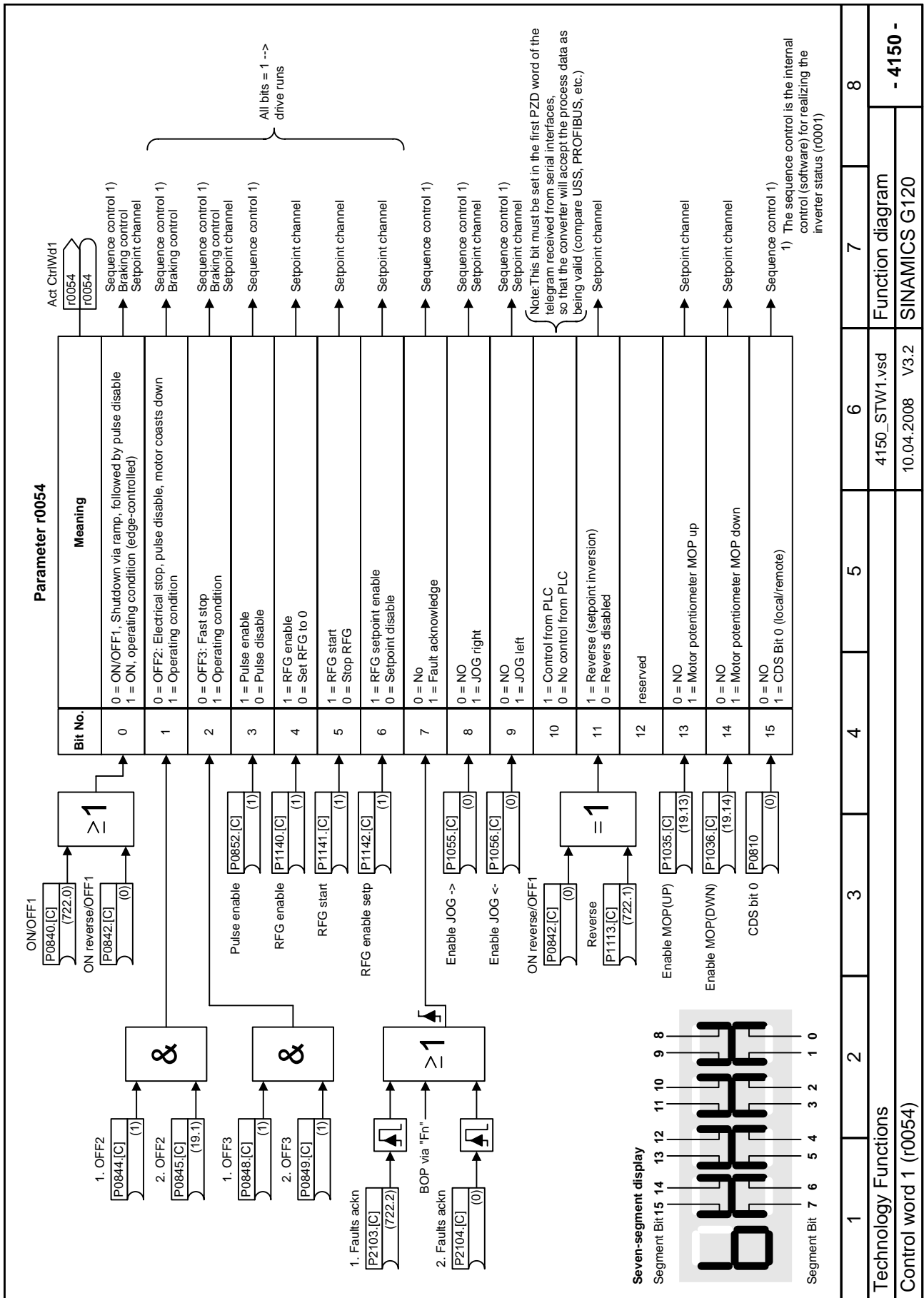


Fig. 2-30 4150 – Control word 1 (r0054)

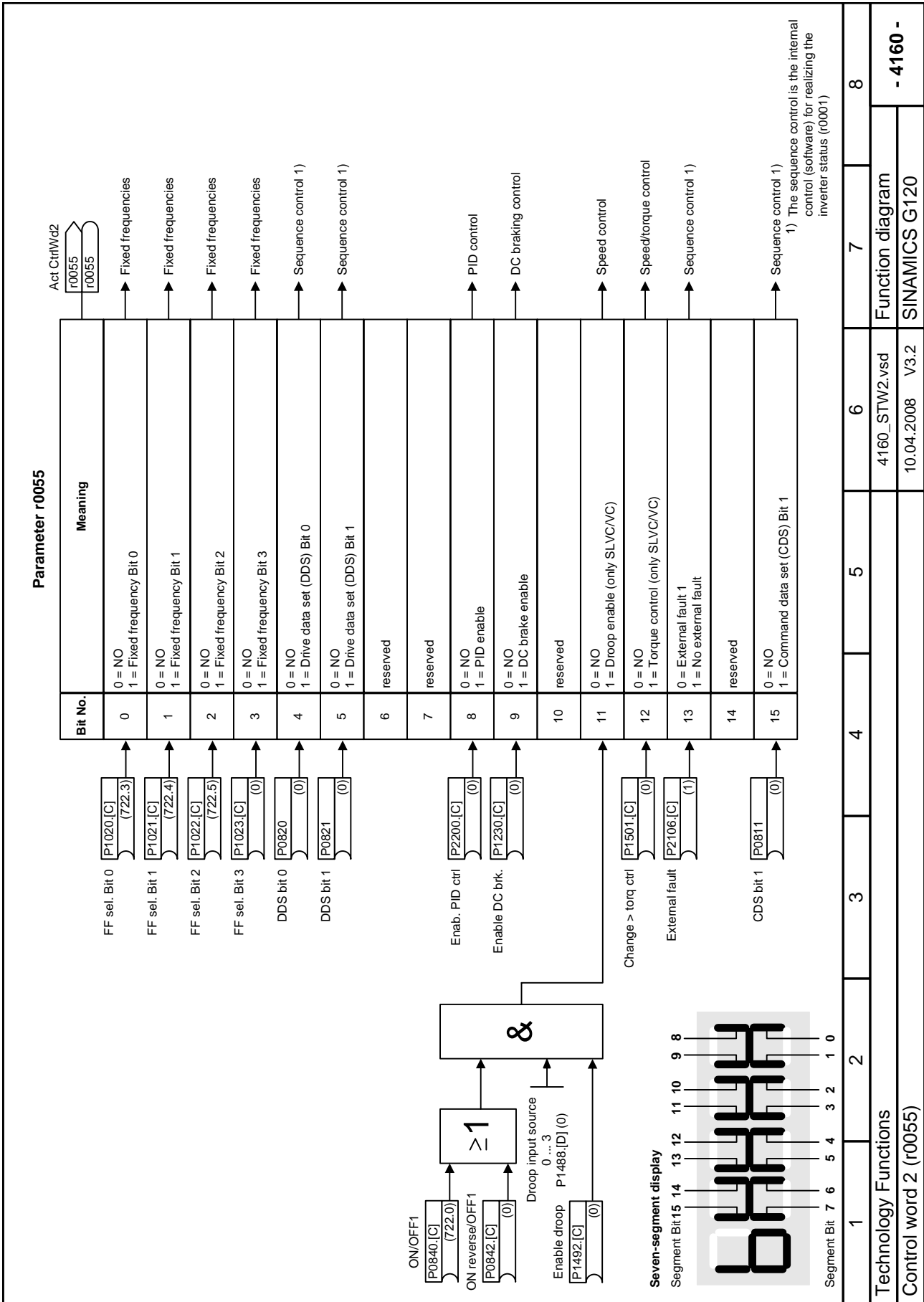


Fig. 2-31 4160 – Control word 2 (r0055)

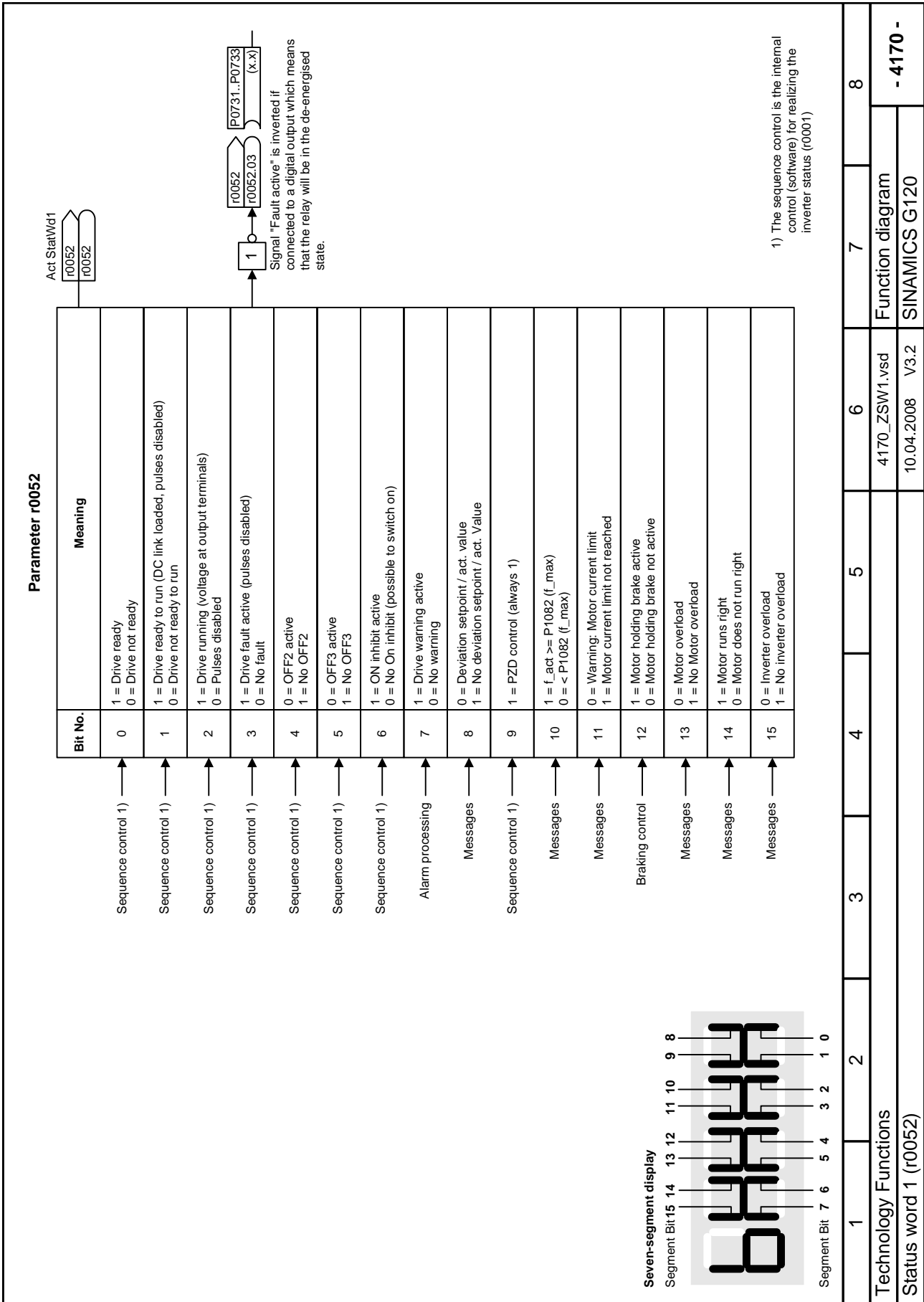


Fig. 2-32 4170 – Status word 1 (r0052)

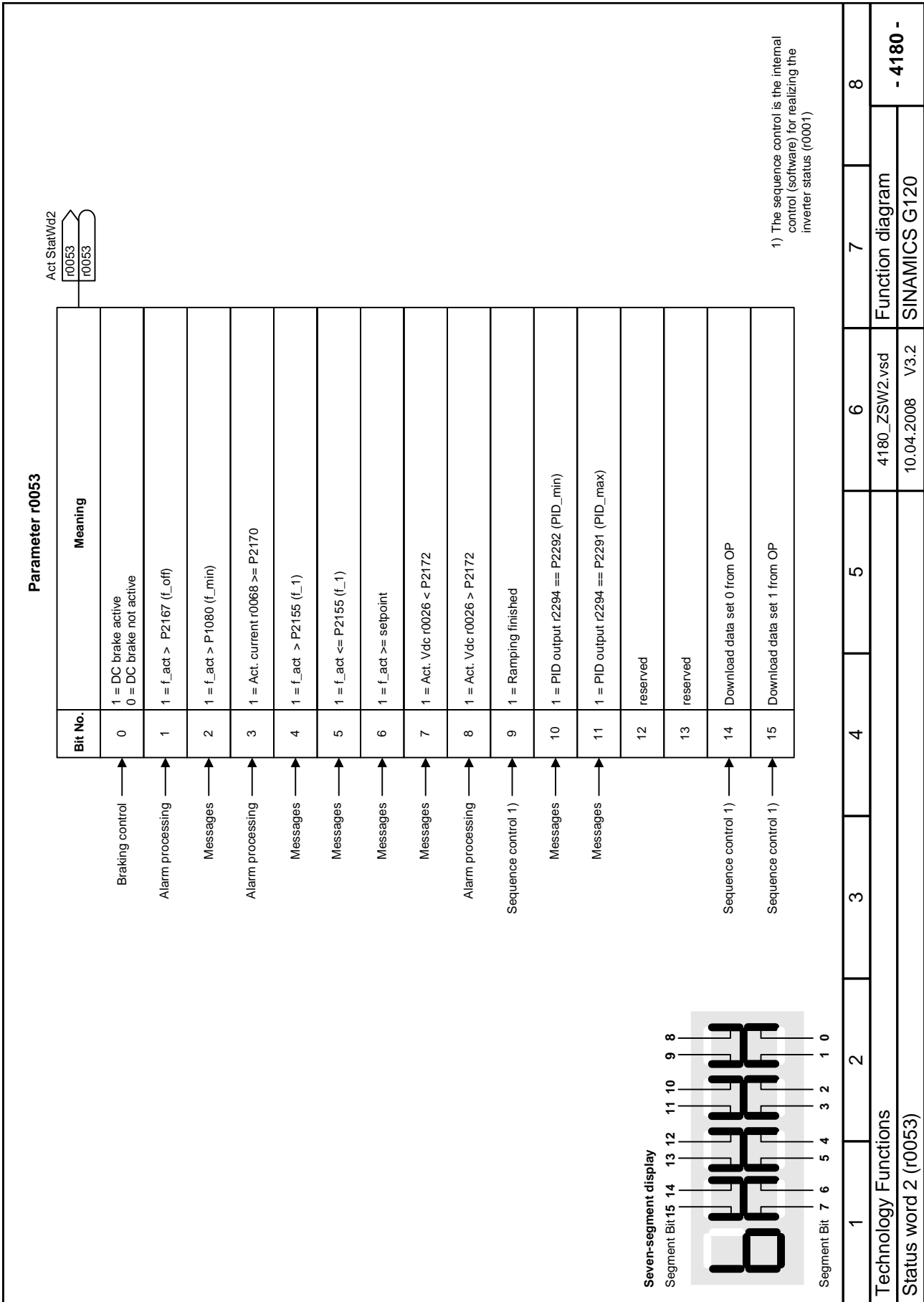


Fig. 2-33 4180 – Status word 2 (r0053)

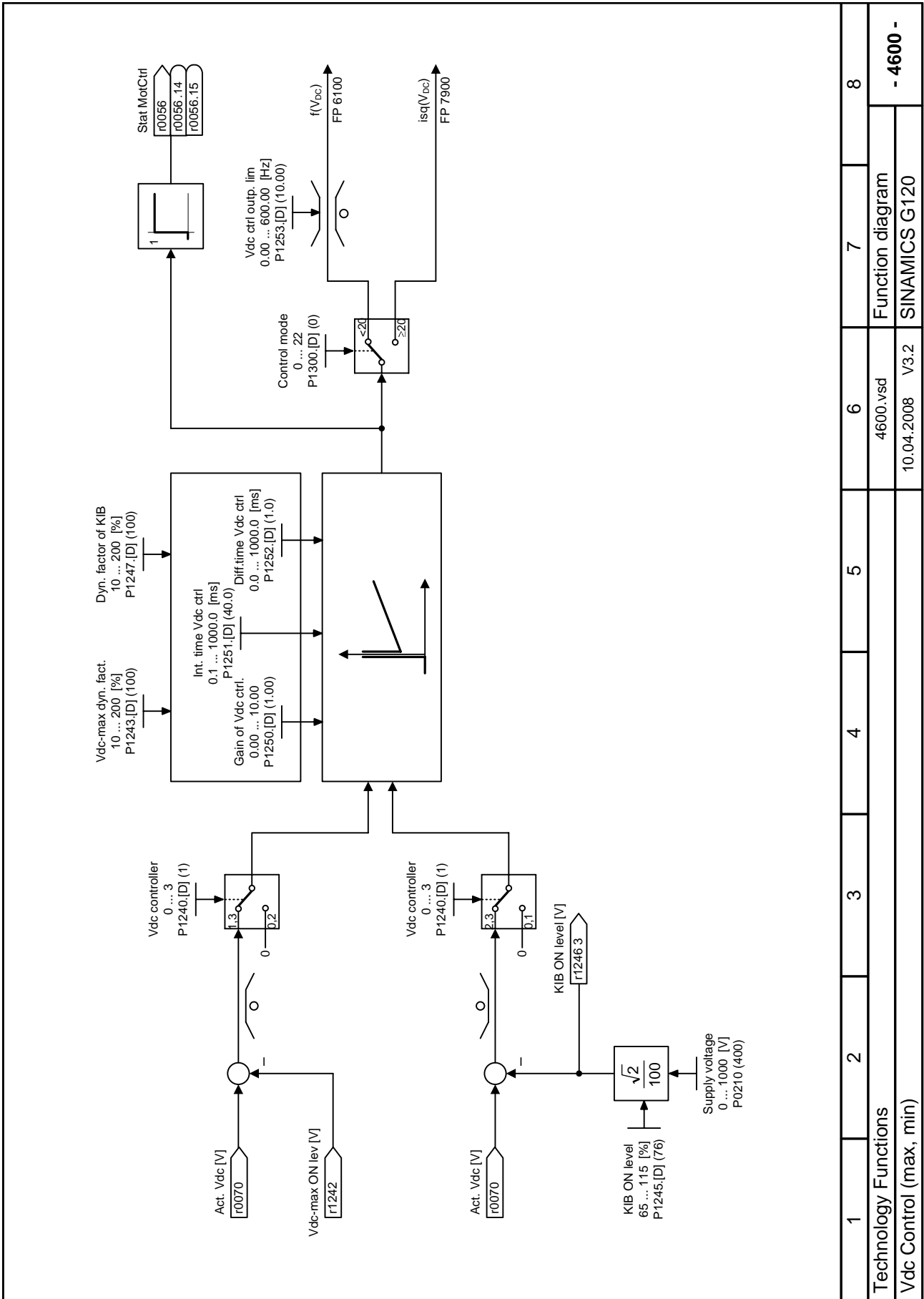


Fig. 2-34 4600 – Vdc Control (max, min)

1	2	3	4	5	6	7	8
Technology Functions							
Vdc Control (max, min)							
4600.vsd				Function diagram			
10.04.2008 V3.2				SINAMICS G120			
- 4600 -							

2.7 Free Function Blocks

Function diagrams

4800 – AND-, OR-, XOR- and NOT- Elements	2-356
4810 – FlipFlops	2-357
4820 – Timers	2-358
4830 – Adders, Subtracters, Multipliers, Dividers, Comparators, Setting in %	2-359

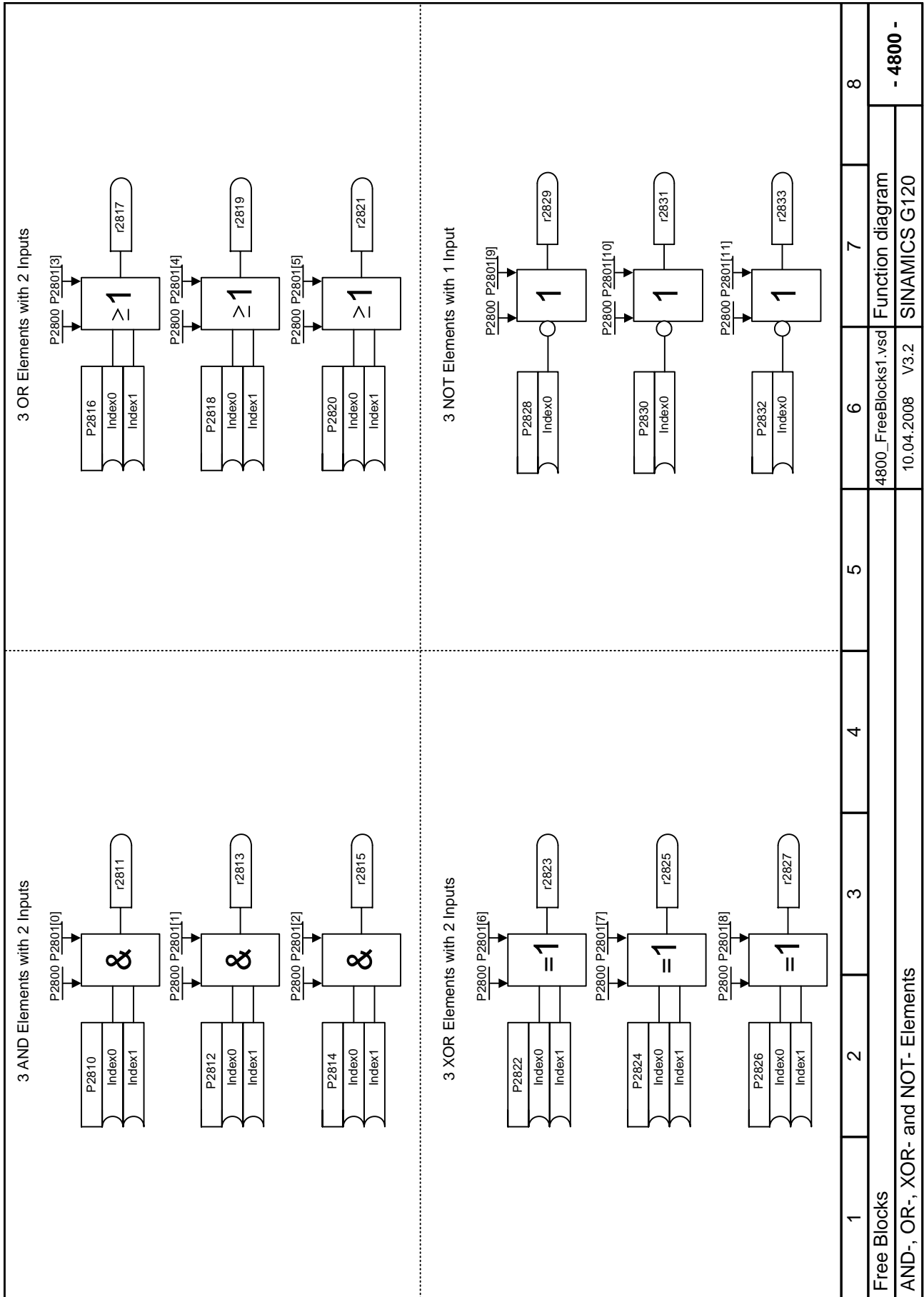


Fig. 2-35 4800 – AND-, OR-, XOR- and NOT- Elements

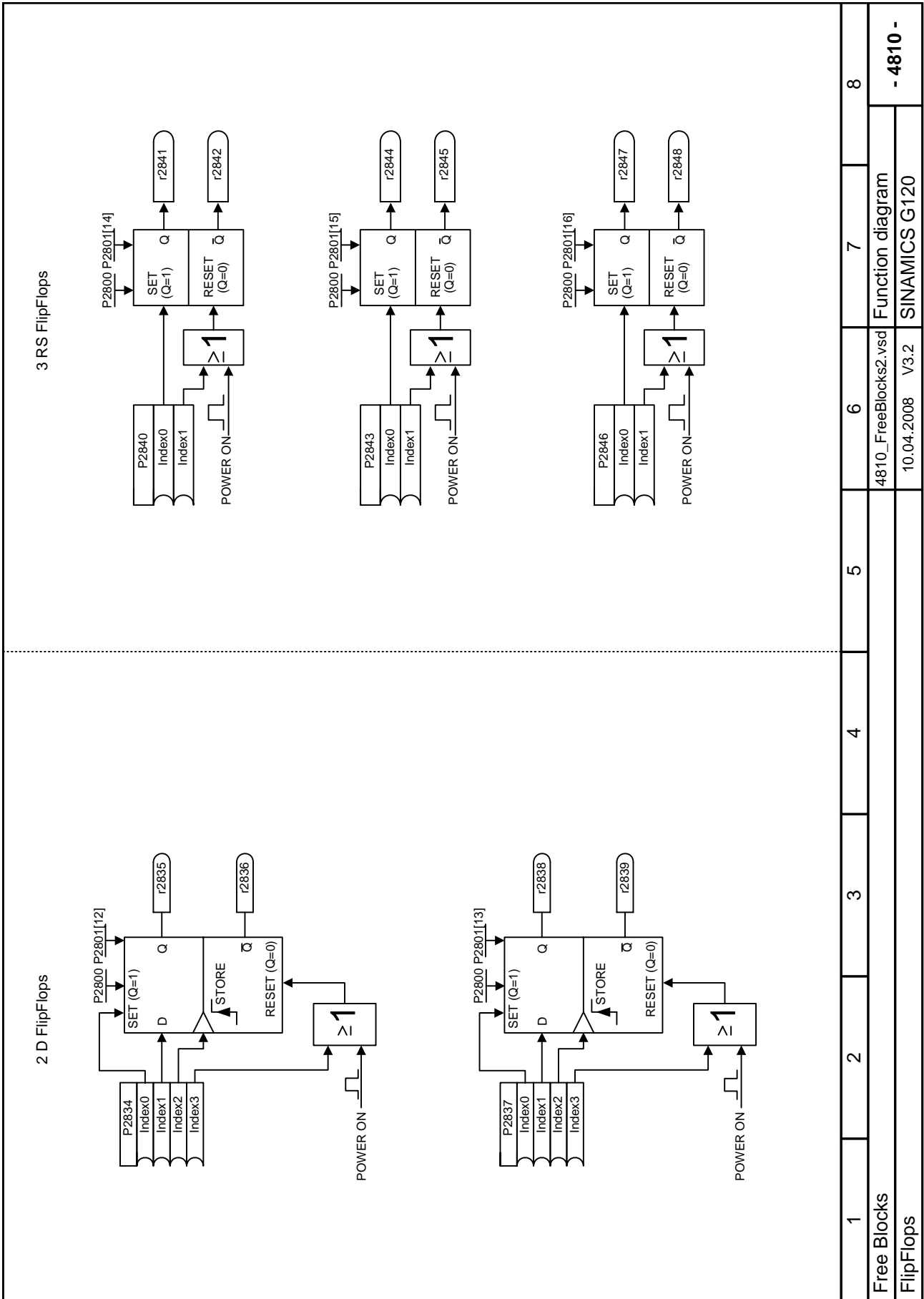
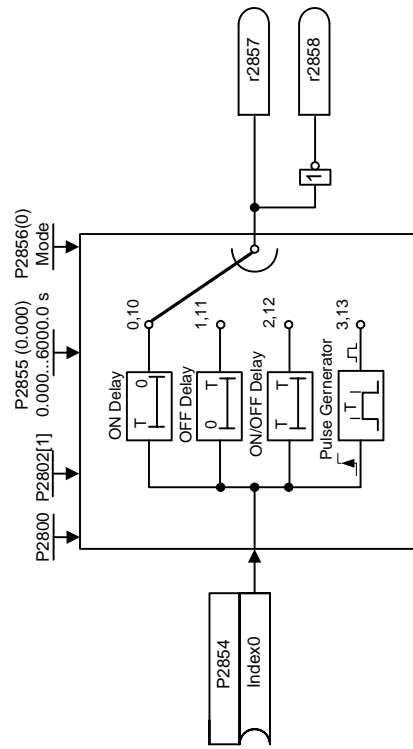
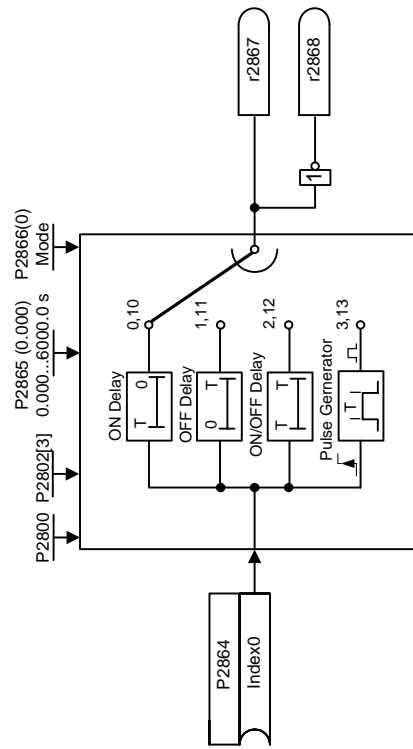
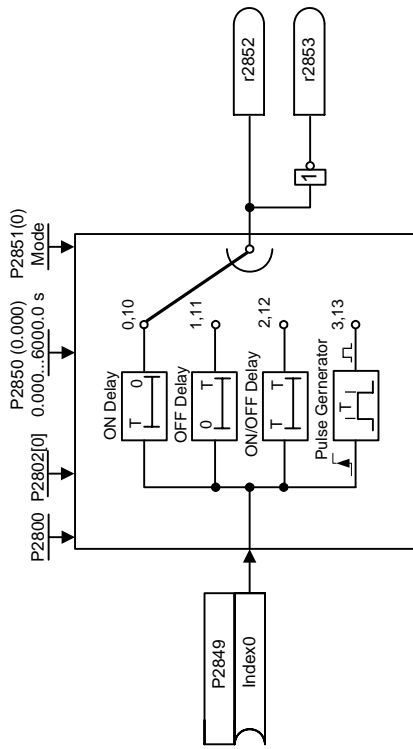
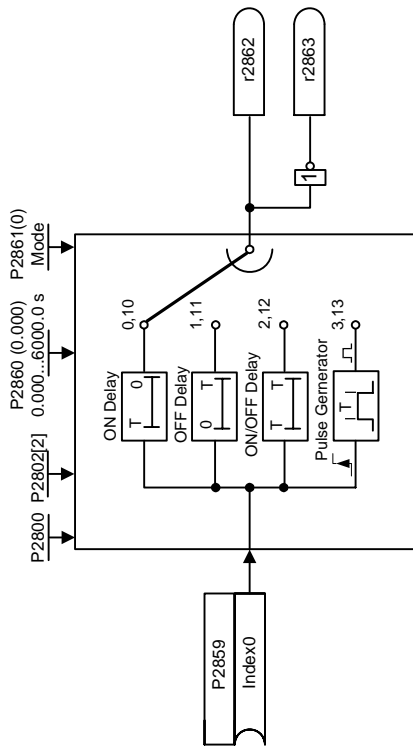


Fig. 2-36 4810 – FlipFlops

4 Timers 0 ... 6000.0 s



1	2	3	4	5	6	7	8
Free Blocks							
Timers							
4820_FreeBlocks3.vsd						Function diagram	
10.04.2008 V3.2						SINAMICS G120	
- 4820 -							

Fig. 2-37 4820 – Timers

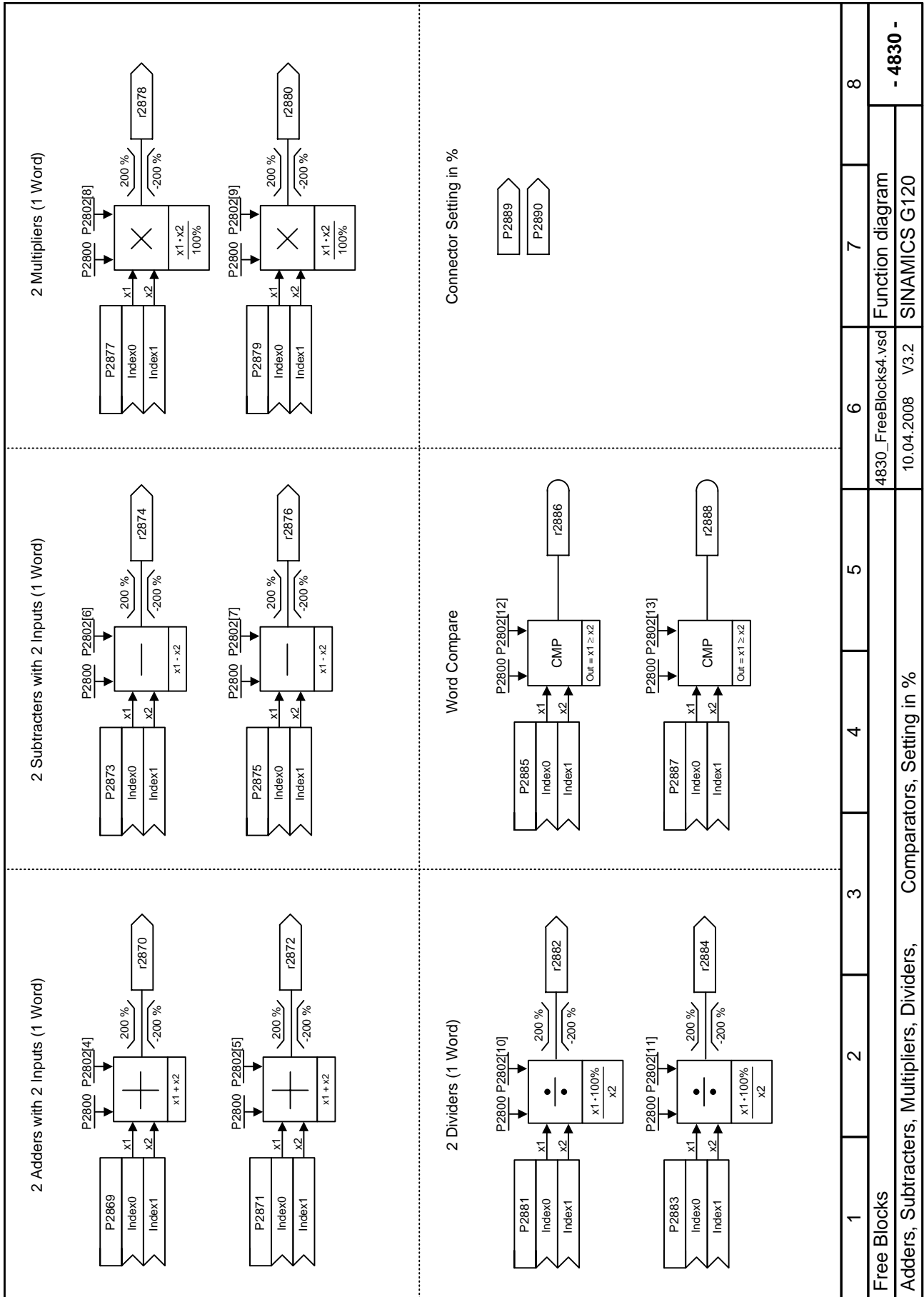
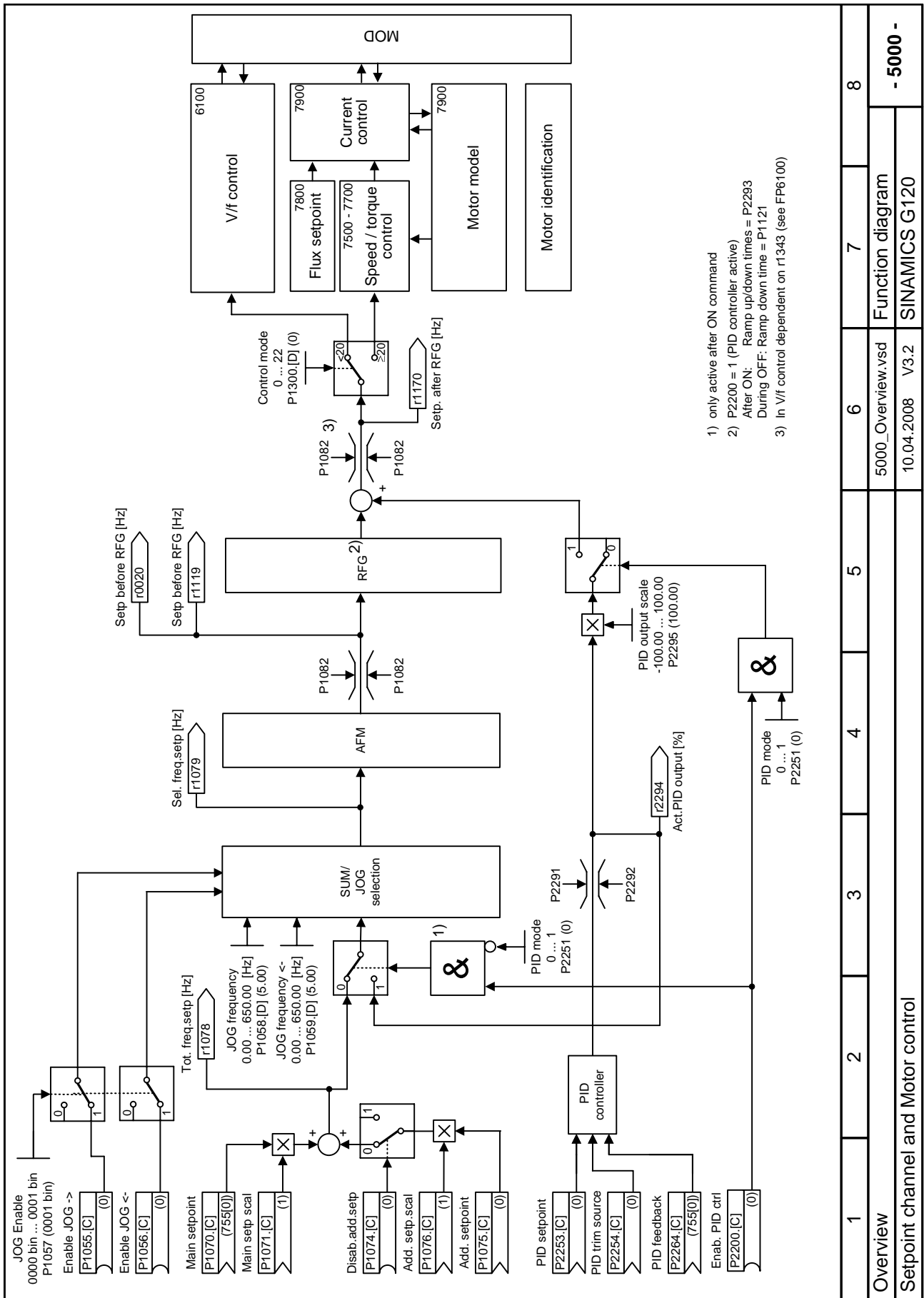


Fig. 2-38 4830 – Adders, Subtractors, Multipliers, Dividers, Comparators, Setting in %

2.8 Setpoint Channel

Function diagrams

5000 – Setpoint channel and Motor control	2-361
5100 – PID Controller	2-362
5150 – Wobble Generator	2-363
5200 – Additional Frequency Modifications (AFM)	2-364
5300 – Ramp Function Generator	2-365



- 1) only active after ON command
- 2) P2200 = 1 (PID controller active)
After ON: Ramp up/down times = P2293
During OFF: Ramp down time = P1121
- 3) In V/f control dependent on r1343 (see FP6100)

Fig. 2-39 5000 – Setpoint channel and Motor control

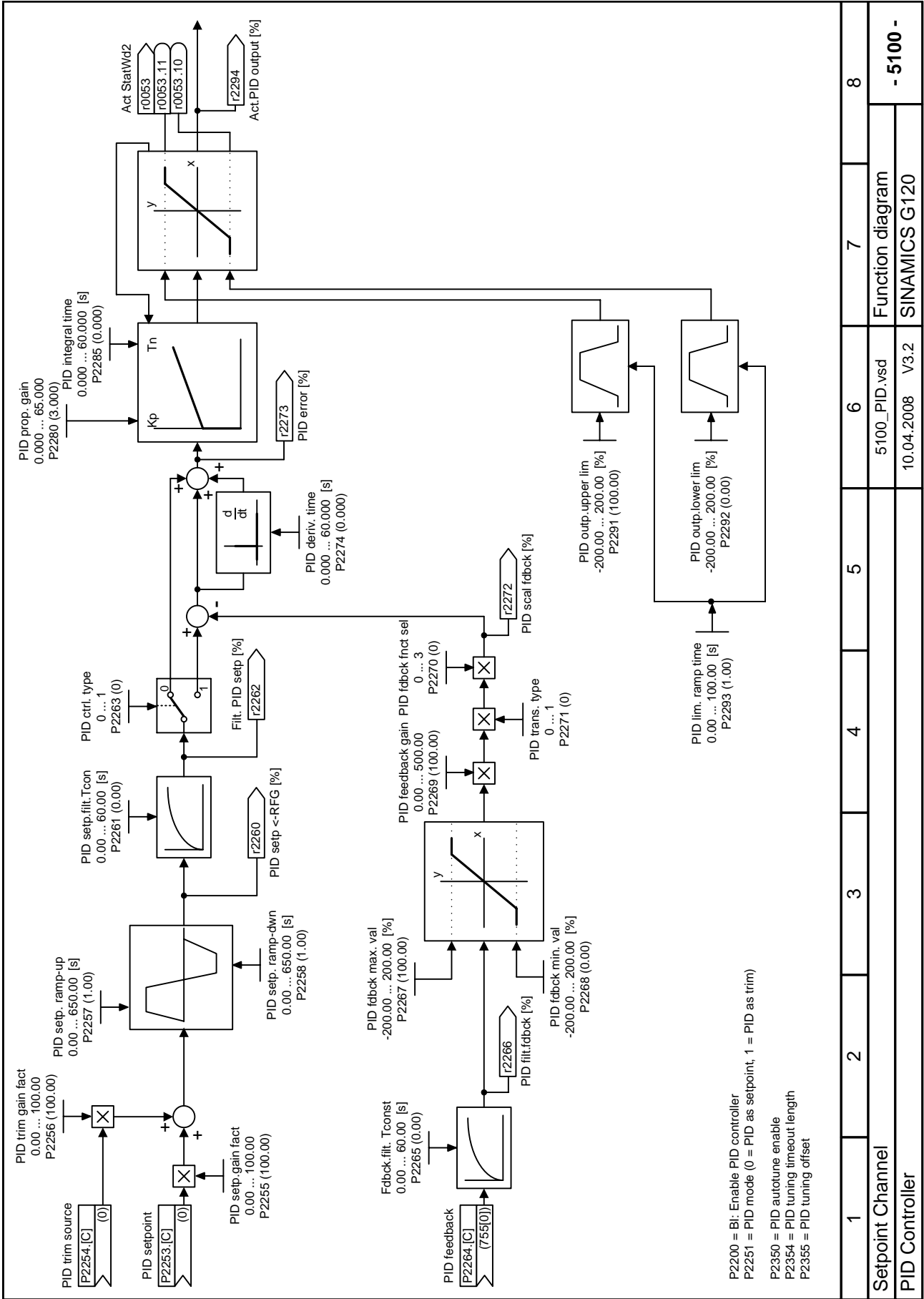


Fig. 2-40 5100 – PID Controller

1	2	3	4	5	6	7	8
Setpoint Channel							
Function diagram							
5100_PID.vsd							
10.04.2008 V3.2							
- 5100 -							
SINAMICS G120							

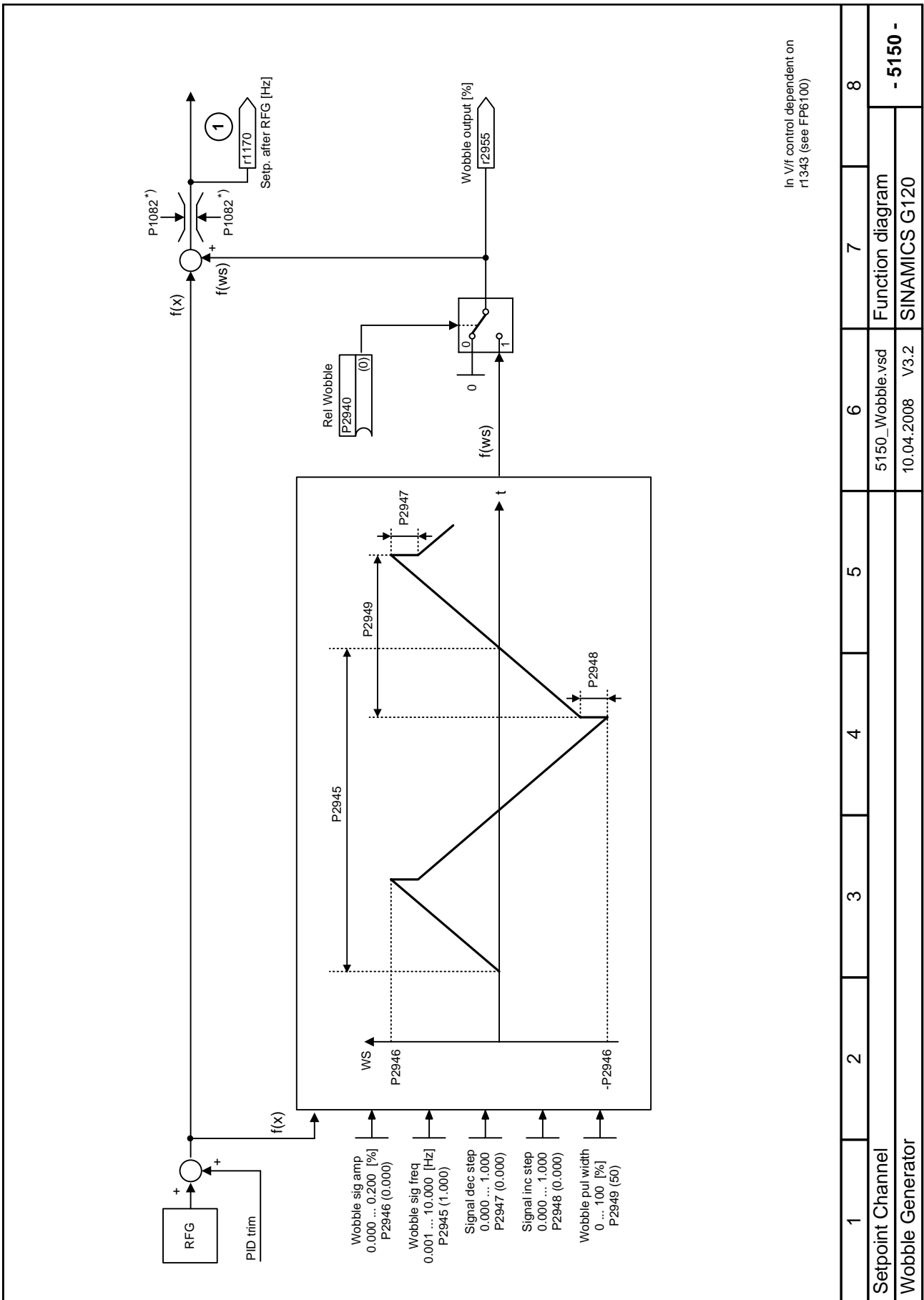


Fig. 2-41 5150 – Wobble Generator

1	2	3	4	5	6	7	8
Setpoint Channel		5150_Wobble.vsd		Function diagram		- 5150 -	
Wobble Generator		10.04.2008 V3.2		SINAMICS G120			

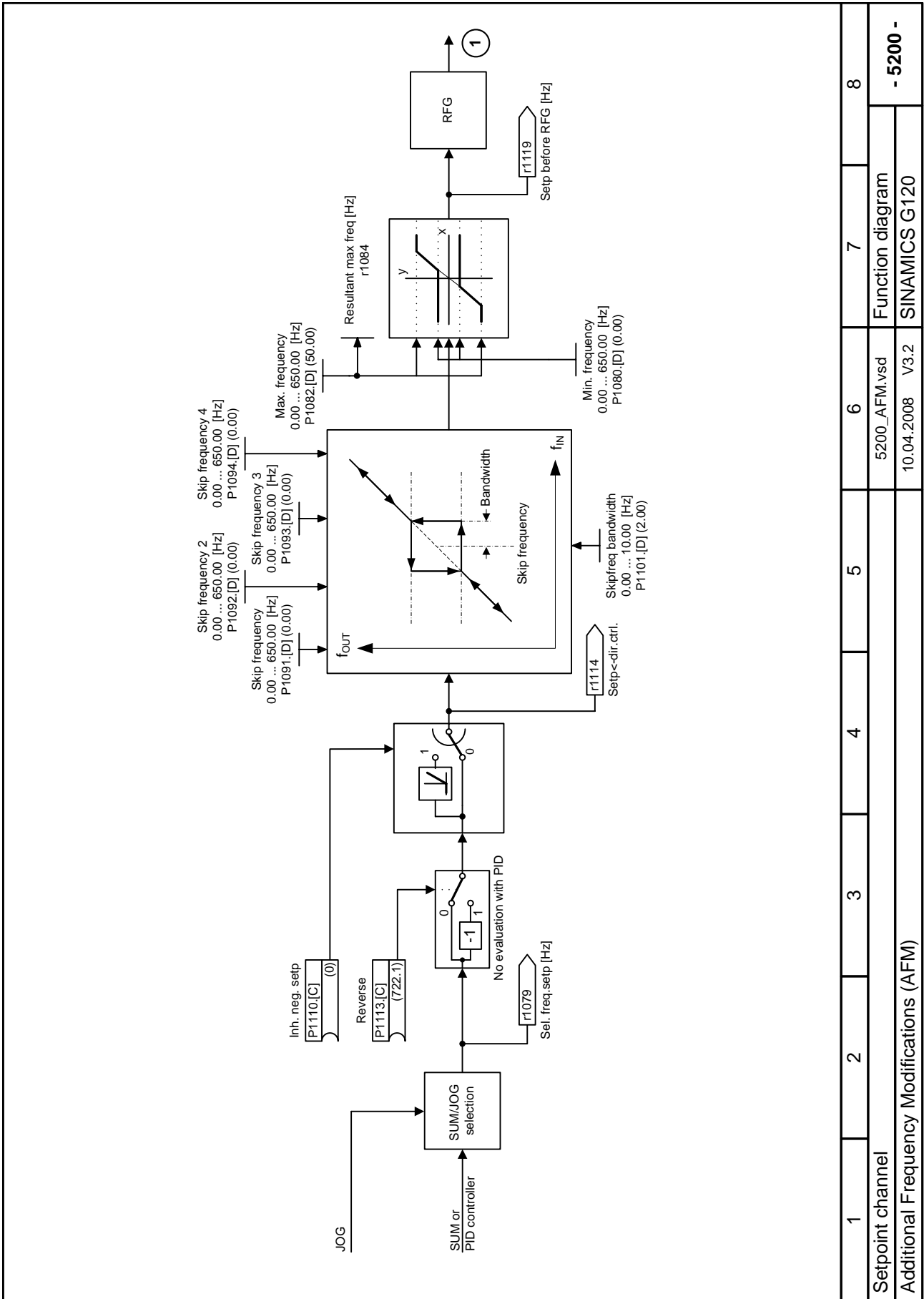
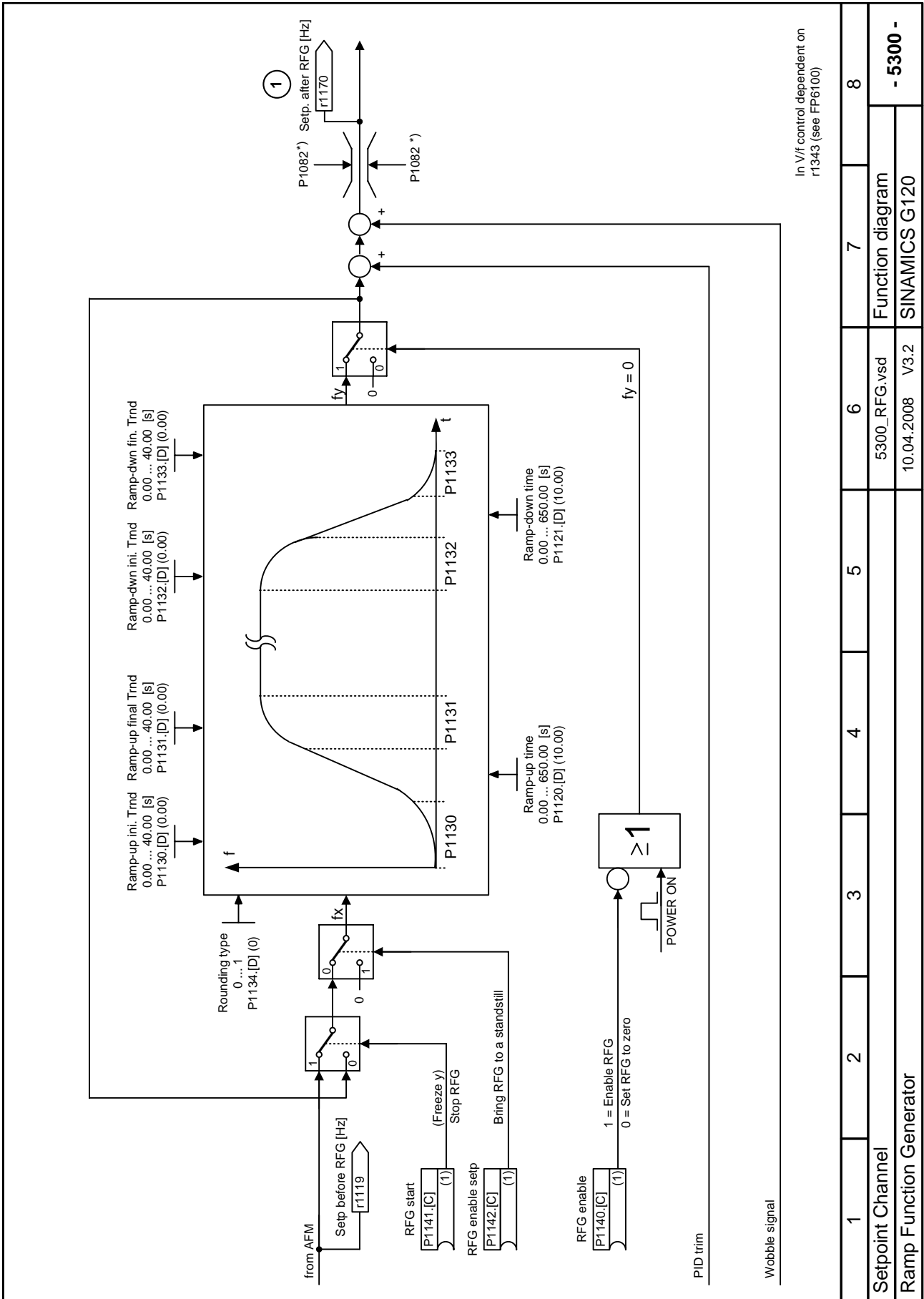


Fig. 2-42 5200 – Additional Frequency Modifications (AFM)

1	2	3	4	5	6	7	8	
Setpoint channel								Function diagram
Additional Frequency Modifications (AFM)								SINAMICS G120
								- 5200 -



In V/f control dependent on r1343 (see FP6100)

1	2	3	4	5	6	7	8
Setpoint Channel						Function diagram	
Ramp Function Generator						SINAMICS G120	
5300_RFG.vsd						- 5300 -	
10.04.2008 V3.2							

Fig. 2-43 5300 – Ramp Function Generator

2.9 V/f Control

Function diagrams

6100 – Overview of V/f Control for inverters with PM240	2-367
6200 – Overview of V/f Control for inverters with PM250/PM260	2-368

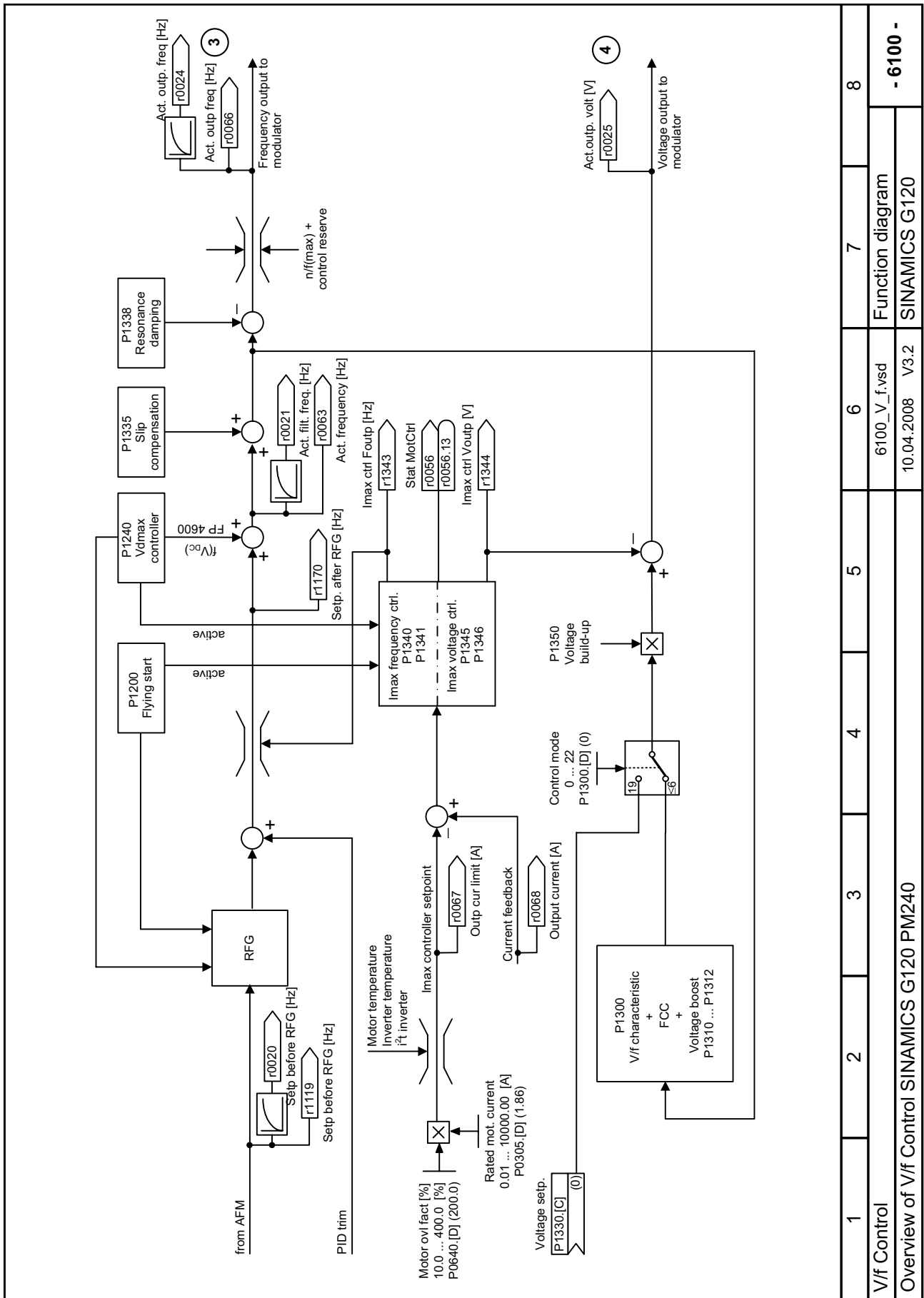


Fig. 2-44 6100 – Overview of V/f Control for inverters with PM240

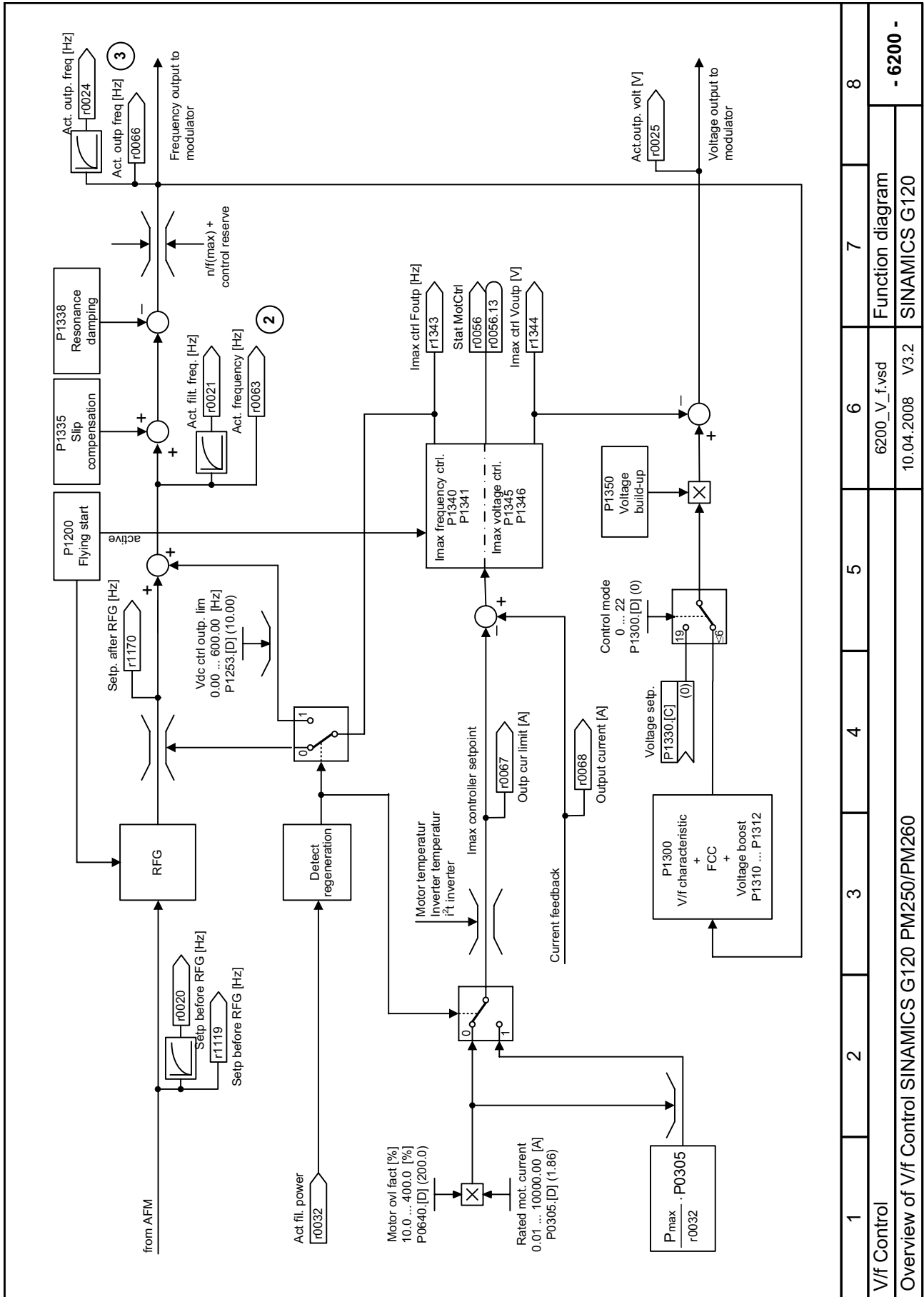


Fig. 2-45 6200 – Overview of V/f Control for inverters with PM250/PM260

1	2	3	4	5	6	7	8
V/f Control							
Overview of V/f Control SINAMICS G120 PM250/PM260							
6200_V_f.vsd						Function diagram	
10.04.2008						V3.2	
						- 6200 -	

2.10 Vector Control

Function diagrams

7000 – Overview of Speed Control without Encoder (SLVC): P1300 = 20 & P1501 = 0	2-370
7010 – Overview of Speed Control with Encoder (VC): P1300 = 21 & P1501 = 0	2-371
7200 – Overview of Torque Control without Encoder (SLVC): P1300 = 22/20 & P1501 = 1	2-372
7210 – Overview of Torque Control with Encoder (VC): P1300 = 23/21 & P1501 = 1	2-373
7500 – Speed Controller without Encoder (SLVC): P1300 = 20 & P1501 = 0	2-374
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7700 – Torque Control and Torque Limitation without Encoder (SLVC)	2-376
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7800 – Flux Setpoint (SLVC and VC)	2-378
7900 – Current Controller & Observer Model without Encoder (SLVC)	2-379
7910 – Current Controller & Observer Model with Encoder (VC)	2-380
8000 – Analog outputs and display values	2-381

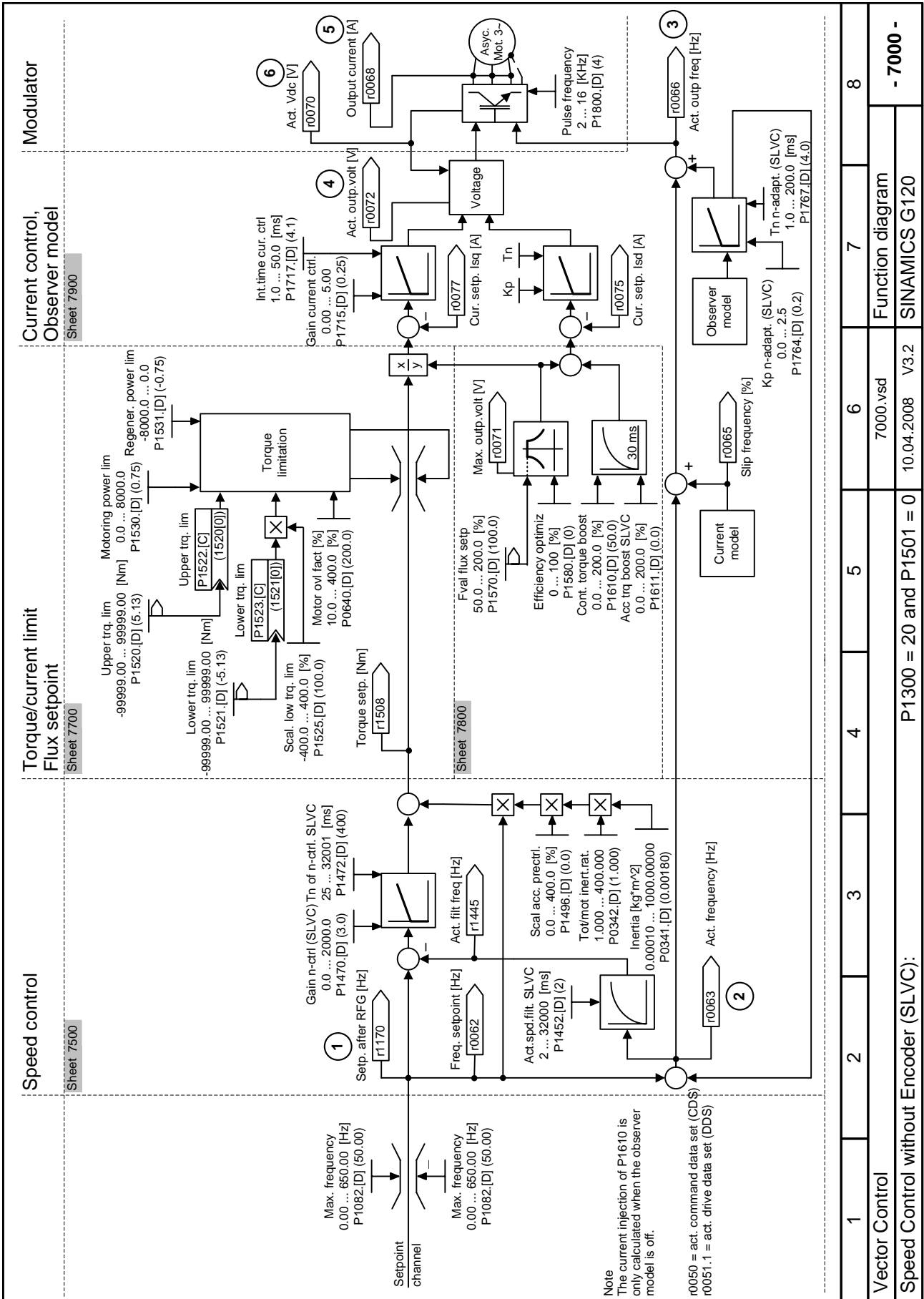


Fig. 2-46 7000 – Overview of Speed Control without Encoder (SLVC): P1300 = 20 & P1501 = 0

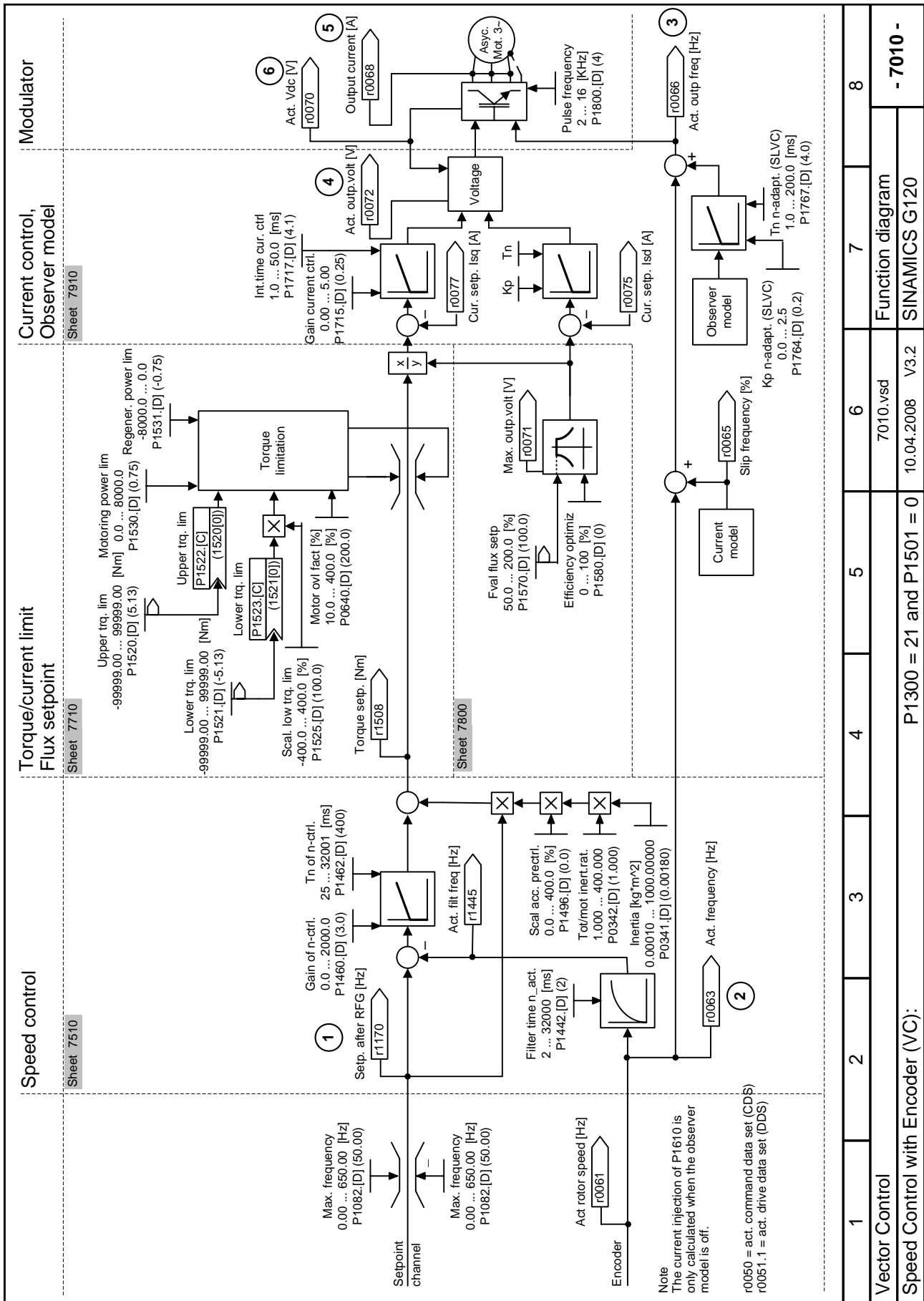


Fig. 2-47 7010 – Overview of Speed Control with Encoder (VC): P1300 = 21 & P1501 = 0

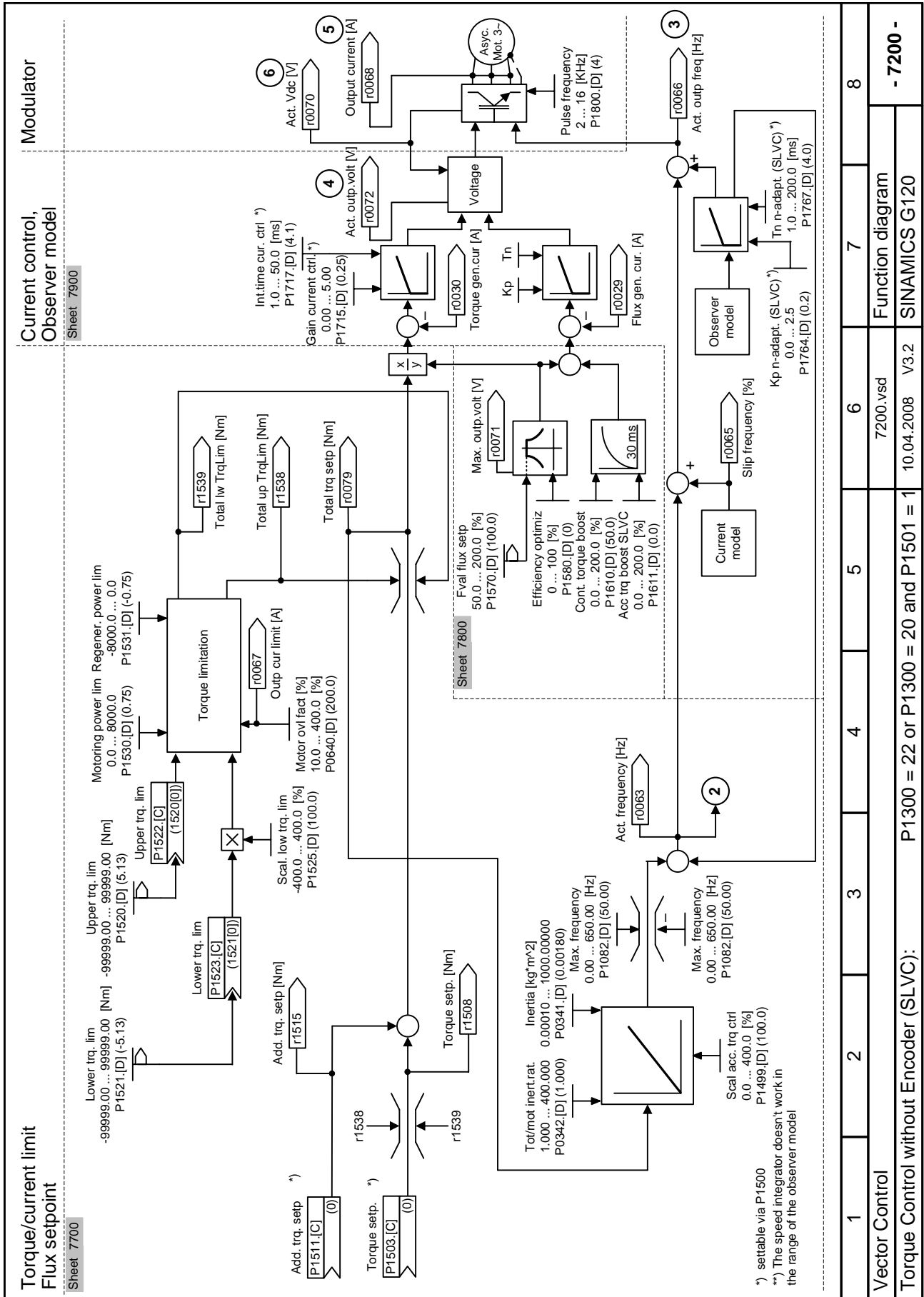


Fig. 2-48 7200 – Overview of Torque Control without Encoder (SLVC): P1300 = 22/20 & P1501 = 1

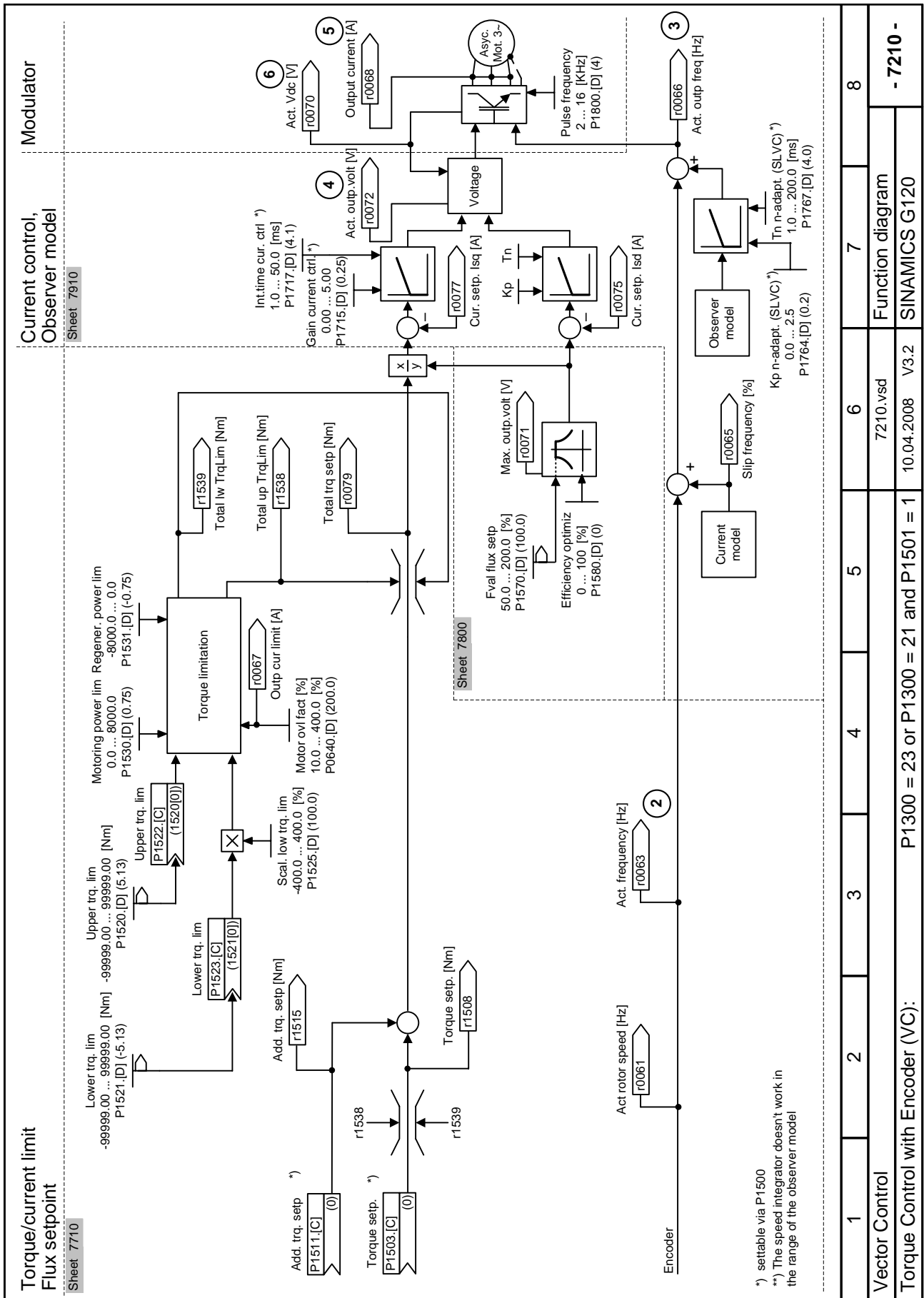


Fig. 2-49 7210 – Overview of Torque Control with Encoder (VC): P1300 = 23/21 & P1501 = 1

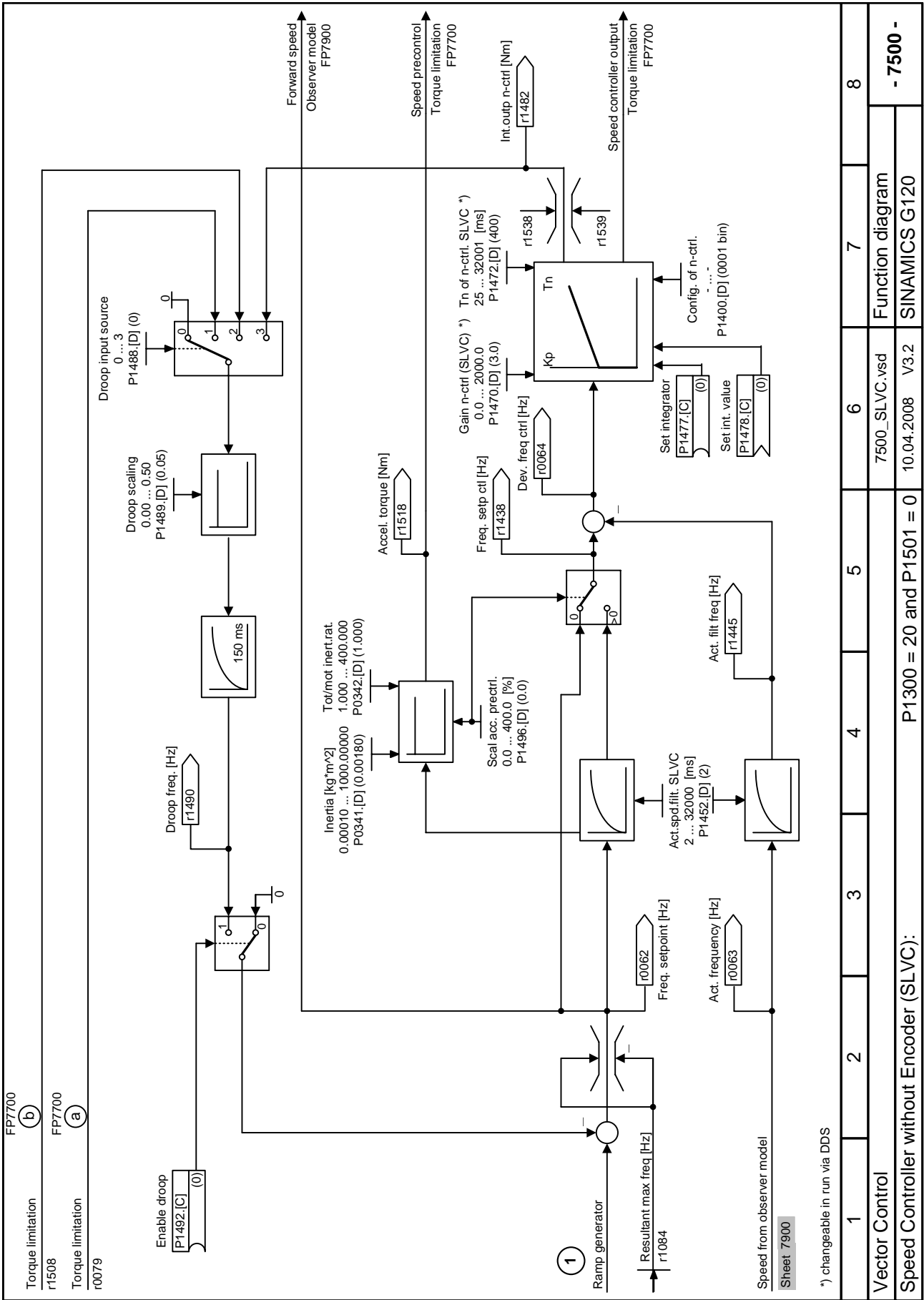


Fig. 2-50 7500 – Speed Controller without Encoder (SLVC): P1300 = 20 & P1501 = 0

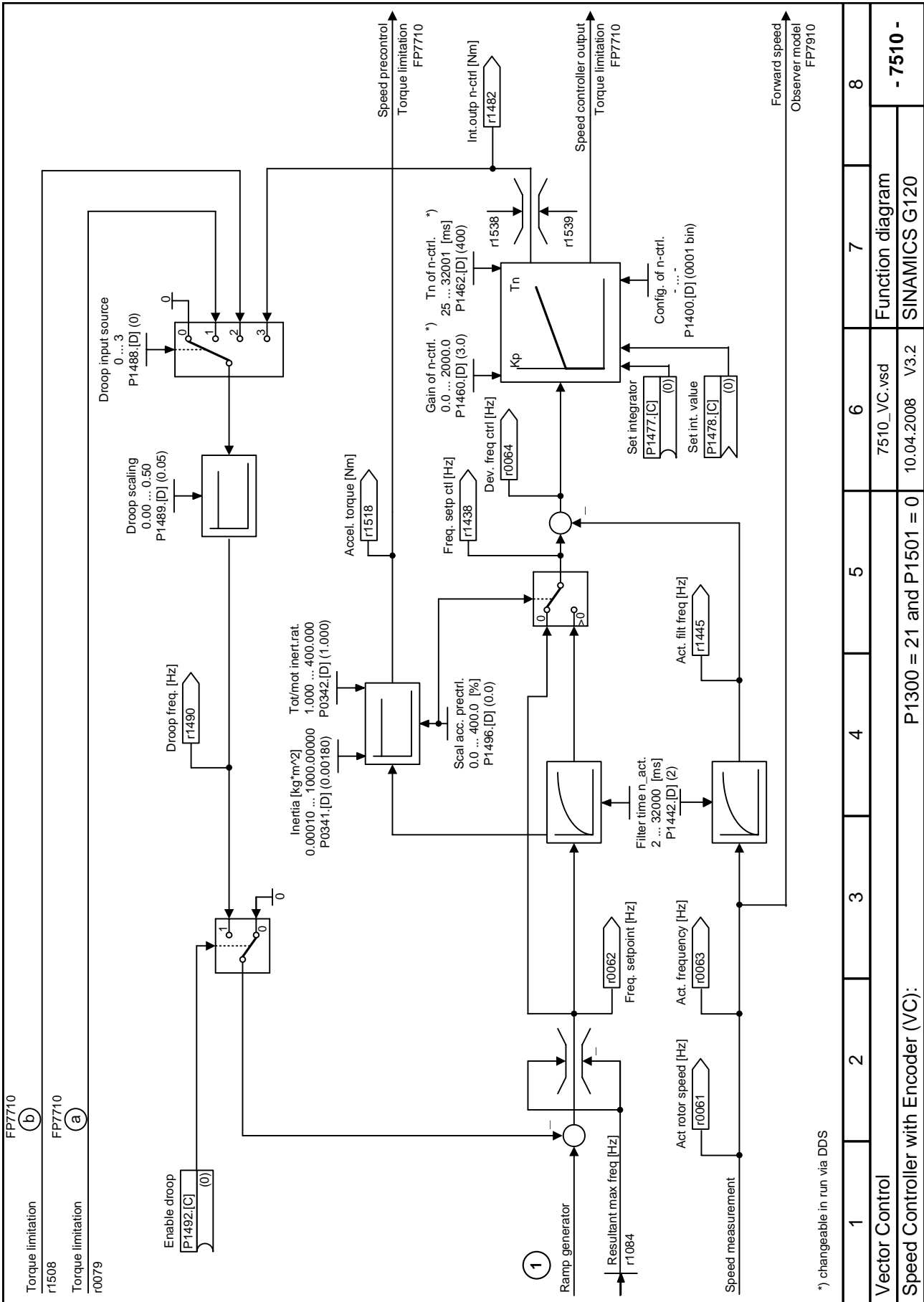


Fig. 2-51 7510 – Speed Controller with Encoder (VC): P1300 = 21 & P1501 = 0

*) changeable in run via DDS

1	2	3	4	5	6	7	8
Vector Control							
Speed Controller with Encoder (VC):							
7510_VC.vsd				Function diagram			
P1300 = 21 and P1501 = 0				SINAMICS G120			
10.04.2008				V3.2			
- 7510 -							

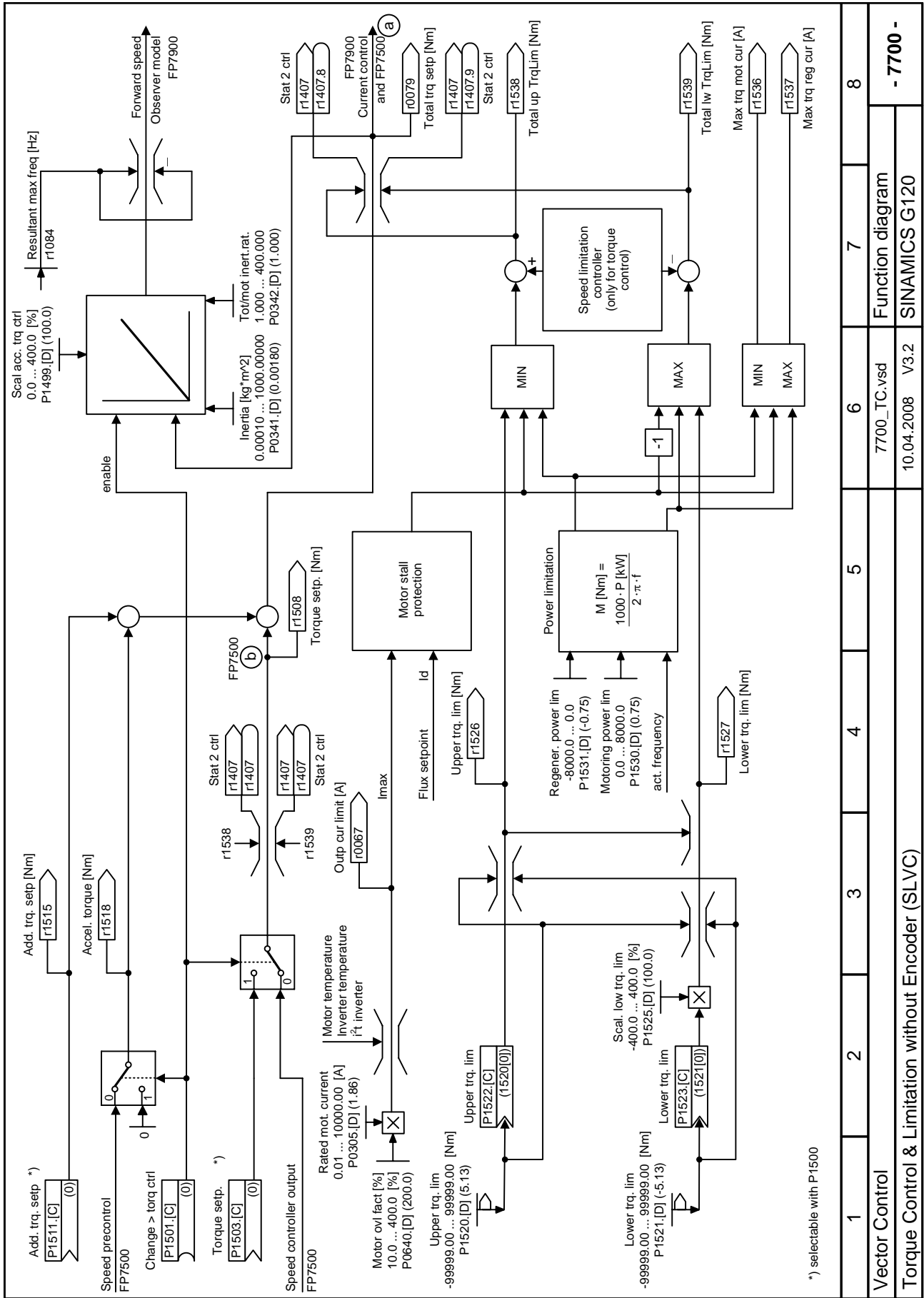


Fig. 2-52 7700 – Torque Control and Torque Limitation without Encoder (SLVC)

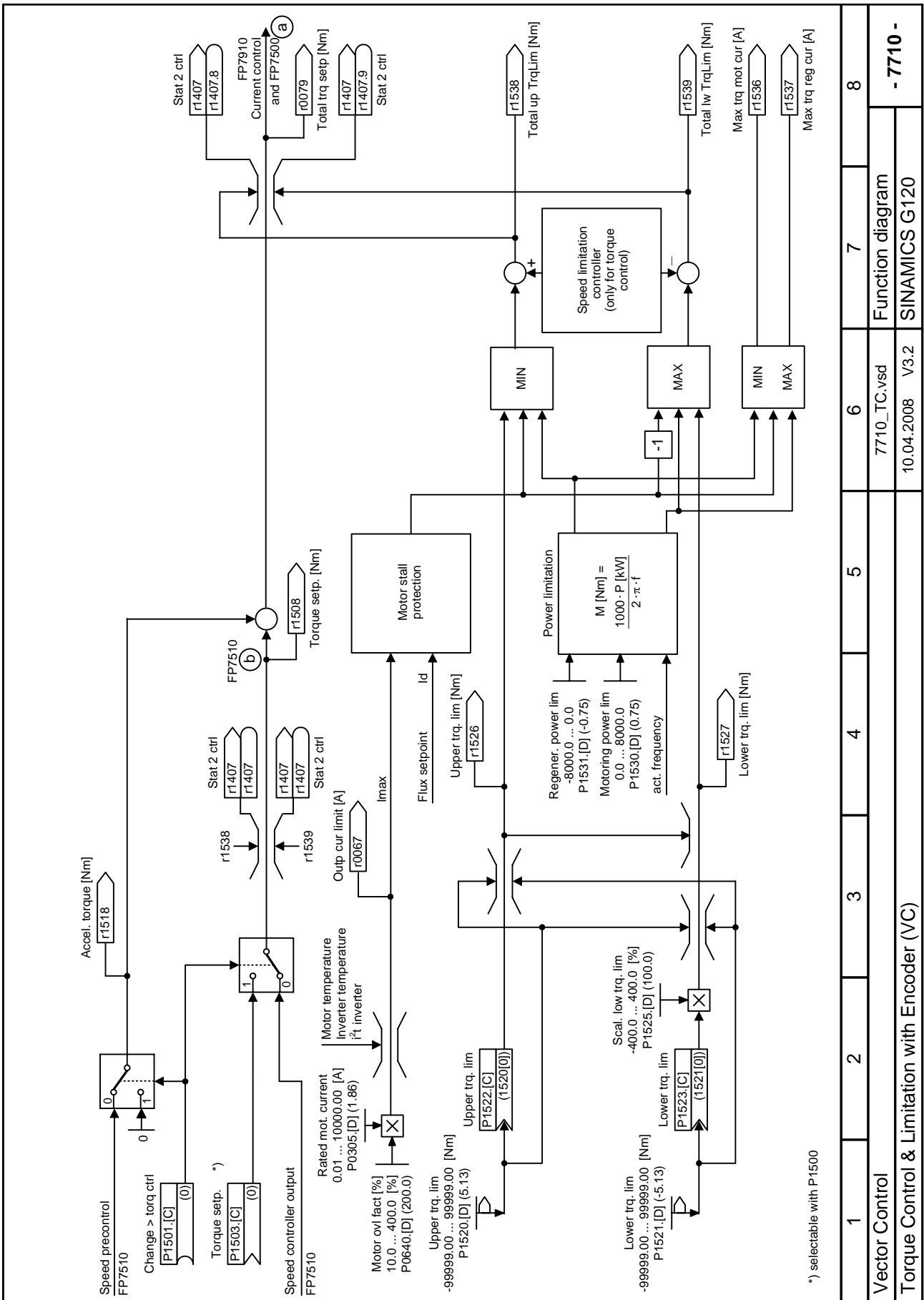


Fig. 2-53 7710 – Torque Control and Torque Limitation with Encoder (VC)

1	2	3	4	5	6	7	8	
Vector Control							Function diagram	
Torque Control & Limitation with Encoder (VC)							SINAMICS G120	
7710_TC.vsd							10.04.2008 V3.2	
							- 7710 -	

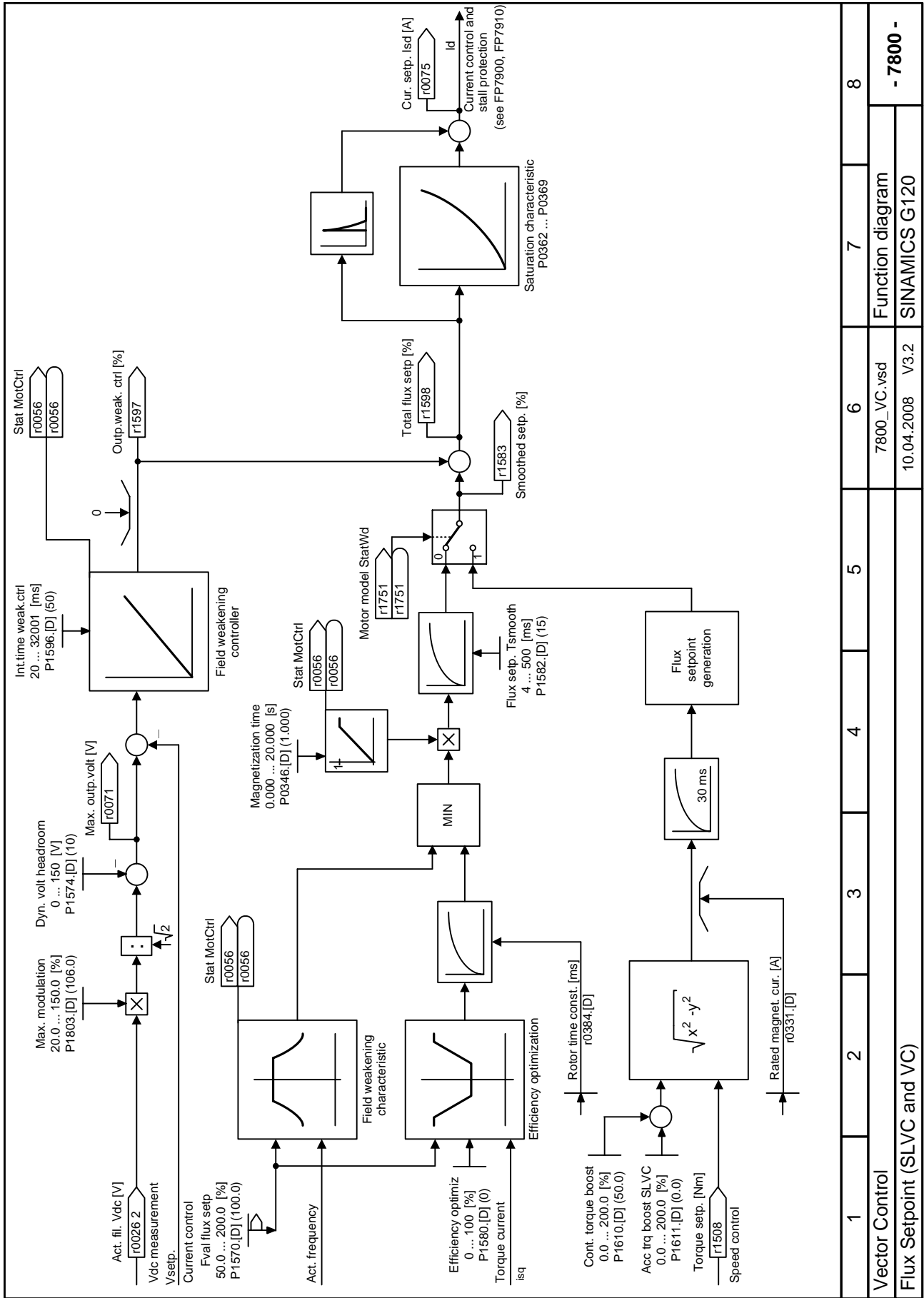


Fig. 2-54 7800 – Flux Setpoint (SLVC and VC)

1	2	3	4	5	6	7	8
Vector Control							
Flux Setpoint (SLVC and VC)							
7800_VC.vsd				Function diagram		- 7800 -	
10.04.2008				V3.2		SINAMICS G120	

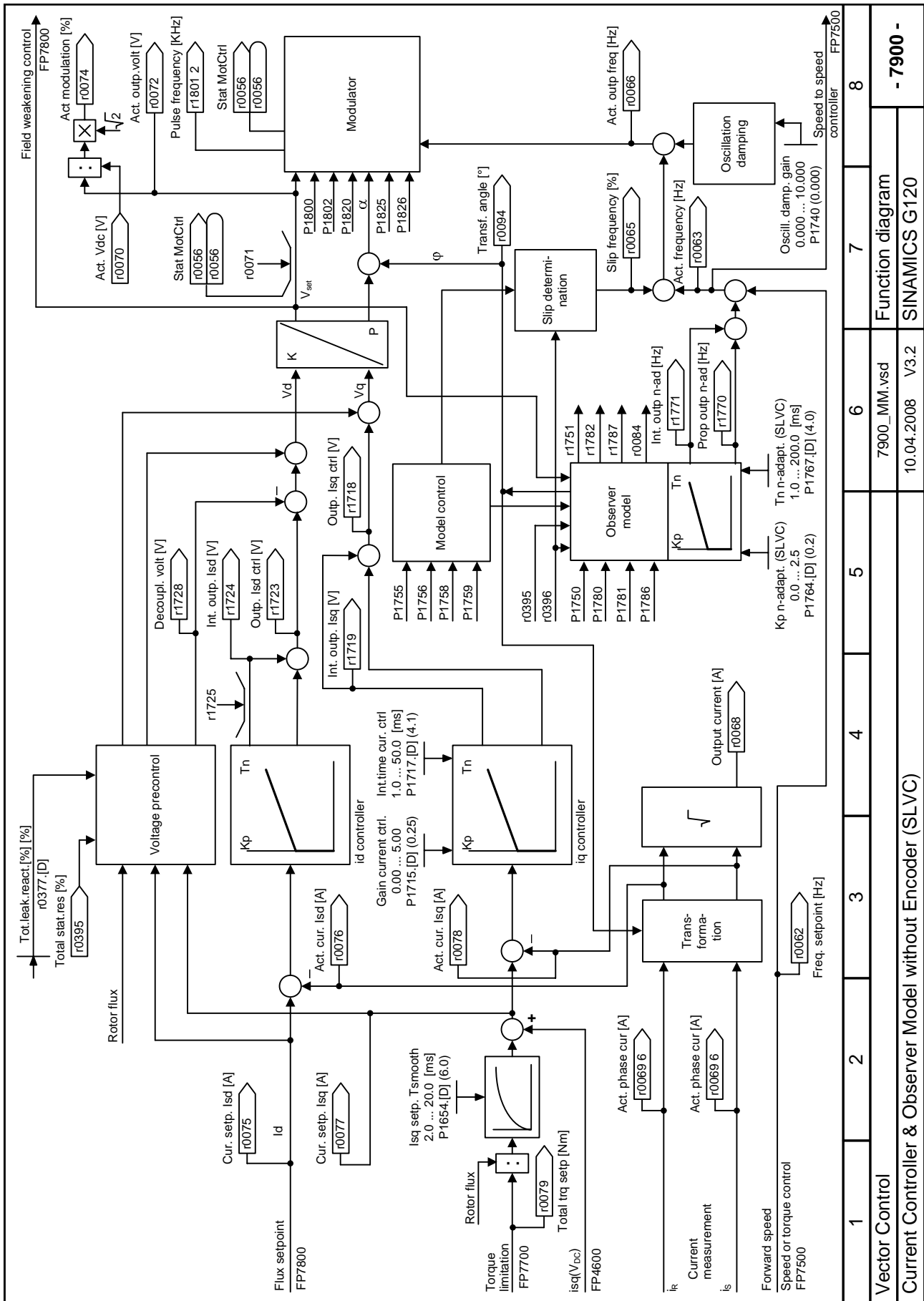


Fig. 2-55 7900 – Current Controller & Observer Model without Encoder (SLVC)

1	2	3	4	5	6	7	8
Vector Control							
Current Controller & Observer Model without Encoder (SLVC)							
7900_MM.vsd				Function diagram			
10.04.2008				V3.2			
- 7900 -							

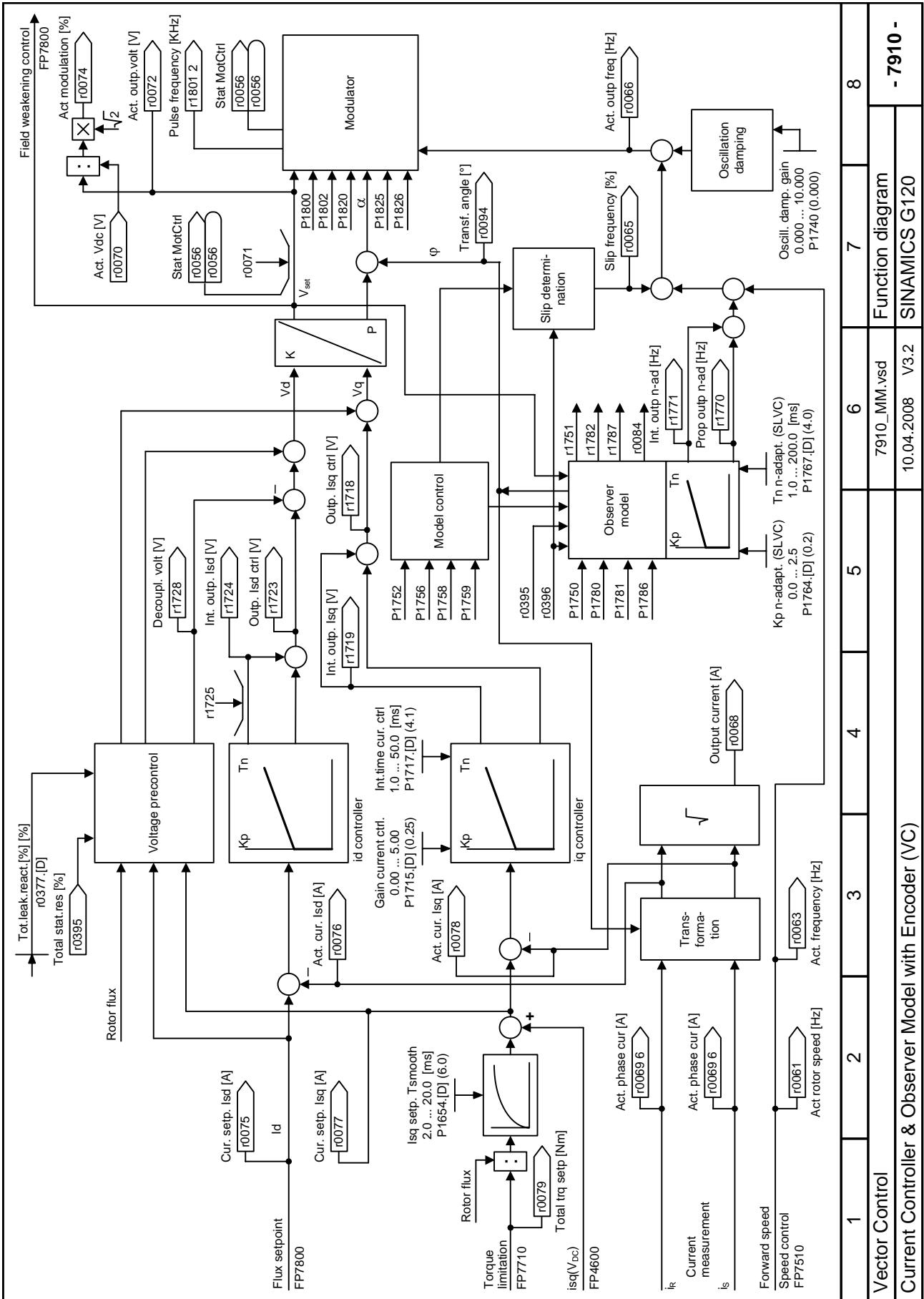


Fig. 2-56 7910 – Current Controller & Observer Model with Encoder (VC)

1	2	3	4	5	6	7	8
Vector Control							
Current Controller & Observer Model with Encoder (VC)							
7910_MM.vsd						Function diagram	
10.04.2008						V3.2	
						- 7910 -	
						SINAMICS G120	

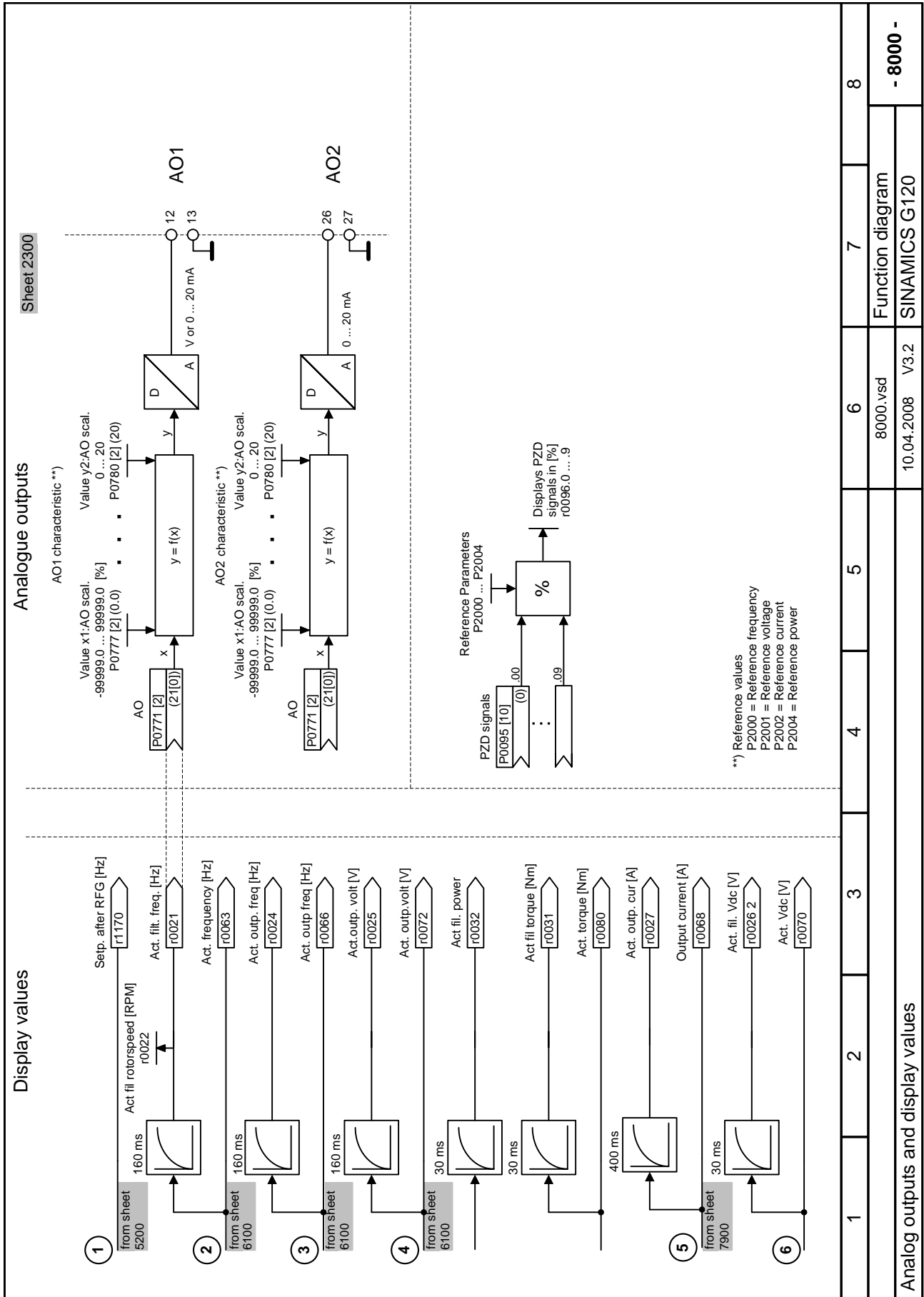


Fig. 2-57 8000 – Analog outputs and display values

Faults and Warnings

3

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3.1 Faults and Warnings – Overview


Fault messages

In the event of a fault, the inverter stops with the preset reaction (refer to „Reaction:“ in Section 3.2) and changes to the state „fault“. If there are reactions in brackets it is possible to change to this fault reaction via parameters P2100 and P2101.

Fault messages are stored in parameter r0947 under their code number (e.g. F0003 = 3). The associated error value is found in parameter r0949. The value 0 is entered if a fault has no error value. It is furthermore possible to read out the point in time that a fault occurred (r0948) and the number of fault messages (P0952) stored in Parameter r0947.

Fault acknowledge

To reset the fault, one of the methods listed below can be used:

1. Cycle the power to the drive
2. Press the  Button on the OP
3. Via a Digital Input (factory setting: DI2)
4. Via control word 1, bit 07

Safety Fault acknowledge

1. Set control word 1, bit 00 to 0
2. Set control word 1, bit 07 to 1

Exception: F00395, F01601. For acknowledgement see description of the fault.

Warning messages

Warning messages are stored in parameter r2110 under their code number (e.g. A0503 = 503) and can be read out from there.

3.2 List of Fault and Warning Messages

Product: G120, Version: 3202700, Language: eng

F00001 (N)	Overcurrent
Reaction:	OFF 2
Acknowledge:	refer to section 3.1
Cause:	<ul style="list-style-type: none"> • Motor power (p0307) does not correspond to the inverter power (r0206) • Motor lead short circuit • Earth faults
Remedy:	<p>Check the following:</p> <ul style="list-style-type: none"> • Motor power (p0307) must correspond to inverter power (r0206). • Cable length limits must not be exceeded. • Motor cable and motor must have no short-circuits or earth faults. • Motor parameters must match the motor in use. • Value of stator resistance (p0350) must be correct. • Motor must not be obstructed or overloaded. • Increase Ramp-up time (p1120). • Reduce Starting boost level (p1312).
Note:	<p>r0949 = 0: HW reported r0949 = 1: SW reported</p>

F00002	Overvoltage
Reaction:	OFF 2
Acknowledge:	refer to section 3.1
Cause:	<ul style="list-style-type: none"> • Main supply voltage too high • Motor is in regenerative mode <p>r0949 = 0: HW reported r0949 = 1 or 2: SW reported</p>
Remedy:	<p>Check the following:</p> <ul style="list-style-type: none"> • Supply voltage (p0210) must lie within limits indicated on rating plate. • Ramp-down time (p1121) must match inertia of load. • Required braking power must lie within specified limits.
Note:	Regenerative mode can be caused by fast ramp downs or if the motor is driven by an active load.

F00003	Undervoltage
Reaction:	OFF 2
Acknowledge:	refer to section 3.1
Cause:	<ul style="list-style-type: none"> • Main supply failed. • Shock load outside specified limits. <p>r0949 = 0: HW reported r0949 = 1 or 2: SW reported</p>
Remedy:	Check Supply voltage (p0210).
Note:	If the CU is powered externally with DC 24 V and the power module is not connected, A0503 appears. Although this alarm appears, the inverter does not trip with F0003 after an ON command.

F00004 Inverter Over Temperature

Reaction: OFF 2

Acknowledge: refer to section 3.1

- Cause:**
- Inverter overloaded
 - Ventilation inadequate
 - Pulse frequency too high
 - Ambient temperature too high
 - Fan inoperative

- Remedy:** Check the following:
- Load or load cycle too high?
 - Motor power (p0307) must match inverter power (r0206)
 - Pulse frequency must be set to default value
 - Ambient temperature too high?
 - Fan must turn when inverter is running
 - Additional for FS FX and GX:
 - r0949 = 1: Rectifier overtemperature
 - r0949 = 2: Ambient overtemperature
 - r0949 = 3: EBOX overtemperature
-

F00005 Inverter I2T

Reaction: OFF 2

Acknowledge: refer to section 3.1

- Cause:**
- Inverter overloaded.
 - Load cycle too demanding.
 - Motor power (p0307) exceeds inverter power capability (r0206).

- Remedy:** Check the following:
- Load cycle must lie within specified limits.
 - Motor power (p0307) must match inverter power (r0206)
-

F00006 Chip temperature rise exceeds critical levels.

Reaction: OFF 2

Acknowledge: refer to section 3.1

- Cause:**
- Load at start-up is too high
 - Load step is too high
 - Ramp-up rate is too fast

- Remedy:** Check the following:
- Load or load step too high?
 - Increase ramp-up time (P1120).
 - Motor power (p0307) must match inverter power (r0206).
 - Use setting P0290 = 0 or 2 for preventing F00006.
-

F00011 Motor Over Temperature

Reaction: OFF 2 (OFF 3)

Acknowledge: refer to section 3.1

Cause: Motor overloaded

- Remedy:** Check the following:
- Load or load step too high?
 - Motor nominal overtemperatures (p0626 - p0628) must be correct
 - Motor temperature warning level (p0604) must match

F00012	Inverter temp. signal lost
Reaction:	OFF 1 (OFF 2)
Acknowledge:	refer to section 3.1
Cause:	Wire breakage of inverter temperature (heat sink) sensor.
Remedy:	

F00015	Motor temperature signal lost
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	Open or short circuit of motor temperature sensor. If signal loss is detected, temperature monitoring switches over to monitoring with the motor thermal model.
Remedy:	Check the following: <ul style="list-style-type: none"> • the connection of the motor temperature sensor to the control unit • the setting of p0601
Note:	If the CU is powered externally with DC 24 V, but no supply voltage to the power module available, the loss of the motor temperature signal will not be detected.

F00020	Mains Phase Missing
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	Fault occurs if one of the three input phases are missed and the pulses are enabled and drive is loaded
Remedy:	Check the input wiring of the mains phases

F00021	Earth fault
Reaction:	OFF 2
Acknowledge:	refer to section 3.1
Cause:	Fault occurs if the sum of the phase currents is higher than 5 % of the nominal inverter current.
Remedy:	
Note:	Framesizes D to F: this fault only occurs on inverters that have 3 current sensors.

F00022	Power stack HW fault
Reaction:	OFF 2
Acknowledge:	refer to section 3.1
Cause:	This hardware fault caused by the following events: <ul style="list-style-type: none"> • DC-link overcurrent = short circuit of IGBT • Short circuit of chopper
Remedy:	Contact Service Department. Change inverter power module

F00023	Output phase fault
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	One output phase is disconnected.
Remedy:	Check motor connection.

F00025	F3E DC-link Ripple
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	Large ripples on the DC link.
Remedy:	Contact Service Department.

F00026 **Supply to Gate Driver Not Enabled**
Reaction: OFF 2
Acknowledge: refer to section 3.1
Cause: Gate driver not enabled. Can be caused also by a synchronization error of the safety state machines.
Remedy: Contact Service Department.

F00027 **Overcurrent on W phase**
Reaction: OFF 2
Acknowledge: refer to section 3.1
Cause: This hardware fault caused by the following events:
 • Over current trip on W phase
 • Earth Fault
Remedy: Check Inverter and Motor wiring

F00028 **Power limit exceeded during regeneration**
Reaction: OFF 2
Acknowledge: refer to section 3.1
Cause: Occurs if motor is driven by an active load, causing motor to go into excessive regeneration.
 Can occur at very high load inertias, when ramping down.
Remedy: • Reduce regeneration from active load
 • Reduce ramp down rate
 • Increase I_{max} regeneration limit in p1253
Note: Fault only occurs with V/f control.

F00029 **EM brake overcurrent**
Reaction: OFF 2
Acknowledge: refer to section 3.1
Cause:
Remedy:

F00030 **Fan failure**
Reaction: OFF 2 (OFF 3)
Acknowledge: refer to section 3.1
Cause: Fan no longer working.
Remedy: Need a new fan.

F00035 **Auto restart after n**
Reaction: OFF 2 (OFF 3)
Acknowledge: refer to section 3.1
Cause: Auto restart attempts exceed value of p1211.
Remedy:

F00041 Motor Data Identification Failure**Reaction:** OFF 2**Acknowledge:** refer to section 3.1**Cause:** Motor data identification failed.

- r0949 = 0: Load missing
 - r0949 = 1: Current limit level reached during identification.
 - r0949 = 2: Identified stator resistance less than 0.1% or greater than 100%.
 - r0949 = 3: Identified rotor resistance less than 0.1% or greater than 100%.
 - r0949 = 4: Identified stator reactance less than 50% and greater than 500%
 - r0949 = 5: Identified main reactance less than 50% and greater than 500%
 - r0949 = 6: Identified rotor time constant less than 10ms or greater than 5s
 - r0949 = 7: Identified total leakage reactance less than 5% and greater than 50%
 - r0949 = 20: Identified IGBT on-voltage less than 0.5 V or greater than 10 V
 - r0949 = 30: Current controller at voltage limit
 - r0949 = 40: Inconsistence of identified dataset, at least one identification failed
 - r0949 = 41: Writing of calculated magnetizing current P0320 failed
 - r0949 = 42: Writing of identified stator resistance failed
 - r0949 = 43: Writing of identified rotor resistance P0354 failed
 - r0949 = 44: Writing of identified rotor time constant P0622 failed
 - r0949 = 45: Writing of identified mutual reactance P0360 failed
 - r0949 = 46: Writing of identified stator leakage reactance P0356 failed
 - r0949 = 47: Writing of identified rotor leakage reactance P0358 failed
 - r0949 = 48: Writing of identified on voltage P1825 failed.
 - r0949 = 49: Writing of the identified dead time compensation P1828 failed
- Percentage values based on the impedance $Z_b = V_{mot,nom} / \sqrt{3} / I_{mot,nom}$

Remedy: Check the following:

- r0949 = 0: is the motor connected to the inverter.
- r0949 = 1 - 49: are the motor data in p0304 - p0311 correct.
- Check what type of motor wiring is required (star, delta).

F00042 Speed Control Optimisation Failure**Reaction:** OFF 2**Acknowledge:** refer to section 3.1**Cause:** Motor data identification failed.

- r0949 = 0: Time out waiting for stable speed
- r0949 = 1: Inconsistent readings

Remedy: Make sure motor has data been entered correctly.
Motor data identification needs to have been done.

F00051 Parameter EEPROM Fault**Reaction:** OFF 2**Acknowledge:** refer to section 3.1**Cause:** Read or write failure while access to EEPROM.

This can also be caused by the EEPROM being full, too many parameters have been changed.

Remedy:

- Must be Power Cycled to cancel this bug as some parameters may not be read correct.
- Factory Reset and new parameterization, if power cycle does not remove fault.
- Change inverter control unit.
- Change some parameters back to default values if the EEPROM is full, then power cycle.

- Note:**
- r0949 = 1: EEPROM Full
 - r0949 = 1000 + Block No: Reading data block failed
 - r0949 = 2000 + Block No: Reading data block timeout
 - r0949 = 3000 + Block No: Reading data block CRC failed
 - r0949 = 4000 + Block No: Writing data block failed
 - r0949 = 5000 + Block No: Writing data block timeout
 - r0949 = 6000 + Block No: writing data block verify failed
 - r0949 = 7000 + Block No: Reading data block at wrong time
 - r0949 = 8000 + Block No: writing data block at wrong time
 - r0949 = 9000 + Block No: Factory Reset did not work because restart or power failure

F00052 Power stack SW fault

Reaction: OFF 2

Acknowledge: refer to section 3.1

Cause: Read failure for power stack information or invalid data.

Remedy:

- Check connection between inverter Power Module and inverter Control Unit

- Powercycle inverter Control Unit
- Change inverter Power Module
- Change inverter Control Unit

- Note:**
- r0949 = 1: Failed reading PS identity
 - r0949 = 2: PS identity wrong
 - r0949 = 3: Failed reading PS version
 - r0949 = 4: PS version wrong
 - r0949 = 5: Start of Part 1 PS data wrong
 - r0949 = 6: PS number of temp. sensor wrong
 - r0949 = 7: PS number of application wrong
 - r0949 = 8: Start of Part 3 PS data wrong
 - r0949 = 9: Reading PS data string wrong
 - r0949 = 10: PS CRC failed
 - r0949 = 11: PS is blank
 - r0949 = 15: Failed CRC of PS block 0
 - r0949 = 16: Failed CRC of PS block 1
 - r0949 = 17: Failed CRC of PS block 2
 - r0949 = 20: PS invalid
 - r0949 = 30: Directory size wrong
 - r0949 = 31: Directory ID wrong
 - r0949 = 32: Invalid block
 - r0949 = 33: File size wrong
 - r0949 = 34: Data section size wrong
 - r0949 = 35: Block section size wrong
 - r0949 = 36: RAM size exceeded
 - r0949 = 37: Parameter size wrong
 - r0949 = 38: Device header wrong
 - r0949 = 39: Invalid file file pointer
 - r0949 = 40: Scaling block version wrong
 - r0949 = 41: Calibration block version wrong
 - r0949 = 50: Wrong serial number format
 - r0949 = 51: Wrong serial number format start
 - r0949 = 52: Wrong serial number format end
 - r0949 = 53: Wrong serial number format month
 - r0949 = 54: Wrong serial number format day
 - r0949 = 1000 + addr: PS read data failed
 - r0949 = 2000 + addr: PS write data failed
 - r0949 = 3000 + addr: PS read data wrong time
 - r0949 = 4000 + addr: PS write data wrong time
 - r0949 = 5000 + addr: PS read data invalid
 - r0949 = 6000 + addr: PS read data invalid

F00055 BOP-EEPROM Fault

Reaction: OFF 2 (OFF 3)

Acknowledge: refer to section 3.1

Cause: Read or write failure while saving non-volatile parameter to EEPROM on BOP whilst parameter cloning.

- Remedy:**
- Factory Reset and new parameterization
 - Change BOP
 - r0949 = 5096 : Use a BOP with a bigger EEPROM
 - r0949 = 9160 : Use a BOP with a smaller EEPROM
- Note:**
- r0949 = 1000 + Block No: Reading data block failed
 - r0949 = 3000 + Block No: Reading data block CRC failed
 - r0949 = 4000 + Block No: Writing data block failed
 - r0949 = 5096 : BOP EEPROM too Small
 - r0949 = 6000 + Block No: writing data block verify failed
 - r0949 = 7000 + Block No: Reading data block at wrong time
 - r0949 = 8000 + Block No: writing data block at wrong time
 - r0949 = 9160 : Drive EEPROM too Small

F00056 BOP not fitted

Reaction: OFF 2 (OFF 3)

Acknowledge: refer to section 3.1

Cause: Trying to initiate parameter cloning without BOP fitted.

Remedy: Fit BOP and try again.

F00057 BOP fault

Reaction: OFF 2 (OFF 3)

Acknowledge: refer to section 3.1

- Cause:**
- Parameter cloning with empty BOP.
 - Parameter cloning with invalid BOP.

Remedy: Download to BOP or replace BOP.

F00058 BOP contents incompatible

Reaction: OFF 2 (OFF 3)

Acknowledge: refer to section 3.1

Cause: Trying to initiate parameter cloning with BOP created on another type of drive.

Remedy: Download to BOP from this type of drive.

F00060 Asic Timeout

Reaction: OFF 2

Acknowledge: refer to section 3.1

Cause: Internal communications failure:

- r0949 = 0: HW reported Link Fail
- r0949 = 1: SW reported Link Fail
- r0949 = 2: After Hotswap, setup frame didn't transmit
- r0949 = 3: After Hotswap, feedback enabled but no message received
- r0949 = 5: No comms with PS asic during powerup to read ps data
- r0949 = 6: Feedback is not disabled for reading PS data
- r0949 = 7: During PS download, message didn't transmit to disable feedback

Remedy: Check connection between inverter power module and inverter control unit

Fault appears sporadically:

- Communication failure due to EMC problems
- Check - and if necessary - improve EMC
- Use EMC filter

Fault appears immediately when mains voltage is applied and an ON command is given.

- If fault persists, change inverter.
 - Contact Service Department.
-

F00061 Par Cl. MMC-PS not fitted Fault

Reaction: OFF 2

Acknowledge: refer to section 3.1

Cause: MMC-PS Cloning Failed.

- r0949 = 0: MMC-PS not connected or incorrect MMC-PS type or MMC failed to initialize for automatic cloning
- r0949 = 1: MMC-PS cannot write to MMC
- r0949 = 2: MMC-PS file not available
- r0949 = 3: MMC-PS cannot read the file
- r0949 = 4: MMC-PS problems in the clone File (e.g CRC)

Remedy:

- r0949 = 0: Use MMC with FAT12 or FAT16 format or correct MMC-PS type, or fit a MMC-PS to drive.
 - r0949 = 1: Check MMC (e.g is MMC full) - Format MMC again to FAT16
 - r0949 = 2: Put the correct named file in the correct directory /USER/SINAMICS/DATA.
 - r0949 = 3: Make sure file is accessible - Recreate file if possible
 - r0949 = 4: File has been changed - Recreate File
-

F00062 Par Cl. MMC-PS contents invalid

Reaction: OFF 2

Acknowledge: refer to section 3.1

Cause: File exists but the contents are not valid Control Word Corruption.

Remedy: Recopy and ensure operation completes.

F00063 Par Cl. MMC-PS contents incompatible

Reaction: OFF 2

Acknowledge: refer to section 3.1

Cause: File exists but was not the correct drive type.

Remedy: Ensure clone from compatible drive type.

F00064	Drive attempted to do an automatic clone during startup
Reaction:	OFF 2
Acknowledge:	refer to section 3.1
Cause:	No Clone00.bin File in the correct directory /USER/SINAMICS/DATA.
Remedy:	If a automatic clone is required: - Insert MMC with correct File and power cycle. If no automatic clone is required: - Remove MMC if not needed and power cycle. - Reset P8458 = 0 and power cycle.
Note:	Fault can only be cleared by a power cycle.

F00070	PLC setpoint fault
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	No setpoint values from PLC during telegram off time
Remedy:	<ul style="list-style-type: none"> • Check and improve - if necessary - the fieldbus specific off time value in p2040 (DP) / p8840 (PN) • Acknowledge fault • if fault persists, change inverter control unit

F00071	USS setpoint fault
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	No setpoint values from USS during telegram off time
Remedy:	Check and if necessary improve the monitoring time in the STARTER SW while getting the command source. Check USS master

F00072	USS Setpoint Fault
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	No setpoint values from USS during telegram off time
Remedy:	Check USS master

F00073	Control Panel setpoint fault
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	No setpoint values from Control Panel during telegram off time
Remedy:	<ul style="list-style-type: none"> • Check and improve - if necessary - the value in p3984 • Acknowledge fault • if fault persists, change inverter control unit

F00080	AI lost Input Signal
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	<ul style="list-style-type: none"> • Broken wire • Signal out of limits
Remedy:	

F00085	External Fault
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	External fault triggered via command input via control word 2, bit 13."
Remedy:	<ul style="list-style-type: none"> • Check P2106. • Disable control word 2 bit 13 as command source. • Disable terminal input for fault trigger.

F00090 Encoder feedback loss

Reaction: OFF 2

Acknowledge: refer to section 3.1

Cause: Signal from encoder lost (check fault value r0949):

- r0949 = 0: Encoder signal lost.
- r0949 = 1: Encoder loss detected due to sudden speed change (i.e. speed change detected on encoder in a single scan > value in P0492).
- r0949 = 2: Encoder signal lost whilst running at low speed.
- r0949 = 5: Encoder not configured in p0400, but required for sensed control (p1300 = 21 or 23).
- r0949 = 6: Encoder not found, but configured in p0400.
- r0949 = 7: Encoder loss detected due to motor stalled.

Remedy: Stop the inverter.

- r0949 = 2: Increase value of p0494 or reduce value of p1120 and p1121.
- r0949 = 5: select encoder type via p0400.
- r0949 = 5: select SLVC mode (p1300 = 20 or 22).
- r0949 = 7: select SLVC mode (p1300 = 20 or 22).
- Check connections between encoder and inverter.
- Check that encoder not faulty (select p1300 = 0, run at fixed speed, check encoder feedback signal in r0061)
- Increase encoder loss threshold in p0492.

F00100 Watchdog Reset

Reaction: OFF 2

Acknowledge: refer to section 3.1

Cause: Software Error

Remedy: Contact Service Department.
Change inverter control unit.

F00101 (N) Stack Overflow

Reaction: OFF 2

Acknowledge: refer to section 3.1

Cause: Software error or processor failure.

Remedy: Contact Service Department.
Change inverter control unit

F00221 PID Feedback below min. Value

Reaction: OFF 2 (OFF 3)

Acknowledge: refer to section 3.1

Cause: PID Feedback below min. value p2268.

Remedy:

- Change value of p2268.
- Adjust feedback gain.

F00222 PID Feedback above max. Value

Reaction: OFF 2 (OFF 3)

Acknowledge: refer to section 3.1

Cause: PID feedback above max. value p2267.

Remedy:

- Change value of p2267.
- Adjust feedback gain.

F00350	Configuration vector for the drive failed
Reaction:	OFF 2
Acknowledge:	refer to section 3.1
Cause:	<p>During startup the drive checks if the configuration vector (SZL vector) has been programmed correctly and if hw matches the programmed vector. If not the drive will trip.</p> <ul style="list-style-type: none"> • r0949 = 1: Internal Failure - No HW Configuration Vector available. • r0949 = 2: Internal Failure - No SW Configuration Vector available. • r0949 = 11: Internal Failure - CU Code not supported. • r0949 = 12: Internal Failure - SW Vector not possible. • r0949 = 13: Wrong power module fitted. • r0949 > 1000: Internal failure - Wrong IO Board fitted.
Remedy:	<p>Internal Failures cannot be fixed. r0949 = 13 - Make sure the right power module is fitted.</p>
Note:	Fault needs power cycle to be acknowledged.

F00395	Acceptance Test / Confirmation pending
Reaction:	OFF 2
Acknowledge:	refer to section 3.1
Cause:	<p>This fault occurs after a Powermodul (PM) / Control Unit (CU) Swap or a Startup Clone. It can also be caused by a faulty read from the EEPROM, see F0051 for more details. The parameterset after a CU swap or a startup clone could have changed and might not match the application. This parameterset needs to be checked before the drive can start a motor.</p> <ul style="list-style-type: none"> • r0949 = 3/4: Swap of PM/CU • r0949 = 5: Startup Clone via MMC has been performed • r0949 = 10: Before the last power up an acceptance test was pending due to a swap or a startup clone.
Remedy:	<p>The current parameterset needs to be checked and confirmed by clearing the fault. With Safety Units an Acceptance Test needs to be performed. Follow the the steps of the Acceptance Log which is part of the Operating Instructions.</p>

F00400 (N)	PROFIBUS: DS101/DB101 (control pannel) failure
Reaction:	OFF 2
Acknowledge:	refer to section 3.1
Cause:	Timeout, trigger fault,...
Remedy:	Restart C2 connection.

F00401 (N)	Wrong telegram configured in p0922.
Reaction:	OFF 2
Acknowledge:	refer to section 3.1
Cause:	Different configuration in controller and device.
Remedy:	<ul style="list-style-type: none"> • r0949 = 0: Check p0922 and/or PROFINET controller configuration.

F00452	Belt Failure
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	<p>Load conditions on motor indicate belt failure or mechanical fault.</p> <ul style="list-style-type: none"> • r0949 = 0: trip low torque/speed • r0949 = 1: trip high torque/speed
Remedy:	<p>Check the following:</p> <ul style="list-style-type: none"> • No breakage, seizure or obstruction of drive train. Apply lubrication if required. • If using an external speed sensor, check the following parameters for correct function: <ul style="list-style-type: none"> • p2192 (delay time for permitted deviation) • If using the torque envelope, check parameters:

F00453 Motor Stalled

Reaction: OFF 2

Acknowledge: refer to section 3.1

- Cause:**
- In SLVC or VC (p1300 greater than 20) and Ramp rate too fast
 - In SLVC or VC (p1300 greater than 20) and done OFF2 and RUN onto a spinning motor without Flying start enabled
 - In SLVC (p1300 = 20 or 21) and load too large at very low frequency
 - In SLVC or VC (p1300 greater than 20) and no motor connected or motor too small for inverter
 - In VC, the motor cable phase sequence (U-V-W) and the encoder cable wiring may be wired up incorrectly.
 - The speed controller settings are not optimised to the application. This can cause instabilities.

- Remedy:**
- Reduce ramp rate in p1120
 - Enable flying start (p1200 equal to 1)
 - Increase boost in p1611
 - Connect motor or use larger motor for this inverter or use V/f mode (p1300 < 20).
 - Correct the wiring to the motor and / or the encoder as required. Confirm the rotation direction in V/f control mode and compare parameters r0061 and r0021.
 - Optimise the speed controller settings (gain and integration time).

A00501 Current Limit

Reaction: NONE

Acknowledge: refer to section 3.1

- Cause:**
- Motor power does not correspond to the inverter power
 - Motor leads are too long
 - Earth faults

- Remedy:** Check the following:
- Motor power (P0307) must correspond to inverter power (r0206).
 - Cable length limits must not be exceeded.
 - Motor cable and motor must have no short-circuits or earth faults
 - Motor parameters must match the motor in use
 - Value of stator resistance (P0350) must be correct
 - Motor must not be obstructed or overloaded
 - Increase Ramp-up time (P1120)
 - Reduce Starting boost level (P1312)

A00502 Overvoltage limit

Reaction: NONE

Acknowledge: refer to section 3.1

Cause:

Remedy: If this warning is displayed permanently, check drive input voltage.

A00503 UnderVoltage Limit

Reaction: NONE

Acknowledge: refer to section 3.1

- Cause:**
- Main supply failed
 - Main supply and consequently DC-link voltage (r0026) below specified limit.

Remedy: Check main supply voltage.

A00504	Inverter OverTemperature
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	Warning level of inverter heat sink temperature, warning level of chip junction temperature, or allowed change in temperature on chip junction is exceeded, resulting in pulse frequency reduction and/or output frequency reduction (depending on parameterization in P0290).
Remedy:	<p>Note:</p> <p>r0037 = 0: Heat sink temperature r0037 = 1: Chip junction temperature (includes heat sink)</p> <p>Additional for FS FX and GX:</p> <p>r0037 = 2: Rectifier overtemperature r0037 = 3: Ambient overtemperature r0037 = 4: EBOX overtemperature</p> <p>Check the following:</p> <ul style="list-style-type: none"> • Ambient temperature must lie within specified limits • Load conditions and load steps must be appropriate • Fan must turn when drive is running

A00505	Inverter I2T
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	Warning level exceeded, current will be reduced if parameterized (P0610 = 1)
Remedy:	Check that load cycle lies within specified limits.

A00506	IGBT junction temperature rise warning
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	Overload warning. Difference between heat sink and IGBT junction temperature exceeds warning limits.
Remedy:	Check that load steps and shock loads lie within specified limits.

A00507	Inverter temp. signal lost
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	Inverter temperature signal loss
Remedy:	<p>Check the following:</p> <ul style="list-style-type: none"> • the connection of the motor temperature sensor to the control unit • the setting of p0601

A00511	Motor OverTemperature I2T
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	<ul style="list-style-type: none"> • Motor overloaded. • Load cycles or load steps too high.
Remedy:	<p>Independently of the kind of temperature determination check:</p> <ul style="list-style-type: none"> • P0604 motor temperature warning threshold • P0625 motor ambient temperature <p>If P0601 = 0 or 1, check the following:</p> <ul style="list-style-type: none"> • Check if name plate data are correct? If not perform quick commissioning. Accurate equivalent circuit data can be found by performing motor identification (P1910 = 1). • Check if motor weight (P0344) is reasonable. Change if necessary. • Via P0626, P0627, P0628 the standard overtemperatures can be changed, if the motor is not a Siemens standard motor. <p>If P0601 = 2, Check the following:</p> <ul style="list-style-type: none"> • Check if temperature shown in r0035 is reasonable. • Check if the sensor is a KTY84 (other sensors are not supported)
A00522	I2C read out timeout
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	The cyclic access to the UCE Values and powerstack temperatures via the i2c bus (Mega Master) is disturbed
Remedy:	
A00523	Output fault
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	One phase of output is disconnected.
Remedy:	Check motor connection.
A00525	F3E Dclink Ripple
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	Large dclink ripple
	Large dclink ripple detected
Remedy:	
A00530	One of the fans has failed
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	Fan no longer working.
Remedy:	Replace Fan.
A00535	Braking Resistor Overload
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	<p>The breaking energy is too large.</p> <p>The breaking resistor is not suited for the application.</p>
Remedy:	<p>Reduce the breaking energy.</p> <p>Use a breaking resistor with a higher rating.</p>

A00541	Motor Data Identification Active
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	Motor data identification (P1910) selected or running.
Remedy:	

A00542	Speed Control Optimisation Active
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	Speed Control Optimisation (P1960) is selected or running.
Remedy:	

A00544	Speed deviation
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	The actual speed has exceeded the maximal speed (status bit r2197.12) or the speed deviation is larger than specified (status bit 2197.7).
Remedy:	The motoring or regenerative load is too large.

A00564	MMC Plugged During Operation
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	MMC-PS Plugged During Operation and none was present at startup. Therefore, possible corruption of current dataset on next power cycle from Automatic Cloning at Startup.
Remedy:	Remove MMC-PS from drive.

A00590	Encoder feedback loss warning
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	<ul style="list-style-type: none"> • Encoder signal lost. • Inverter has changed-over to sensorless vector control.
Remedy:	<p>Stop inverter and then</p> <ul style="list-style-type: none"> • Check the speed encoder, if an encoder is not being used, set P0400 to 0 and select the sensorless closed-loop vector control mode (P1300 = 20 or 22). • Check the encoder connections • Check whether the encoder is operating correctly (set P1300 = 0 and operate the drive at a fixed speed and check the encoder signal in r0061. • Increase the permissible speed deviation in P0492.

A00600	RTOS Overrun Warning
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	Internal time slice overrun
Remedy:	Contact Service Department

A00700	Fieldbus: Parameter or configuration error
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	wrong parameter and/or configuration telegram.
Remedy:	check parameter and/or configuration telegram. PROFINet: check used GSDML.

A00701	Fieldbus: DoubleWord error
Reaction:	NONE
Acknowledge:	refer to section 3.1

Cause: error in double word reference table.
Remedy: power cycle.

A00702 **Fieldbus: no bus/network detection**
Reaction: NONE
Acknowledge: refer to section 3.1
Cause: connection error, no bus initialization (no master), no clear bus signal, ...
Remedy: check the cables and the bus/network hardware.

A00703 **Fieldbus: no reference values**
Reaction: NONE
Acknowledge: refer to section 3.1
Cause: no or empty control word 1 received.
Remedy: check bus transmission.

A00704 **PROFIBUS: loose of links**
Reaction: NONE
Acknowledge: refer to section 3.1
Cause: lost subscriber information.
Remedy: temporary, if permanent the fault detection is activated.

A00705 **Fieldbus: timeout actual value**
Reaction: NONE
Acknowledge: refer to section 3.1
Cause: no actual data from CUP.
Remedy: temporary, if permanent the fault detection is activated.

A00706 **Fieldbus: fatal SW error**
Reaction: NONE
Acknowledge: refer to section 3.1
Cause: e.g. hardware check, communication, V1SL stack, ...
Remedy: if permanent power cycle, reload firmware.

A00707 **PROFIBUS: wrong PB address at startup**
Reaction: NONE
Acknowledge: refer to section 3.1
Cause: wrong DIP switch or parameter settings for PROFIBUS address.
Remedy: check DIP switch and/or P0918.

A00708 **--- not used ---**
Reaction: NONE
Acknowledge: refer to section 3.1
Cause:
Remedy:

A00709 **--- not used ---**
Reaction: NONE
Acknowledge: refer to section 3.1
Cause:
Remedy:

A00710 **CB communication error**
Reaction: NONE
Acknowledge: refer to section 3.1
Cause: Communication with CB (communication board) is lost.

Remedy: Check CB hardware.

A00711 CB configuration error

Reaction: NONE

Acknowledge: refer to section 3.1

Cause: CB (communication board) reports a configuration error.

Remedy: Check CB parameters.

A00910 Vdc-max controller de-activated

Reaction: NONE

Acknowledge: refer to section 3.1

Cause: Occurs

- if main supply voltage (P0210) is permanently too high.
- if motor is driven by an active load, causing motor to go into regenerative mode.
- at very high load inertias, when ramping down.

Remedy: Check the following:

- Input voltage must lie within range.
- Load must be match.
- In certain cases apply braking resistor.

A00911 Vdc-max controller active

Reaction: NONE

Acknowledge: refer to section 3.1

Cause: Vdc max controller is active; so ramp-down times will be increased automatically to keep DC-link voltage (r0026) within limits (P2172).

Remedy: Check the following:

- Supply voltage must lie within limits indicated on rating plate.
- Ramp-down time (P1121) must match inertia of load.

Note: Higher inertia requires longer ramp times; otherwise, apply braking resistor.

A00912 Vdc-min Controller active

Reaction: NONE

Acknowledge: refer to section 3.1

Cause: Vdc min controller will be activated if DC-link voltage (r0026) falls below minimum level (P2172). The kinetic energy of the motor is used to buffer the DC-link voltage, thus causing deceleration of the drive! So short mains failures do not necessarily lead to an undervoltage trip.

Remedy:

A00921 AO parameters not set properly

Reaction: NONE

Acknowledge: refer to section 3.1

Cause: AO parameters (P0777 and P0779) should not be set to identical values, since this would produce illogical results.

Remedy: Check the following:

- Parameter settings for output identical
- Parameter settings for input identical
- Parameter settings for output do not correspond to AO type

Set P0777 and P0779 to different values.

A00922 No load applied to inverter

Reaction: NONE

Acknowledge: refer to section 3.1

Cause: No Load is applied to the inverter.

As a result, some functions may not work as under normal load conditions.

Remedy: Check that motor is connected to inverter.

A00923 Both JOG Left and JOG Right are requested

Reaction: NONE

Acknowledge: refer to section 3.1

Cause: Both JOG right and JOG left (P1055/P1056) have been requested. This freezes the RFG output frequency at its current value.

Remedy: Do not press JOG right and left simultaneously.

A00936 PID Autotuning Active

Reaction: NONE

Acknowledge: refer to section 3.1

Cause: PID Autotuning (P2350) selected or running

Remedy: Warning disappears when PID Autotuning has finished.

A00952 Belt Failure Detected

Reaction: NONE

Acknowledge: refer to section 3.1

Cause: Load conditions on motor indicate belt failure or mechanical fault.

Remedy: Check the following:

- No breakage, seizure or obstruction of drive train.
- Apply lubrication if required.

If using an external speed sensor, check the following parameters for correct function:

- P2192 (delay time for permitted deviation)

If using the torque envelope, check parameters:

- P2182 (threshold frequency f1)
- P2183 (threshold frequency f2)
- P2184 (threshold frequency f3)
- P2185 (upper torque threshold 1)
- P2186 (lower torque threshold 1)
- P2187 (upper torque threshold 2)
- P2188 (lower torque threshold 2)
- P2189 (upper torque threshold 3)
- P2190 (lower torque threshold 3)
- P2192 (delay time for permitted deviation)

F01600 passivated STO with drive fault**Reaction:** OFF 2 (OFF 3)**Acknowledge:** refer to section 3.1**Cause:** A passivated safe torque off (passivated STO) has been initiated by hardware due to a drive fault:

- r0949 = 33: passivated STO acknowledge after a drive fault requires the OFF first and then an acknowledge (ACK) to remove the safety fault! If however ACK is given first and then the OFF command, the alarm handler clears the fault but the passivated STO is still active.
- r0949 = 100: The signals for the STO signal are not consistent on P1.
- r0949 = 101: Maximum frequency exceeded on P1 during activation of the SS1. The estimated frequency deviates from the SBR monitoring ramp, when the drive is in vector mode (with p1300 > 19).
- r0949 = 104: Communication timeout of processor P1 during forced dynamisation. The handshaking via hardware lines has failed.
- r0949 = 106: Error in the mechanical brake or in the brake feedback path of P1.
- r0949 = 107: Error in the gate driver or feedback path of P1. Can happen when either the hardware measurement circuit on the PM is faulty or when P1 and P2 are not synchronised.
- r0949 = 108: Signal debounce error on P1. The safety signals are not consistent for a longer time than parameterised in p9650/p9850.
- r0949 = 109: Hardware detection fault on P1. The hardware type (safety or non-safety module) has not been recognised correctly.
- r0949 = 200: The STO signals are not consistent on P2. Avoid fast periodic activation and deactivation of the STO.
- r0949 = 201: Maximum frequency exceeded on activation of SS1 on P2.
- r0949 = 202: Maximum frequency exceeded on activation of SLS in P2.
- r0949 = 204: Communication timeout of processor P2 during forced dynamisation. The handshaking via hardware lines has failed.
- r0949 = 206: Error in the mechanical brake or in the brake feedback path of P2
- r0949 = 207: Error in gate driver or feedback path on P2.
- r0949 = 208: Signal debounce error on P2. The safety signals are not consistent for a longer time than parameterised in p9650/p9850.
- r0949 = 209: Hardware type could not be detected correctly on P2.

Remedy:

- r0949 = 100 or 200
Increase the ramping times p1120/p1121 or the safety tolerance p9691/p9891, check the motor parameters (p0394 - p0311) or run the motor identification (p1910) again. Decrease the rate of switching the safety signals or lower the cycle time of the PLC.
- r0949 = 101 or 201
Increase the ramping times p1120/p1121 or the safety tolerance p9691/p9891, check the motor parameters (p0394 - p0311) or run the motor identification (p1910) again.
- r0949 = 102 or 202
Increase the ramping times (p1120, p1121) so that deviation between reference and actual frequency is minimized.
Increase the safety tolerance p9691/p9891 or run the motor identification (p1910) again for better tuning of the observer and controllers.
- r0949 = 104 or 204
Acknowledge the fault once more
Power cycle the CU
- r0949 = 106 or 206
Check connection with safe brake module and mechanical brake
Check the 24 V power supply for safe brake module
- r0949 = 107 or 207
Check connection between CU and power module
Power cycle the CU
- r0949 = 108 or 208
Decrease the rate of switching the safe digital inputs or increase debounce delay time p9650/p9850.
- r0949 = 109 or 209
Power cycle the CU
Change CU

F01601	System startup error
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	<p>System startup error. Error during the startup initialisation after a PowerCycle or HotSwap. This error is critical and cannot be acknowledged. A restart (hotswap or power cycle) of the drive is required!</p> <ul style="list-style-type: none"> • r0949 = 0: Handshaking error on P1. Either an unexpected reboot by P1 or a synchronisation error during startup. Please power-cycle the inverter module again or perform a hotswap. • r0949 = 1: Handshaking error on P2. Either a faulty reboot by P2 or a synchronisation error during startup. Please power-cycle the inverter module or perform a hotswap. • r0949 = 100: Version error detected by P1. The safety version number is not identical on P1 and P2. • r0949 = 101: Startup semaphore is wrong on P1. Can happen if commissioning was not finished properly before performing a power cycle. There might also be a problem of the EEPROM. • r0949 = 102: Error with semaphore on P1. The drive loads default parameters instead of the user settings. • r0949 = 103: Error with initial and first hardware type detection on P1. The hardware type (standard or safety module) could not be identified. Either the control board is faulty or affected by EMC. • r0949 = 104: Timeout error on P1 while waiting for communication with P2. • r0949 = 105: Error on P1 during hardware exchange phase. Processors have not agreed on same type of hardware platform. • r0949 = 106: Timeout error on P1 in hardware detection state. Handshaking with P2 failed. • r0949 = 107: Checksum error on P1. The safety parameters are not consistent in EEPROM. • r0949 = 108: Error on P1 during parameter transfer to P2. The correct safety parameters are not available on P2 due to a communication problem. • r0949 = 109: Timeout error on P1 during parameter transfer to P2 due to different safety checksums on P1 and P2. The parameter transfer to P2 has failed. • r0949 = 110: Timeout error on P1 during forced dynamisation and processor self test. • r0949 = 111: Timeout error on P1 when leaving the safety commissioning at startup. • r0949 = 112: Checksum error on P1 during processor initialisation. • r0949 = 200: Version error detected by P2. The safety version number (see r9770) is not identical on P1 and P2. • r0949 = 201: Startup semaphore is wrong on P2. Can happen if commissioning was not finished properly before performing a power cycle. There might also be a problem of the EEPROM. • r0949 = 202: Error with semaphore on P2. The drive loads default parameters instead of the user settings. • r0949 = 203: Error on P2 with initial and first hardware detection. The hardware type (standard or safety module) could not be identified. Either the control board is faulty or affected by EMC. • r0949 = 204: Timeout error on P1 while waiting for communication with P2. • r0949 = 205: Error on P1 during hardware exchange phase. Processors have not agreed on same type of hardware platform. • r0949 = 206: Timeout error on P2 during hardware detection. Handshaking with P1 failed. • r0949 = 207: Checksum error on P2. The safety parameters on P2 are not consistent. • r0949 = 208: Error on P2 during parameter transfer from P1. The safety parameters on P2 are not valid due to a communication problem. • r0949 = 209: Timeout error on P2 during parameter transfer from P1. Possibly due to different checksums on P1 and P2. • r0949 = 210: Timeout error on P2 in startup dynamisation phase. The communication failed. • r0949 = 211: Timeout error on P2 when leaving the initial safety commissioning. • r0949 = 212: Checksum error on P2 during processor initialisation.
Remedy:	<ul style="list-style-type: none"> • Power-cycle CU (since fault F1601 cannot be acknowledged). • Make sure that CU is connected correctly to PM. • Reduce EMC.

F01610	EEPROM inconsistent
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	EEPROM data inconsistency error: <ul style="list-style-type: none"> • r0949 = 100: Safety parameters have not been written correctly to EEPROM on P1. Try to load parameters again. • r0949 = 200: EEPROM data inconsistency error on P2. • r0949 = 2011: Safety parameters have not been written correctly to EEPROM.
Remedy:	Load safety parameters again.

F01611	Defect in cross comparis
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	Data exchange error between processors: <ul style="list-style-type: none"> • r0949 = 100: P2 has entered the safe torque off due to a drive fault on P2 or a subsequent fault of F1600/F1630 • r0949 = 102: Dynamic checksums are different on P1. Cross comparison fault or problem with processor communication. • r0949 = 103: Derived frequency is different on both processors. Cross comparison fault or problem with processor communication. • r0949 = 104: Frequency error on P1 caused by VFM. • r0949 = 105: Inconsistency between r9620 and r9820 detected by P1. • r0949 = 201: Frequency check with error on P2. • r0949 = 202: Dynamic checksums are different on P2. Cross comparison fault or problem with processor communication. • r0949 = 205: Inconsistency between r9620 and r9820 detected by P2.
Remedy:	<ul style="list-style-type: none"> • Reduce EMC. • Perform a forced dynamisation.

F01612	Diff. in hardw. detection
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	The hardware (safety or non-safety hardware) could not be identified. <ul style="list-style-type: none"> • r0949 = 100: Identification error during startup on P1. • r0949 = 101: Runtime detection error on P1. • r0949 = 102: Hardware or software configuration error on P1. • r0949 = 200: Startup error on P2. • r0949 = 201: Runtime detection error on P2. • r0949 = 202: Hardware or software configuration error on P2.
Remedy:	Inverter hardware is faulty or problem in processor communication. Perform a power cycle.

F01614	Frequency consistency fault
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	<p>Error in frequency detection of the frequency estimation circuit (voltage frequency measurement (VFM) module):</p> <ul style="list-style-type: none"> • r0949 = 100: Difference in frequency comparison on P1. • r0949 = 101: VFM estimated frequency too high on P1. • r0949 = 102: VFM estimated frequency too low on P1. • r0949 = 103: Estimated frequency of VFM module was not detected on P1. • r0949 = 104: Error in cycle-time on P1. • r0949 = 200: Frequency deviation on P2. • r0949 = 201: VFM estimated frequency too high on P2. • r0949 = 202: VFM estimated frequency too low on P2. • r0949 = 203: Estimated VFM frequency was not detected on P2. • r0949 = 204: Error in cycle-time on P2. <p>Error can occur with small ramping times. When the VC or SLVC mode is configured (see p1300) the cause can be the same as for fault F0453.</p>
Remedy:	<ul style="list-style-type: none"> • Increase ramping times p1120 and p1121. • Make sure that drive is not at current limit when starting. • See remedies for F0453. • Check hardware speed estimation circuit.
F01615	Error in hardw. environm
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	<ul style="list-style-type: none"> • r0949 = 100: Error in supply voltage 3.3 V or 24 V on the control board. • r0949 = 101: Temperature of control board exceeds the limits.
Remedy:	<ul style="list-style-type: none"> • r0949 = 100: Check supply voltage. Reduce EMC. • r0949 = 101: Check ambient temperature.
F01616	Processor selftest faulty
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	<p>The selftest is started together with the forced dynamisation and must be enabled by setting p9601.1 and p9801.1. The processor selftest has uncovered an error:</p> <ul style="list-style-type: none"> • r0949 = 100: General error on P1. • r0949 = 101: Error in RAM test on P1. • r0949 = 102: Error in ROM test on P1. • r0949 = 103: Error in processor function test on P1. • r0949 = 200: Error in processor self-test on P2.
Remedy:	Run self-test again (set bit 1 in p9601 and p9801 and enter the STO mode, then leave the STO mode again).
F01625	Consecutive no. incorr
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	<p>The consecutive counter checks the consistency of the communication between P1 and P2:</p> <ul style="list-style-type: none"> • r0949 = 100: The consecutive monitoring counter has an error on P1. • r0949 = 101: Processors are out of synchronism. • r0949 = 102: Processor communication has failed. • r0949 = 103: Processor communication has failed or processors are out of synchronism. • r0949 = 200: The consecutive counter has an error on P2.
Remedy:	<ul style="list-style-type: none"> • Acknowledge safety fault. • Restart inverter module or check EMC levels on accumulated faults.

F01630 Safe Brake Control faulty**Reaction:** OFF 2 (OFF 3)**Acknowledge:** refer to section 3.1**Cause:** An error has been detected with the brake feedback.

- r0949 = 0: Problem with the safe brake.
- r0949 = 100: SB-Module: wire break detected or internal braketests failed during dynamisation.
- r0949 = 200: Internal braketests failed during dynamisation.

Remedy:

- Check the wiring of the brake module.
- Exchange brake module.

F01640 PROFIsafe Driver Fault**Reaction:** OFF 2 (OFF 3)**Acknowledge:** refer to section 3.1**Cause:** An error has been detected with the PROFIsafe driver.

- r0949 = 102: A parameterisation error occurred on P1. Wrong value in P9810 (PROFIsafe address). The parameters received from the bus are not correct.
- r0949 = 103: A consecutive number error occurred on P1. Current PROFIsafe message has a wrong sign of life.
- r0949 = 104: A CRC error occurred on P1. The PROFIsafe message checksum was incorrect.
- r0949 = 105: A watchdog error occurred on P1. PROFIsafe driver timed out.
- r0949 = 106: Fail safe values are active on P1.
- r0949 = 107: PROFIsafe default error on P1. Wrong value in P9810 (PROFIsafe address).
- r0949 = 202: A parameterisation error occurred on P2. Wrong value in P9810 (PROFIsafe address). The parameters received from the bus are not correct.
- r0949 = 203: A consecutive number error occurred on P2. Current PROFIsafe message has a wrong sign of life.
- r0949 = 204: A CRC error occurred on P2. The PROFIsafe message checksum was incorrect.
- r0949 = 205: A watchdog error occurred on P2. PROFIsafe driver timed out.
- r0949 = 206: Fail safe values are active on P2.
- r0949 = 207: PROFIsafe default error on P2. Wrong value in P9810 (PROFIsafe address).
- r0949 = 208: PROFIsafe configuration error on P2. The drive configuration does not match the configuration from the bus.

Remedy:

- Check all PROFIsafe settings (including your higher level failsafe control system).
- Acknowledge PROFIsafe fault.

F01649 Internal software error**Reaction:** OFF 2 (OFF 3)**Acknowledge:** refer to section 3.1

Cause:

- r0949 = 1: Buffer overflow on checksum calculation for P1 parameter access functions.
- r0949 = 2: Buffer overflow on checksum calculation for P2 parameter access functions.
- r0949 = 3: Endless safety loop on P1.
- r0949 = 4: Endless safety loop on P2.
- r0949 > 100: Internal or unexpected software fault.

Only for Siemens internal diagnostics.

Remedy: Contact hotline.

F01650	Fault in safety parameters
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	Error during startup or safety commissioning/reset: <ul style="list-style-type: none"> • r0949 = 0: Error during safety commissioning/reset. • r0949 = 1: Checksum error during safety commissioning or safety reset. • r0949 = 2: Error during internal parameter transfer. • r0949 = 3: Error finalizing the buffer transfer. • r0949 = 4: Failure during saving of parameters to EEPROM. • r0949 = 5: Error in safety parameter transfer during safety reset. • r0949 = 11: Communication channel between processors not ready. • r0949 = 2000: Safety commissioning can only be finished by setting parameter p3900.
Remedy:	<ul style="list-style-type: none"> • Perform safety commissioning. • Try leaving via p3900 = 11.
F01655	Fault at processor reset
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	<ul style="list-style-type: none"> • r0949 = 100: Safety reset timeout on P1. • r0949 = 200: Safety reset timeout on P2.
Remedy:	<ul style="list-style-type: none"> • Retrigger the safety reset (perform a hot swap of the inverter module).
F01659	Denial of paramet. change
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	A write request for one or more safety parameters was rejected: <ul style="list-style-type: none"> • r0949 = 0: Problem during finalization of safety parameters. Drive has reloaded the old data. • r0949 = 1: Safety password not set correctly. • r0949 = 3: Tolerance too small (p9691 < p9690). Increase tolerance p9691! • r0949 = 203: Tolerance too small (p9891 < p9890). Increase tolerance!
Remedy:	Acknowledge fault and enter safety commissioning again. If not possible, leave the safety commissioning with p3900 = 11 and operate the drive with the old safety settings.
F01660	Wrong safety checksum
Reaction:	OFF 2 (OFF 3)
Acknowledge:	refer to section 3.1
Cause:	<ul style="list-style-type: none"> • r0949 = 0: Attempt to leave safety commissioning with r9798 != p9799. • r0949 = 1: Attempt to leave safety commissioning with r9898 != p9899. • r0949 = 2: Attempt to leave safety commissioning with r9798 != r9898.
Remedy:	<ul style="list-style-type: none"> • Make sure that checksums in p9798 and p9898 are identical. If not, ensure that parametrisation is identical (p96xx = p98xx). • Set checksum in p9799 or p9899 correctly. • If setting the checksums not successful, leave safety commissioning via p3900 = 11 (cancel commissioning).
A01690	Safety parameter changed
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	The warning indicates that at least one parameter has been changed in the safety commissioning or safety reset.
Remedy:	Finish safety commissioning by setting p3900 = 10 or p3900 = 11 or wait until safety reset is complete.

A01691	SLS signal inconsistency
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	Problem with the consistency of the safety input signals. The drive reduces the frequency according to the settings of the SS1. When zero frequency is reached, the passivated STO is entered and a drive fault is issued.
Remedy:	Check consistency of safety input signals and acknowledge the following safe torque off due to a drive fault.

A01692	Speed for SLS exceeded
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	a) Output frequency when entering the SLS is higher than p9690 and p9692 is configured to trigger a passivated STO with a drive fault. b) Output frequency exceeds the SLS tolerance p9691. In both cases, the frequency is reduced according to the settings for the SS1, then the passivated STO state is entered and a fault is generated.
Remedy:	ad a) Reduce speed before entering the SLS or change the setting in p9692. ad b) increase the tolerance in p9691/p9891 compared to p9690/p9890. In both cases the passivated STO will be entered once zero frequency is reached. Acknowledge the passivated STO and the drive fault.

A01696	Switch-on is inhibited
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	Switching on of the drive not possible and the drive will therefore remain in the READY state (see r0002).
Remedy:	Check if a deactivated gate driver or the current safety mode (STO, SS1, SLS) is inhibiting the start. Check the inhibit bit (r0052.6).

A01697	Wrong safety param. data
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	Semaphore problem at startup. Cannot load last safety parameters. Loading default values instead.
Remedy:	Restart drive (perform power cycle) to load correct safety data.

A01698	Safety commis./reset act
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	The safety reset or the safety commissioning are currently active (selected via p0010 = 95).
Remedy:	Finish commissioning with p3900 = 10 (accept changed) or p3900 = 11 (discard changes) or wait until safety reset is complete.

A01699	Forced dynamis. required
Reaction:	NONE
Acknowledge:	refer to section 3.1
Cause:	Dynamisation timer (see r9660) has expired. A new dynamisation test is required.
Remedy:	Select and then de-select STO (p9601.bit1 and p9801.bit1 must be set).

ASCII-Table

A

The following table contains the decimal and hexadecimal notation of selected ASCII indications.

Table A-1 ASCII-Table (in part)

Indication	Decimal	Hexadecimal	Indication	Dezimal	Hexadecimal
Leerzeichen	32	20	H	72	48
-	45	2D	I	73	49
0	48	30	J	74	4A
1	49	31	K	75	4B
2	50	32	L	76	4C
3	51	33	M	77	4D
4	52	34	N	78	4E
5	53	35	O	79	4F
6	54	36	P	80	50
7	55	37	Q	81	51
8	56	38	R	82	52
9	57	39	S	83	53
A	65	41	T	84	54
B	66	42	U	85	55
C	67	43	V	86	56
D	68	44	W	87	57
E	69	45	X	88	58
F	70	46	Y	89	59
G	71	47	Z	90	5A

List of Abbreviations

Abbreviations used with the SINAMICS G120 Products:

Abbreviation	Meaning
A	
AC	Alternating current
A/D	Analog digital converter
ADR	Address
AFM	Additional frequency modification
AG	Automation unit
AI	Analog input
AK	Request identifier
AO	Analog output
AOP	Advanced operator panel
ASIC	Application specific integrated circuit
ASP	Analog setpoint
ASVM	Asymmetric space vector modulation
B	
BCC	Block check character
BCD	Binary-coded decimal code
BI	Binector input
BIA	Berufsgenossenschaftliches Institut für Arbeitssicherheit
BICO	Binector/connector
BO	Binector output
C	
C	Commissioning
CB	Communication board
CCW	Counter-clockwise
CDS	Command data set
CI	Connector input
CM	Configuration management
CMD	Command
CO	Cconnector output
CO/BO	Connector output/Binector output
COM	Common (terminal is connected to NO or NC)
CT	Commissioning, ready to run
CU	Control unit

Abbreviation	Meaning
CUT	Commissioning, run, ready to run
CW	Clockwise
D	
D/A	Digital analog converter
DC	Digital analog converter
DDS	Drive data set
DI	Digital input
DIP	DIP switch
DO	Digital output
DP	Distributed I/Os
DS	Drive state
E	
ECD	Equivalent circuit diagram
EEC	European Economic Community
EEPROM	Electrical erasable programmable read-only memory
ELCB	Earth leakage circuit breaker
EMC	Electromagnetic compatibility
EMF	Electromagnetic force
ES	Engineering System
F	
FAQ	Frequently asked question
FB	Function block
FFB	Freely Assignable Function block
FCC	Flux current control
FCL	Fast current limiting
FF	Fixed frequency
FFB	Free function block
FOC	Field orientated control
FREQ	Frequency
FSA	Frame size A
FSB	Frame size B
FSC	Frame size C
FSD	Frame size D
FSE	Frame size E
FSF	Frame size F
G	
GSD	Device data file (Geräte Stamm Datei)
GSG	Getting started guide
GUI ID	Global unique identifier
H	
HIW	Main actual value

Abbreviation	Meaning
HMI	Human machine interface
HO	High Overload (Constant Torque)
HSW	Main setpoint
HTL	High-voltage transistor logic
I	
I/O	In-/output
IBN	Commissioning
IGBT	Insulated gate bipolar transistor
IND	Sub-index
J	
JOG	JOG
K	
KIB	Kinetic buffering
L	
LCD	Liquid crystal display
LED	Light emitting diode
LGE	Length
LO	Light Overload (Variable Torque)
LWL	Fiber Optic conductor
M	
MHB	Motor holding brake
MLP	Multi-Language Pack
MOP	Motor operated potentiometer
N	
NC	Normally closed
NEMA	National Electrical Manufacturers Association
NO	Normally open
O	
OLM	Optical Link Module
OLP	Optical Link Plug
OP	Operator Panel
OPI	Operating Instructions
P	
PID	Proportional, integral, derivative controller
PKE	Parameter ID
PKW	Parameter ID value area (Parameterkennung Wert)
PLC	Programmable logic control
PM	Power module
PM-IF	Power module interface
PNU	Parameter Number
PPO	Parameter process data object

Abbreviation	Meaning
PTC	Positive temperature coefficient
PWE	Parameter value
PWM	Pulse-width modulation
Pxxxx	Write parameter
PZD	Process data area (Prozessdaten)
Q	
QC	Quick commissioning
R	
RAM	Random-access memory
RCCB	Residual current circuit breaker
RCD	Residual current device
RFG	Ramp-function generator
RFI	Radio frequency interference
ROM	Read-only memory
RPM	Revolutions per minute
rxxxx	read-only parameters of analogue signals
S	
SBC	Safe Break Control
SLVC	Sensorless vector control
SLS	Safe-Limited Speed
SOL	Serial option link
SS1	Safe stop 1
STO	Safe torque off
STW	Control word
STX	Start of text
SVM	Space vector modulation
T	
TTL	Transistor-transistor logic
U	
USS	Universal serial interface
V	
V/f	Voltage/frequency
VC	Vector control
VT	Variable torque
W	
WEA	Automatic restart
Z	
ZSW	Status word
ZUSW	Additional setpoint

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