

## Technical Documentation

UHC-126-U-PFN  
UHC-126-U-ETC  
UHC-126-U-PDP

Axis control module with universal positioning, pressure limitation control and Fieldbus interface



*View differs for PDP - version*

**CONTENTS**

1	General information .....	5
1.1	Order number .....	5
1.2	Scope of supply .....	5
1.3	Accessories .....	5
1.4	Symbols used .....	6
1.5	Legal notice .....	6
1.6	Safety instructions .....	7
2	Characteristics .....	8
2.1	Device description .....	9
3	Use and application .....	10
3.1	Installation instructions .....	10
3.2	Typical system structure .....	11
3.3	Method of operation .....	12
3.4	Commissioning .....	13
4	Technical description .....	15
4.1	Input and output signals .....	15
4.2	LED definitions .....	16
4.2.1	First section (with USB) .....	16
4.2.2	Second section (Ethernet Fieldbus) .....	16
4.3	Second section (Profibus – DP) .....	17
4.4	Block diagram .....	17
4.5	Typical wiring .....	18
4.6	Connection examples .....	18
4.7	Technical data .....	19
5	Parameters .....	21
5.1	Parameter overview .....	21
5.2	Basic Parameters .....	24
5.2.1	MODE (Switching between parameter groups) .....	24
5.3	System Parameters .....	24
5.3.1	LG (Changing the language) .....	24
5.3.2	SENS (Monitoring of the module functions) .....	24
5.3.3	EOUT (Output signal if READY = OFF) .....	25
5.3.4	PASSFB (Password fieldbus) .....	25
5.3.5	PBADR (Profibus address) .....	25
5.3.6	HAND (Manual speed) .....	26
5.3.7	VMODE (Method of positioning) .....	26
5.3.8	POSWIN:S (In-position monitoring) .....	27
5.3.9	POSWIN:D (Dynamic position monitoring) .....	27
5.3.10	PRESSWIN (Pressure window) .....	27
5.4	Input and output configuration .....	28
5.4.1	SYS_RANGE (Working stroke) .....	28
5.4.2	SELECT:X (Position sensor type) .....	28
5.4.3	SIGNAL X (Type of input signal) .....	28
5.4.4	N_RANGE:X (Nominal range of the sensor) .....	28
5.4.5	OFFSET:X (Sensor offset) .....	29
5.4.6	Using of the commands SYS_RANGE, N_RANGE:X and OFFSET:X .....	29
5.4.7	SSI:POL (Signal direction) .....	30
5.4.8	SSI:RES (Signal resolution) .....	30
5.4.9	SSI:BITS (Number of data bits) .....	30
5.4.10	SSI:CODE (Signal coding) .....	30
5.4.11	SSI:ERRBIT (Position of the “out of range” bit) .....	30
5.4.12	PS_RANGE (System pressure) .....	31

5.4.13	N_RANGE X1/X2 (Nominal range of the pressure sensors) .....	31
5.4.14	SIGNAL X1/X2 (Type of input signal) .....	31
5.4.15	SIGNAL:U (Type and polarity of the output signal) .....	31
5.5	Positioning controller .....	32
5.5.1	Control structure in SDD mode .....	32
5.5.2	VRAMP (Ramp time for external speed demand) .....	32
5.5.3	A (Acceleration (ramp) time in SDD mode) .....	32
5.5.4	D (Deceleration / braking distance) .....	33
5.5.5	Control structure in NC mode .....	33
5.5.6	ACCEL (Acceleration in NC mode) .....	34
5.5.7	VMAX (Maximum speed in NC mode) .....	34
5.5.8	V0:RES (Scaling of the loop gain) .....	34
5.5.9	V0 (Loop gain setting) .....	34
5.5.10	PT1 (Transfer function of the controller) .....	35
5.5.11	CTRL (Deceleration characteristics) .....	35
5.5.12	MIN (Deadband compensation) .....	36
5.5.13	MAX (Output scaling) .....	36
5.5.14	TRIGGER (Response threshold for the MIN parameter) .....	36
5.5.15	OFFSET (Valve zero point adjustment) .....	37
5.6	Pressure controller .....	38
5.6.1	Operating modes / controller structure .....	38
5.6.2	Operating direction / Inverting .....	39
5.6.3	RA (Command signal ramp time) .....	40
5.6.4	P_OFFSET (pressure offset) .....	40
5.6.5	ARATIO (Cylinder area ratio) .....	40
5.6.6	C1/C2 (PID control parameters) .....	41
5.7	Advanced functions .....	42
5.7.1	FF (Feed forward in NC mode) .....	42
5.7.2	AFC:P (Gain of the acceleration feedback) .....	42
5.7.3	AFC:T1 (Filter time for acceleration feedback) .....	42
5.7.4	AFC_V0:A/B (Loop gain with active acceleration feedback) .....	43
5.7.5	Drift compensation / high accurate positioning .....	43
5.7.6	DC:AV (Activation value) .....	44
5.7.7	DC:DV (Deactivation value) .....	44
5.7.8	DC:I (Integrator time) .....	44
5.7.9	DC:CR (Integrator limitation) .....	44
5.7.10	MR-Controller .....	45
5.7.11	SELPLUS (additionally transmitted bus signals) .....	45
5.7.12	Limits of the pressure Controller .....	46
5.7.13	PROFSTOP (Stop of the profile generator) .....	46
5.8	Special commands .....	47
5.8.1	AINMODE (Input scaling mode) .....	47
5.8.2	AIN (Analogue input scaling) .....	47
5.8.3	ETC_LOOP (Transfer rate) .....	48
5.8.4	MR (Activation of the MR-Controller) .....	48
5.8.5	Remote control square - wave generator .....	49
5.8.6	PCTRLOLD (Compatibility mode) .....	49
5.8.7	DIAG (Query of the last switch-off causes) .....	49
5.8.8	SSI:BITMASK .....	49
5.8.9	PROCESS DATA (Monitoring) .....	50
6	Common device functions .....	51
6.1	Failure monitoring .....	51
6.2	Troubleshooting .....	51

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6.3	Status Information.....	53
7	EtherCAT IO interface .....	54
7.1	ETHERCAT CoE .....	54
7.2	EtherCAT installation .....	54
7.3	EtherCAT access handling .....	54
7.4	EtherCAT device profiles (ESI).....	55
7.5	Standard Objects .....	56
8	ProfiNet IO RT interface .....	57
8.1	PROFINET IO function .....	57
8.2	ProfiNet Installationguide .....	57
8.3	PROFINET address assignment.....	57
8.4	Device data file (GSDML) .....	57
9	Profibus Interface.....	58
9.1	Profibus function .....	58
9.2	Installation .....	58
9.3	Device data file (GSD) .....	58
10	Process data.....	59
10.1	Input from Fieldbus .....	59
10.2	DATA sent to Fieldbus .....	63
11	Parameterization via Fieldbus .....	67
11.1	Procedure .....	67
11.2	Parameterlist.....	68
12	Profinet – Driver Blocks for Simatic – Controllers .....	69
12.1	TIA – Portal.....	69
12.2	STEP7 – classic.....	72
12.3	Common Properties.....	75
13	Notes .....	76

## 1 General information

### 1.1 Order number

Universal axis control module (position control and pressure control) with analog output  $\pm 10$  V differential output or 4 ... 20 mA output, SSI or analog sensor interface

<b>UHC-126-U-PFN</b>	- ProfiNet interface
<b>UHC-126-U-ETC</b>	- EtherCAT interface
<b>UHC-126-U-PDP</b>	- Profibus – DP interface

#### Alternative versions

<b>PPC-125-U-PDP</b>	- Profibus interface, reduced functionality, compatible to the older modules (POS-123 and PPC-125)
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### 1.2 Scope of supply

The scope of supply includes the module plus the terminal blocks which are part of the housing. Interface cables and further parts which may be required should be ordered separately. This documentation can be downloaded as a PDF file from [www.w-e-st.de](http://www.w-e-st.de).

### 1.3 Accessories

<b>WPC-300</b>	- Start-Up-Tool (downloadable from our homepage – products/software)
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Any standard cable with USB-A and USB-B connector can be used as the programming cable.

## 1.4 Symbols used



General information



Safety-related information

## 1.5 Legal notice

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Datum: 20.03.2023

The data and characteristics described herein serve only to describe the product. The user is required to evaluate this data and to check suitability for the particular application. General suitability cannot be inferred from this document. We reserve the right to make technical modifications due to further development of the product described in this manual. The technical information and dimensions are non-binding. No claims may be made based on them.

This document is protected by copyright.

## 1.6 Safety instructions

Please read this document and the safety instructions carefully. This document will help to define the product area of application and to put it into operation. Additional documents (WPC-300 for the start-up software) and knowledge of the application should be taken into account or be available.

General regulations and laws (depending on the country: e. g. accident prevention and environmental protection) must be complied with.



These modules are designed for hydraulic applications in open or closed-loop control circuits. Uncontrolled movements can be caused by device defects (in the hydraulic module or the components), application errors and electrical faults. Work on the drive or the electronics must only be carried out whilst the equipment is switched off and not under pressure.



This handbook describes the functions and the electrical connections for this electronic assembly. All technical documents which pertain to the system must be complied with when commissioning.



This device may only be connected and put into operation by trained specialist staff. The instruction manual must be read with care. The installation instructions and the commissioning instructions must be followed. Guarantee and liability claims are invalid if the instructions are not complied with and/or in case of incorrect installation or inappropriate use.



### **CAUTION!**

All electronic modules are manufactured to a high quality. Malfunctions due to the failure of components cannot, however, be excluded. Despite extensive testing the same also applies for the software. If these devices are deployed in safety-relevant applications, suitable external measures must be taken to guarantee the necessary safety. The same applies for faults which affect safety. No liability can be assumed for possible damage.



### **Further instructions**

- The module may only be operated in compliance with the national EMC regulations. It is the user's responsibility to adhere to these regulations.
- The device is only intended for use in the commercial sector.
- When not in use the module must be protected from the effects of the weather, contamination and mechanical damage.
- The module may not be used in an explosive environment.
- To ensure adequate cooling the ventilation slots must not be covered.
- The device must be disposed of in accordance with national statutory provisions.

## 2 Characteristics

This electronic module was developed for controlling the position and/or pressure of a hydraulic axis via the integrated fieldbus interface.

The hydraulic axis can be driven as positioning control with digital stroke measurement (SSI interface) or by analog sensors.

Additionally, an integrated pressure limitation control function for one or two pressure sensors (differential pressure) is implemented. Command signals and actual values are transmitted by a fieldbus communication interface. Feedback are status information and actual values.

Proportional valves with integrated electronics (typically control valves) can be driven by the analogue output.

Internal failure and the system statuses are monitored. The ready output is available as a fieldbus information and parallel as a hardware output.

The parameterization is performed via a USB interface in combination with our PC program WPC-300. Alternatively, defined parameters can be modified via the fieldbus interface.

Typical applications: general positioning drives, fast transport drives, handling systems, speed-controlled axes and presses with positioning and pressure control.

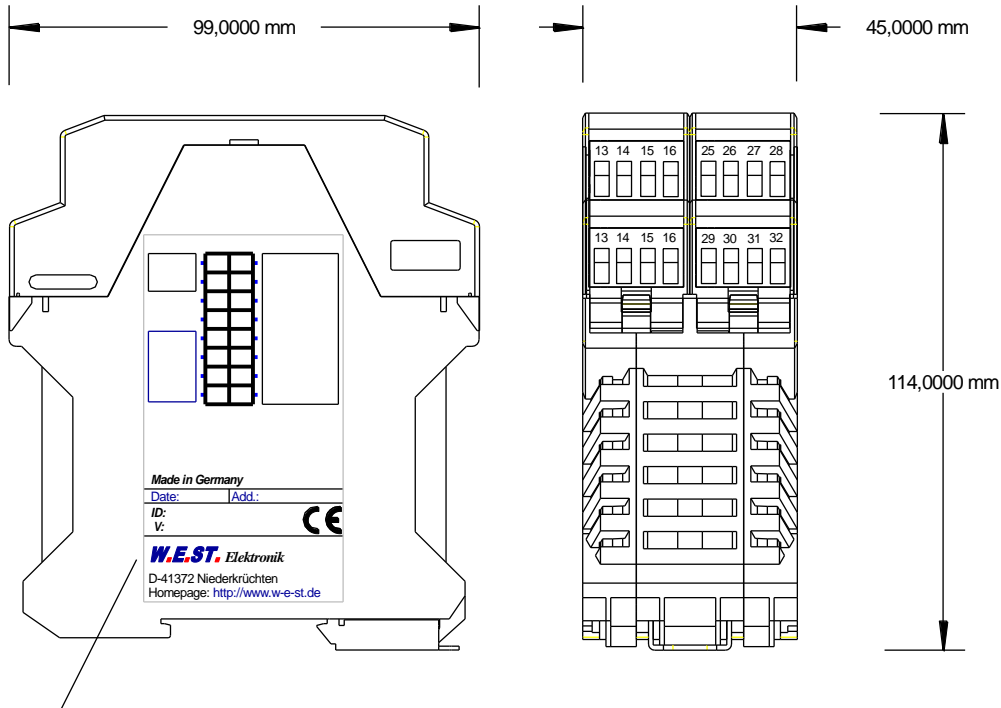
## Features

- **Fieldbus for command values, sensor values, control word and status word**
- **SSI- or analog feedback sensors (0... 10 V or 4... 20 mA)**
- **Resolution up to 1 µm (SSI - interface)**
- **Speed resolution 0,005 mm/s**
- **Positioning modes are: stroke-dependent deceleration or NC mode with internal profile generator**
- **Profiling of the movement with two positions and two speeds**
- **Alternatively continuous command signal transition**
- **Differential pressure limitation control or direct pressure control**
- **Expanded closed loop control functions:**
  - **P<sub>T1</sub> filter**
  - **Drift compensation for optimal zero point adjustment**
  - **Accurate positioning by compensation of force depended positioning deviations**
  - **Feed forward to reduce the following error**
  - **Acceleration feedback by measuring the differential pressure (used to improve the dynamic behavior in case of low dynamics drives)**
- **Usable with overlapped proportional valves and with zero lapped control valves**
- **Fault diagnosis and extended function checking**
- **Simplified parameterization with WPC-300 software**

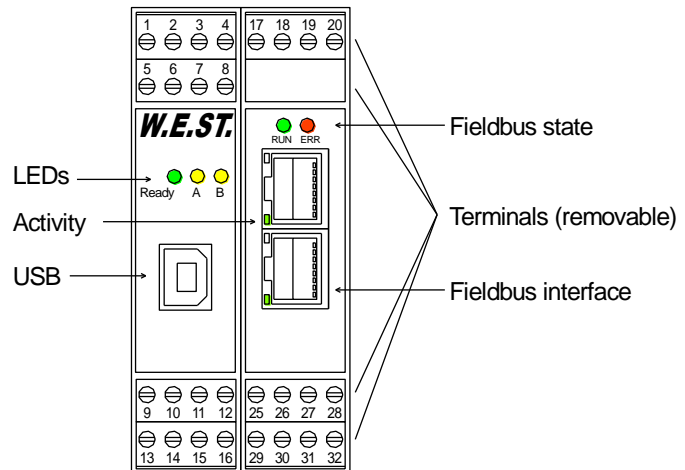


## 2.1 Device description

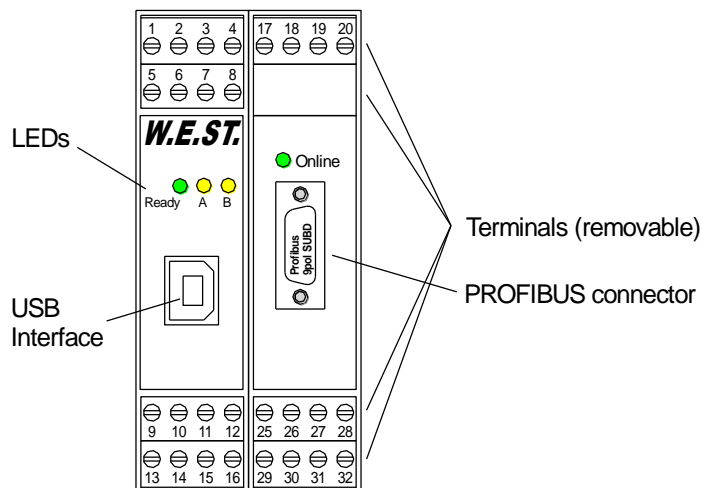
Ethernet – based fieldbus:



Type plate and terminal pin assignment



Front view Profibus – DP module:



## 3 Use and application

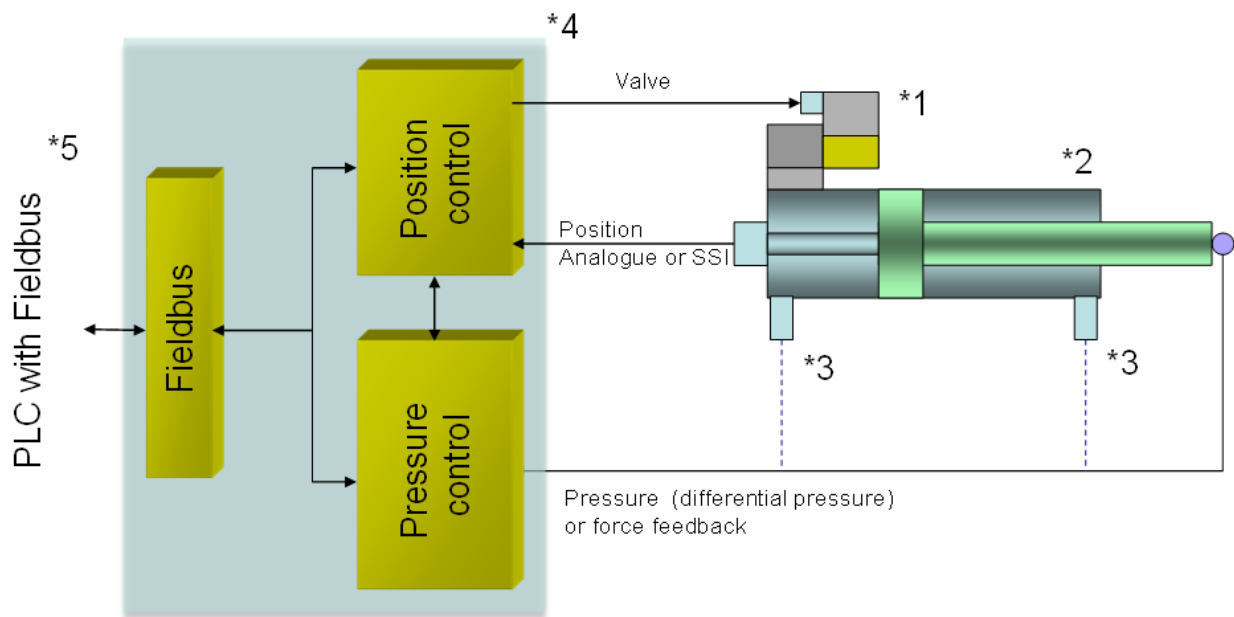
### 3.1 Installation instructions

- This module is designed for installation in a shielded EMC housing (control cabinet). All cables which lead outside must be screened; complete screening is required. It is also necessary to avoid strong electro-magnetic interference sources being installed nearby when using our open and closed loop control modules.
- **Typical installation location:** 24 V control signal area (close to PLC)  
The devices must be arranged in the control cabinet so that the power section and the signal section are separate from each other.  
Experience shows that the installation place close to the PLC (24 V area) is most suitable. All digital and analogue inputs and outputs are fitted with filters and surge absorbers in the device.
- The module should be installed and wired in accordance with the documentation bearing in mind EMC principles. If other consumers are operated with the same power supply, a star-shaped ground wiring scheme is recommended. The following points must be observed when wiring:
  - The signal cables must be laid separately from power cables.
  - Analogue signal cables **must be screened**.
  - All other cables must be screened if there are powerful interference sources (frequency converters, power contactors) and cable lengths > 3 m. Inexpensive SMD ferrites can be used with high-frequency radiation.
  - The screening should be connected to PE (PE terminal) as close to the module as possible. The local requirements for screening must be taken into account in all cases. The screening should be connected to at both ends. Equipotential bonding must be provided where there are differences between the connected electrical components.
  - If having longer lengths of cable (> 10 m), the diameters and screening measures should be checked by specialists (e. g. for possible interference, noise sources and voltage drop). Special care is required if using cables of over 40 m in length, and the manufacturer should be consulted if necessary.
- A low-resistance connection between PE and the mounting rail should be provided. Transient interference is transmitted from the module directly to the mounting rail and from there to the local earth.
- Power should be supplied by a regulated power supply unit (typically a PELV system complying with IEC364-4-4, secure low voltage). The low internal resistance of regulated power supplies gives better interference voltage dissipation, which improves the signal quality of high-resolution sensors in particular. Switched inductances (relays and valve coils) which are connected to the same power supply must always be provided with appropriate overvoltage protection directly at the coil.

### 3.2 Typical system structure

This minimal system consists of the following components:

- (\*1) Proportional valve with integrated electronics
- (\*2) Drive (e.g. hydraulic cylinder)
- (\*3) Sensors for position (SSI or analog) and pressure
- (\*4) UHC-126 control module
- (\*5) Interface to PLC



### 3.3 Method of operation

#### Positioning control plus pressure control

##### General information

This module is a combined system of position control and pressure control. The standard communication via fieldbus simplifies the wiring. The UHC-126-U can be used as a universal axis controller for hydraulic drives. Because of a second position and a second velocity, it is optionally possible to drive to target position with the corresponding speed (rapid traverse and creeping speed respectively creeping speed and rapid traverse)

**Positioning:** Similar to our standard positioning modules, the axis can be used as point to point controller (stroke depended deceleration) as well as in NC mode. With only a few parameters the controller can be optimized, the movement profile is preset via Fieldbus (position and velocity).

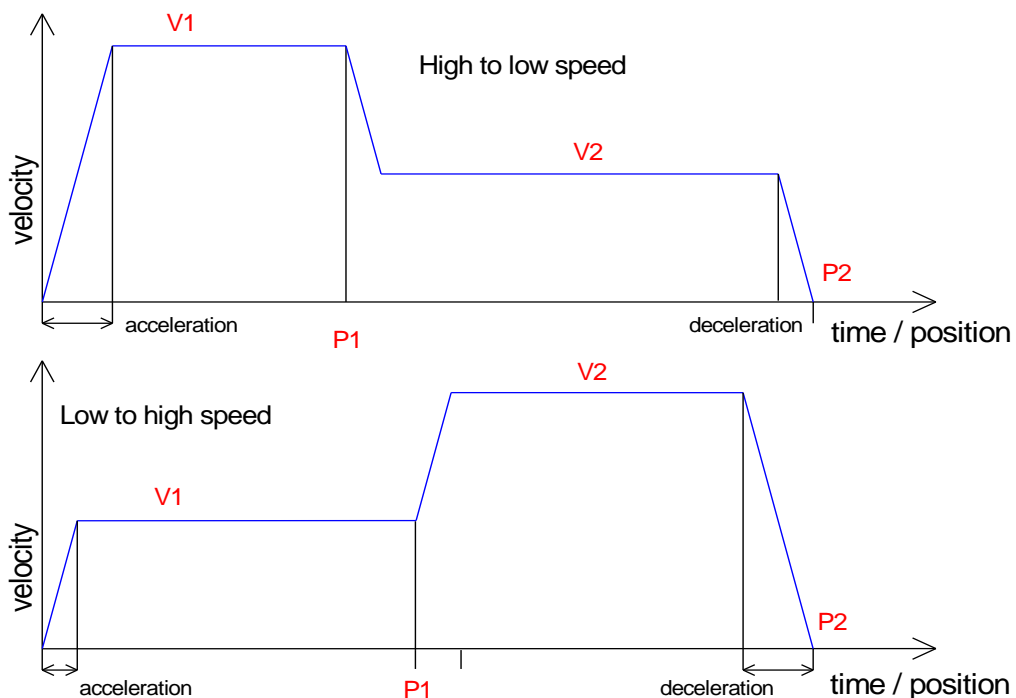
##### Optional additional function: motion profile with second speed

Because of the input of a second position and speed, the axis can be driven to this position with the second velocity. This mode is only activated when the velocity command value V2 is not equal to zero.

The following features have to be noticed:

- The position command value (P2) is the end position that is approached with the velocity (V2).
- The position setpoint (P1) is the switching position, which is approached with the speed (V1) and then switched over to the speed (V2).
- The speed is switched via the speed ramp (in NC mode via the acceleration).
- If the position setpoint (P2) is between the feedback value and the position setpoint (P1) (P1 and P2 are reversed), the position (P2) is started at speed (V1).

The following illustrations show two possible speed profiles, which result depending on the choice of speed V2 in relation to V1:



Influences on positioning accuracy:

The positioning accuracy is determined by the hydraulic and mechanical conditions. The right choice of valve is therefore a decisive factor. In addition, two mutually contradictory requirements (short position time and high accuracy) must be taken into account when designing the system.

The electronic limitations lie mainly in the resolution of the analogue signals, although a resolution of  $< 0,01\%$  only needs to be considered for our modules with long positions. In addition, the linearity of the individual signal points (PLC, sensor and control module) must be taken into account.

It is generally recommended to calculate the static and dynamic behavior of the hydraulic axis. For supporting this, following technical basic data are required:

- minimum natural frequency of the cylinder,
- maximum theoretical speed for extending and retracting,
- valve characteristics (natural frequency, overlapped or zero lapped, hysteresis and the flow gain (flow and pressure drop),
- system pressure, maximum pump flow,
- a description of the general system requirements.

**Pressure closed loop control**

The pressure control is designed as a pressure limitation control, as required for typical press applications, for example. If the feedback pressure is higher than the command pressure, the pressure controller takes over the control of the axis. This kind of control is typically used in metal forming applications. The behavior of the pressure closed loop control is adjustable by an optimized PID compensator. Two different setups can be selected over the fieldbus. Optionally, the pressure control function can be used without the position controller.

### 3.4 Commissioning

Step	Task
Installation	Install the device in accordance with the circuit diagram. Ensure it is wired correctly and the signals are well shielded. The device must be installed in a protective housing (control cabinet or similar). The wiring to the fieldbus interface is done by appropriate cables.
Switching on for the first time	Ensure that no unwanted movement is possible in the drive (e. g. switch off the hydraulics). Connect an ammeter and check the current consumed by the device. If it is higher than specified, there is an error in the wiring. Switch the device off immediately and check the wiring.
Setting up communication	Once the power input is correct, the PC (notebook) should be connected to the serial interface. Please see the WPC-300 program documentation for how to set up the communication. Further commissioning and diagnosis are supported by the operating software.
Pre-parameterization	Now set up the following parameters (with reference to the system design and circuit diagrams): <ul style="list-style-type: none"><li>- The SYSTEM data, INPUT sensor settings, control parameter and OUTPUT parameters. Pre-parameterization is necessary to minimize the risk of uncontrolled movements.</li><li>- Reduce the speed limitation to a value which is uncritical for the application.</li></ul>
Fieldbus Communication	By selecting the device driver, the IP address of the device and the configuration file, the communication can now be operated to the device. At the corresponding positions setpoints and control bits can now be sent and actual values and status bits are read back. Read the description of the interface in a separate chapter.
Remote Control	If there is no bus communication available at the beginning of the commissioning, the axis can be operated solely via the WPC program. In the monitor window, the

Step	Task
	<p>"Remote Control" mode can be activated. Then it is possible to enter a speed value and move the axis using the manual signals or to enter a position set-point and to activate the position controller by setting the "Start" – signal.</p> <p><b>CAUTION!</b> WPC will take over complete control in this state. The hardware – enable signal at PIN 8 and the bus interface are inoperable in this case.</p>
Control signal	<p>Check the control signal with a current- or voltmeter.</p> <p><b>Voltages:</b> The differential output (PIN 15 minus PIN16) lies in the range of <math>\pm 10</math> V.</p> <p><b>Current:</b> PIN 15 is used for 4... 20 mA (12 mA for 0 % of the control signal). An alternative output signal (in case of not READY) can be defined by the EOUT command.</p>
Switching on the hydraulics	<p>The hydraulics can now be switched on. Since the module is not yet generating a signal, the drive should be at a standstill or drift slightly (leave its position at a slow speed).</p>
Activating ENABLE	<p><b>CAUTION!</b> The drive can now leave its position and move to an end position at full speed. Take safety measures to prevent personal injury and damage.</p> <p>Both hardware ENABLE and software ENABLE (over the fieldbus) have to be activated. Outputs and failure processing are active. The drive stays (closed loop controlled) in the current position. If the drive moves to an end position, the polarity is probably wrong.</p>
Speed demand	<p>The speed is sent by the fieldbus. At zero speed, no movement is possible.</p>
Manual (HAND) operation	<p>If START is disabled, the axis can be moved manually with HAND+ or HAND-. After disabling the HAND signal, the axis stops closed loop controlled at the current position. The axis can also be driven without a sensor signal.</p>
Activating START	<p>With the start signal the demand value input is accepted and the axis moves to the target position.</p> <p>If START is disabled, the axis stops in the preset deceleration distance D:S.</p>
Optimize controller	<p>Now optimize the control parameters according to your application and your requirements.</p>

## 4 Technical description

### 4.1 Input and output signals

Connection	Supply
PIN 3	Power supply (see technical data)
PIN 4	0 V (GND) connection.
PIN 19	Power supply Fieldbus and SSI-interface (see technical data)
PIN 20	0 V (GND)
Connection	Analog signals
PIN 6	Actual pressure (X2), range 0... 10 V or 4... 20 mA, scalable (SIGNAL:X2)
PIN 13	Actual pressure (X1), range 0... 10 V or 4... 20 mA, scalable (SIGNAL:X1)
PIN 14	Actual position (X), range 0... 10 V or 4... 20 mA, scalable (SIGNAL:X)
PIN 11 / PIN 12	0 v (GND) connection for the analogue signals
PIN 15 / 16 PIN 15 / 12	Control output, range: +/- 10 V (differential output) or PIN 15: 4... 12... 20 mA Type of signal and polarity can be selected by the parameter SIGNAL:U.
Connection	SSI interface
PIN 25	CLK+ output
PIN 26	CLK- output
PIN 27	DATA+ input
PIN 28	DATA- input
PIN 31	Power supply output 24 V
PIN 32	Power supply output 0 V
Connection	Digital inputs and outputs
PIN 8	<b>Enable input:</b> Hardware ENABLE (have to be activated together with fieldbus ENABLE)
Connection	Digital inputs and outputs
PIN 1	<b>READY output:</b> <b>ON:</b> The module is enabled; there are no discernible errors. <b>OFF:</b> Enable (PIN 8 or Fieldbus bit) is disabled or an error has been detected (depending on command SENS)

## 4.2 LED definitions

### 4.2.1 First section (with USB)

LEDs	Description of the LED function
GREEN	Identical to the READY output except for the error indication. <b>OFF:</b> No power supply or ENABLE is not activated <b>ON:</b> System is ready for operation <b>Flashing:</b> Error discovered Only active when SENS = ON
YELLOW A	Identical to the STATUS output. <b>OFF:</b> The axis is outside the INPOS window. <b>ON:</b> The axis is within the INPOS window.
GREEN + YELLOW A+B	1. <b>Chasing light (over all LEDs):</b> The bootloader is active. No normal functions are possible. 2. <b>All LEDs flash shortly every 6 s:</b> An internal data error was detected and corrected automatically! The module still works regularly. To acknowledge the error the module has to be cycle powered.
YELLOW A + YELLOW B	<b>Both yellow LEDs flash alternately every 1 s:</b> The nonvolatile stored parameters are inconsistent! To acknowledge the error, the data have to be saved with the SAVE command or the corresponding button in the WPC.

### 4.2.2 Second section (Ethernet Fieldbus)

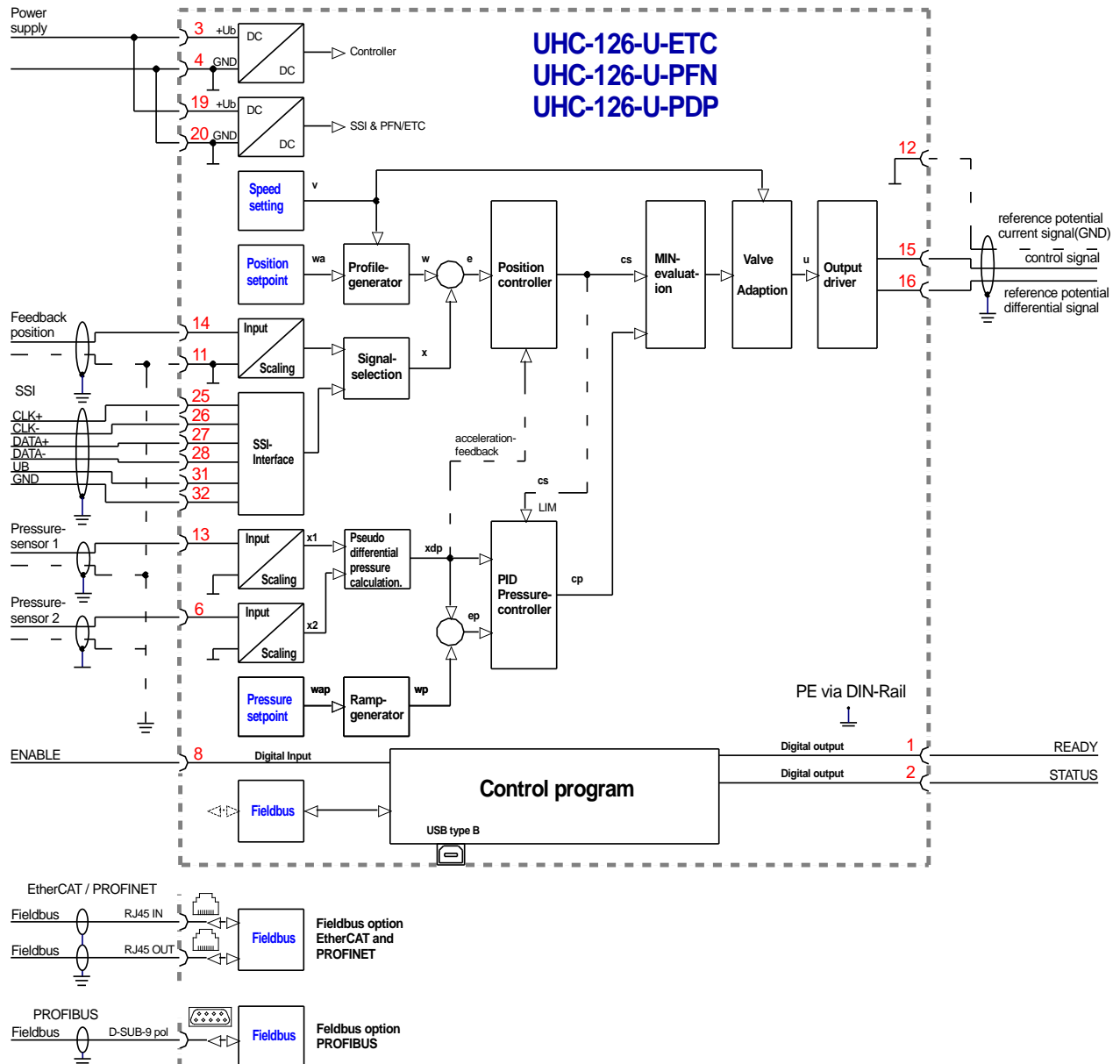
LEDs	Description of the LED function
GREEN at the ports	Green LEDs shows network traffic at the relating port. <b>OFF:</b> No connection available <b>ON:</b> Active network connected <b>Flashing:</b> Existing data traffic
GREEN	The green RUN LED indicates the status of the central communication processor. <b>OFF:</b> Bus not started / Initializing <b>Flashing:</b> Status EtherCAT: Safe Operational Status ProfiNet: wait for data <b>Flickering:</b> Status EtherCAT: - Status ProfiNet: Failure <b>ON:</b> Connected and active
RED	The red ERR LED indicates a failure state. <b>OFF:</b> No Error. <b>Flashing:</b> EtherCAT: No communication (PLC-Failure, lost frames) ProfiNet: Node flash test <b>ON:</b> ProfiNet: Failure in the data communication



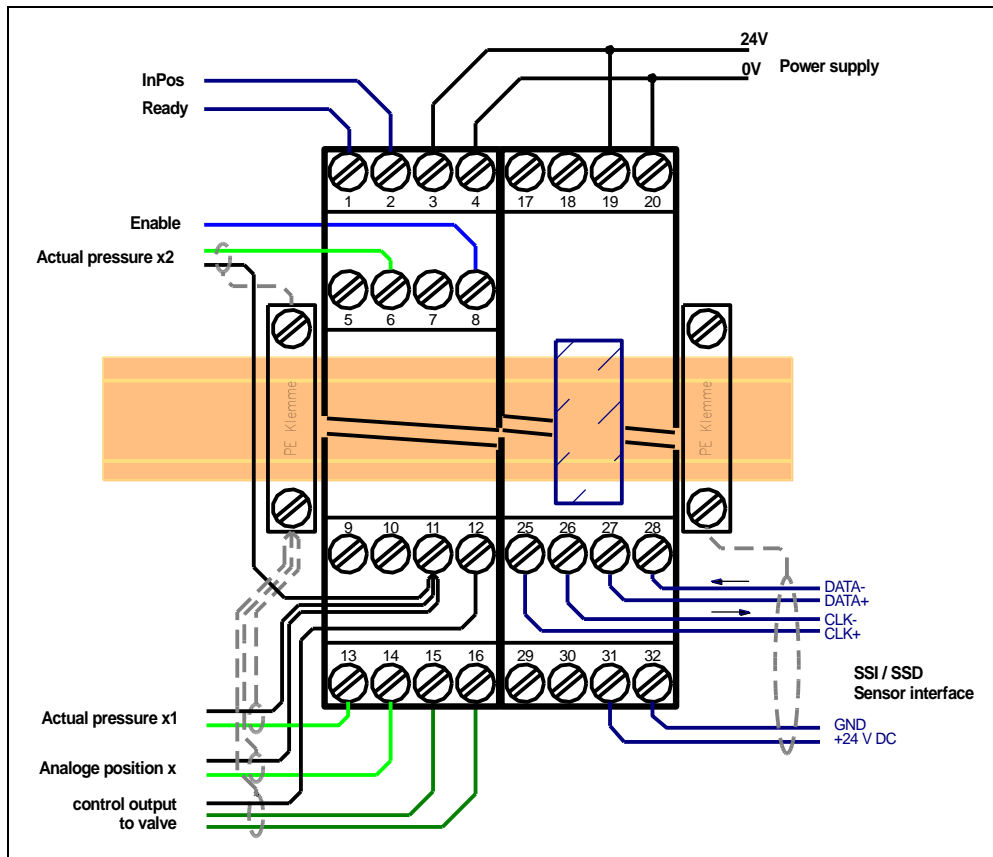
### 4.3 Second section (Profibus – DP)

The diagnostics LED on the 2nd section indicates online operation on a Profibus system.

### 4.4 Block diagram

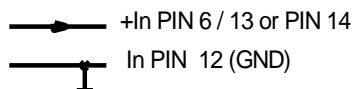


## 4.5 Typical wiring

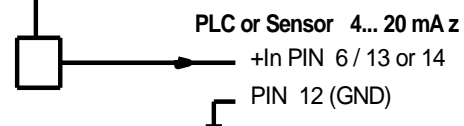


## 4.6 Connection examples

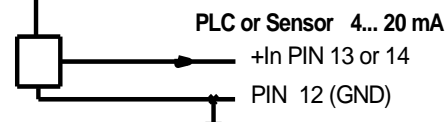
SPS / PLC 0... 10 V Signal



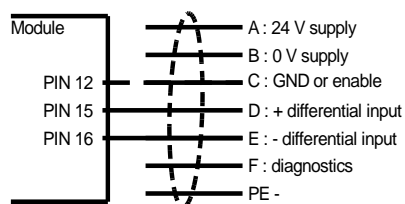
z. B. 24 V



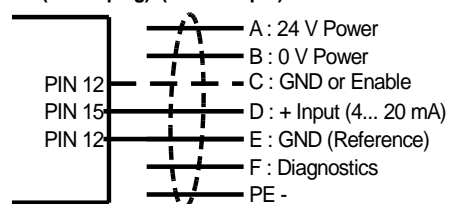
z. B. 24 V



Valve (6 + PE plug) (voltages input)



Valve (6 + PE plug) (current input)



## 4.7 Technical data

Supply voltage (U <sub>b</sub> )	[VDC]	24 (±10 %)
Power consumption	[W]	max. 5.5 without sensor supply
External protection	[A]	1 medium time lag
Digital inputs		
OFF	[V]	< 2
ON	[V]	> 10
Input resistance	[kOhm]	25
Digital outputs		
OFF	[V]	< 2
ON	[V]	max. U <sub>b</sub>
Maximum output current	[mA]	50
Analogue inputs		
Voltage	[V]	Unipolar 0... 10
Input resistance	[kOhm]	min. 25
Signal resolution	[%]	0.003 incl. Oversampling
Current	[mA]	4... 20
Load	[Ohm]	240 Ohm
Signal resolution	[%]	0.006 incl. Oversampling
Analogue outputs		
Voltage	[V]	0... 10, +/- 10 differential
Maximum load	[mA]	10
Current	[mA]	4... 20
Maximum load	[Ohm]	390
Signal resolution	[%]	0.007
SSI-interface		
Data rate	[kbit/s]	RS-422 specification 120
Controller sample time	[ms]	1
Serial Interface	-	USB - virtuel COM Port
Data rate	[kBaud]	9.6... 115.2
Profinet IO		
Data rate	[Mbit/s]	100
Conformance class	-	CC-B
Profibus DP interface		
Data rate	[kbit/s]	9.6, 19.2, 93.75, 187.5, 500, 1500, 3000, 6000, 12000
ID-number		1810h
Housing		Snap-On Modul nach EN 50022
Material	-	Polyamid PA 6.6
Flammability class	-	V0 (UL94)
Weight	[kg]	0.285

Protection class		IP20
Temperature range	[°C]	-20... 60
Storage temperature	[°C]	-20... 70
Humidity	[%]	< 95 (non-condensing)
Connections	-	
Communication		USB type B
Plug connectors		7 x 4-pole terminal blocks
PE		via the DIN mounting rail
Fieldbus		RJ45 IN OUT or
		D-Sub 9 pol. (Profibus)
EMC	-	EN61000-6-4: 2007 +A1:2011
		EN61000-6-2: 2005

## 5 Parameters

### 5.1 Parameter overview

Group	Command	Default	Unit	Description
<b>Basic parameters</b>				
	MODE	---	-	Parameter view
<b>System (MODE = SYSTEM)</b>				
	LG	EN	-	Changing language help texts
	SENS	ON	-	Malfunction monitor
	EOUT	0	0.01 %	Output signal if not ready
	PASSFB	0	-	Password for fieldbus parameterization
	PBADR	126	-	Profibus device address
	HAND:A	3330	0.01 %	Output signal in manual mode
	HAND:B	-3330	0.01 %	
	VMODE	SDD	-	Method of positioning
	POSWIN:S	200	µm	Ranges of the in-position monitoring
	POSWIN:D	200	µm	
	PRESSWIN	2000	µm	Control window for pressure monitoring
<b>Input / Output Signals (MODE = IO_CONF)</b>				
<i>Analog position sensor scaling, system range</i>				
	SYS_RANGE	100	mm	Axis working stroke
	SELECT:X	SSI	-	Sensor selection
	SIGNAL:X	U0-10	-	Type of the sensor signal (if the analog input is used)
	N_RANGE:X	100	mm	Nominal range
	OFFSET:X	0	µm	Offset value
<i>SSI position sensor</i>				
	SSI:POL	+	-	Polarity
	SSI:RES	100	10 nm	Resolution of the sensor
	SSI:BITS	24	-	Number of data bits
	SSI:CODE	GRAY	-	Code
	SSI:ERRBIT	0	-	Position of the error bit
<i>Pressure sensor scaling, system pressure range</i>				
	PS_RANGE	100	bar	System pressure
	SIGNAL:X1	U0-10	-	Type of the sensor
	N_RANGE:X1	100	bar	Nominal pressure of the sensor
	SIGNAL:X2	OFF	-	Type of the sensor
	N_RANGE:X2	100	bar	Nominal pressure of the sensor
<i>Output</i>				
	SIGNAL:U	U+-10	-	Type and polarity of the analog output

## Position controller (MODE = POSITION)

	VRAMP	200	ms	Ramp time for the external command speed
NC mode				
	ACCEL	250	mm/s <sup>2</sup>	Acceleration in NC mode
	VMAX	50	mm/s	Maximum speed in NC mode
	V0:RES	1		Can be used to change the resolution
	V0:A	8	1/s	Closed loop gain without acceleration feedback
	V0:B	8	1/s	
SDD mode				
	A:A	100	ms	Acceleration (ramp times) in SDD mode
	A:B	100	ms	
	D:A	25	mm	Deceleration stroke in SDD mode
	D:B	25	mm	
Further settings, output adaption				
	D:S	10	mm	STOP - Overtravel
	PT1	0	ms	PT1 time constant
	CTRL	SQRT1	-	Control characteristics
	MIN:A	0	0.01 %	Deadband compensation or flow characteristic linearization
	MIN:B	0	0.01 %	
	MAX:A	10000	0.01 %	Output scaling
	MAX:B	10000	0.01 %	
	TRIGGER	200	0.01 %	Trigger point of MIN parameter
	OFFSET	0	0.01 %	Output offset value

## Pressure control (MODE = PRESSURE)

<b>Ramps, Offset</b>			
<b>RA:UP</b>	100	ms	Ramp times for the pressure setpoint
<b>RA:DOWN</b>	100	ms	
<b>P_OFFSET</b>	0	mbar	Pressure offset, is added to the actual value
<b>ARATIO</b>	1000	-	Area ratio of the cylinder
<b>Parameter Set 1</b>			
<b>C1:P</b>	50	0,01	P Gain
<b>C1:I</b>	4000	0,1 ms	I Gain, reset time
<b>C1:D</b>	0	0,1 ms	D Gain, derivative time
<b>C1:D_T1</b>	10	0,1 ms	D filter
<b>C1:I_ACT</b>	5000	0,01 %	Integrator activation threshold
<b>Parameter Set 2</b>			
<b>C2:P</b>	50	0,01	P Gain
<b>C2:I</b>	4000	0,1 ms	I Gain, reset time
<b>C2:D</b>	0	0,1 ms	D Gain, derivative time
<b>C2:D_T1</b>	10	0,1 ms	D filter
<b>C2:I_ACT</b>	5000	0,01 %	Integrator activation threshold

**Special function (MODE = EXTRA)**

*Feedforward*

<b>FF:A</b>	0	-	Feed forward control gain factors
<b>FF:B</b>	0	-	

*Acceleration feedback*

<b>AFC:P</b>	0	0,01	Acceleration feedback (Gain and filter time)
<b>AFC:T1</b>	10	ms	
<b>AFC_VO:A</b>	8	1/s	Closed loop gain with acceleration feedback
<b>AFC_VO:B</b>	8	1/s	

*MR controller*

<b>MR:T1</b>	20	ms	filter constants of the MR – controller
<b>MR:T2</b>	20	ms	

*Drift compensation, fine positioning*

<b>DC:AV</b>	0	0,01 %	point of activation
<b>DC:DV</b>	0	0,01 %	point of deactivation
<b>DC:I</b>	2000	ms	reset time of the integrator
<b>DC:CR</b>	500	0,01 %	output limit

*Additionally transmitted bus signals*

<b>SELPLUS:1</b>	-	-	Selection of additional signal 1
<b>SELPLUS:2</b>	-	-	Selection of additional signal 2

*Integrator Limitation (Pressure Controller)*

<b>CP:I_ULIM</b>	10000	0,01 %	Upper integrator limit
<b>CP:I_LLIM</b>	-10000	0,01 %	Lower integrator limit

*Behavior of the profile generator when the pressure controller is active*

<b>PROFSTOP</b>	OFF	-	Stop the profile generator
-----------------	-----	---	----------------------------

**Special commands**

<b>AINMODE</b>	EASY	-	Input scaling mode
<b>AIN_1:X</b>	A: 1000	-	Free scaling of the analogue inputs (MATH).
<b>AIN_2:X</b>	B: 1000	-	
	C: 0	0,01 %	Please contact W.E.St. before using this option.
	X: V	-	
<b>ETC_LOOP</b>	NORMAL	-	Cycle time of data transfer. Only available on EtherCAT devices!
<b>MR</b>	OFF	-	Activation of the MR controller via a command.
<b>ACA:CYCLE</b>	0	ms	Square-wave generator: cycle time
<b>ACA:POS1</b>	25	mm	Lower switching position
<b>ACA:POS2</b>	75	mm	Upper switching position
<b>PCTRLD</b>	OFF	-	Compatibility mode pressure controller tracking
<b>DIAG</b>	-	-	Query of the last switch-off causes
<b>SSI:BITMASK</b>	0	-	Masking out bits from the SSI telegram

## 5.2 Basic Parameters

### 5.2.1 MODE (Switching between parameter groups)

Command	Parameters	Unit	Group
<b>MODE</b> <b>x</b>	x= SYSTEM IO_CONF POSITION  PRESSURE EXTRA ALL	-	<b>BASICS</b>

This command is changing the different parameter groups.

---      No group is displayed (default)  
**SYSTEM**      System data  
**IO\_CONF**      Definition of the in- and output signals  
**POSITION**      Parameters of the position controller  
**PRESSURE**      Parameters of the pressure controller  
**EXTRA**      Special functions  
**ALL**      All parameters are listed

## 5.3 System Parameters

### 5.3.1 LG (Changing the language)

Command	Parameters	Unit	Group
<b>LG</b> <b>x</b>	x= DE EN	-	<b>SYSTEM</b>

Either German or English can be selected for the help texts.

### 5.3.2 SENS (Monitoring of the module functions)

Command	Parameters	Unit	Group
<b>SENS</b> <b>x</b>	x= ON OFF AUTO	-	<b>SYSTEM</b>

This command is used to activate/deactivate the monitoring functions (4... 20 mA sensors, output current, signal range and internal failures) of the module.

ON:      All monitoring functions are active. Detected failures can be reset by deactivating the ENABLE input.

OFF:      No monitoring function is active.

AUTO:      AUTO RESET mode. All monitoring functions are active. If the failure doesn't exist anymore, the module automatically resumes to work.



**Normally the monitoring functions are always active because otherwise no errors are detectable via the READY output. Deactivating is possible mainly for troubleshooting.**



### 5.3.3 EOUT (Output signal if READY = OFF)

Command	Parameters	Unit	Group
EOUT      x	x= -10000... 10000	0,01 %	SYSTEM

Output value in case of a detected error or a deactivated ENABLE input. This function can be used if the drive has to be moved to one of the two end positions (with defined speed).

|EOUT| = 0 The output is switched off in the event of an error. This is normal behavior.



**CAUTION!** If the output signal is 4... 20 mA, the output is switched off when |EOUT| = 0. If a null value = 12 mA is to be output in the event of an error, EOUT must be set to 1<sup>1</sup>.

The output value defined here is stored permanently (independent from the parameter set). The effects should be analyzed by the user for each application from the point of view of safety.

Do not use the manual mode in conjunction with the EOUT command. After deactivation of the HAND input, the output is set to the EOUT value.

### 5.3.4 PASSFB (Password fieldbus)

Command	Parameters	Unit	Group
PASSFB      x	x= 0... 10000000	–	SYSTEM

The value entered here serves as password for the parameterizing via fieldbus. For enabling parametrization it has to be send via fieldbus to the relating address. For a value of "0" the password protection is deactivated.

### 5.3.5 PBADR (Profibus address)

Command	Parameters	Unit	Group
PBADR      x	x= 1... 126	–	SYSTEM

This command is used to change the address of the module.



The PBADR must be 126 if an external address change (over the Profibus) should be supported.

<sup>1</sup> This is necessary if using valves without error detection for signals lower than 4 mA. If the valve has an internal error detection, it moves into a defined position after switching off the output.

### 5.3.6 HAND (Manual speed)

Command	Parameters	Unit	Group
HAND: i      x	i= A B x= -10000... 10000	0,01%	SYSTEM

The manual speeds are set with these parameters. The drive moves in a controlled manner in the defined direction when the manual signal is active. The direction is defined by the sign of the parameters. After the manual signal has been disabled, the drive remains under control in the current position.

In case of a fault (position sensor fault), the drive can still be moved with this manual function. The output will be switched off when the hand signals are turned off.

The manual speed is also limited by the external speed demand imposed through the fieldbus (MIN evaluation).



**Caution!** Do not use the manual mode in conjunction with the EOUT command in case of errors. After deactivation of the HAND input, the output is reset to the EOUT value.

### 5.3.7 VMODE (Method of positioning)

Command	Parameters	Unit	Group
VMODE      x	x= SDD NC		SYSTEM

The fundamental control structure can be changed with this parameter.

- SDD:** **Stroke-Dependent Deceleration.** In this mode, stroke-dependent deceleration is activated. This mode is the default mode and is suitable for most applications. With stroke-dependent deceleration the drive comes to a controlled stop at the target position. From the deceleration setpoint the drive then switches to closed loop control mode and moves accurately to the desired position. This control structure is very robust and reacts insensitively to external influences such as fluctuating pressures. One disadvantage is that the speed varies with the fluctuating pressure as the system runs under open-loop control.
- NC:** **Numerically Controlled.** In this mode a position profile is generated internally. The system always works under control and uses the following error to follow the position profile. The magnitude of the following error is determined by the dynamics and the closed loop gain. The advantage is that the speed is constant (regardless of external influences) due to the profile demand. Because of continuous control, it is necessary not to run at 100 % speed, as otherwise the errors cannot be corrected. 70... 80 % of the maximum speed is typical although especially the system behavior and the load pressure should be taken into account when specifying the speed.

### 5.3.8 POSWIN:S (In-position monitoring)

### 5.3.9 POSWIN:D (Dynamic position monitoring)

Command		Parameters	Unit	Group
POSWIN:S	x	x= 2... 200000	µm	SYSTEM
POSWIN:D	x	x= 2... 200000	µm	

This parameter is entered in µm.

The POSWIN command defines a range for which the INPOS message is generated. This function monitors the failure between the command and actual position. The positioning process is not influenced by this function.

START must be activated to generate the INPOS messages.

**POSWIN:S** Standard InPos signal

**POSWIN:D** Dynamic InPos signal to monitor the following error in case of NC mode<sup>2</sup>

### 5.3.10 PRESSWIN (Pressure window)

Command		Parameters	Unit	Group
PRESSWIN	x	x= 100... 50000	mbar	SYSTEM

This parameter is entered in mbar.

The PRESSWIN command defines a range for which the signal is generated. This function monitors the deviation between command value and actual value.

<sup>2</sup> The INPOS:D should always be higher than the INPOS:S. Alternatively two different INPOS windows are definable.

## 5.4 Input and output configuration

### 5.4.1 SYS\_RANGE (Working stroke)

Command	Parameters	Unit	Group
<b>SYS_RANGE</b> x	x= 10... 10000	mm	<b>IO_CONFIG</b>

This command defines the full stroke, which corresponds to 100 % of the input signal. If the demand is set incorrectly, this leads to incorrect system settings, and the dependent parameters such as speed and gain cannot be calculated correctly.

### 5.4.2 SELECT:X (Position sensor type)

Command	Parameters	Unit	Group
<b>SELECT:X</b> x	x= ANA SSI		<b>IO_CONFIG</b>

The employed sensor type for position measurement can be chosen with this command.

**ANA:** The analog sensor interface (0... 10 V or 4... 20 mA) is active.

**SSI:** The SSI sensor interface is active. The input is matched to the sensor with the SSI commands. The relevant sensor data must be available.

### 5.4.3 SIGNAL X (Type of input signal)

Command	Parameters	Unit	Group
<b>SIGNAL:I</b> x	i= X x= OFF U0-10 I4-20  U10-0 I20-4	-	<b>IO_CONFIG</b>

This command defines the type of input signal (current or voltage). Simultaneously the signal direction can be reversed. In OFF mode, the analog input is deactivated.

### 5.4.4 N\_RANGE:X (Nominal range of the sensor)

Command	Parameters	Unit	Group
<b>N_RANGE:X</b> x	x= 10... 10000	mm	<b>IO_CONFIG</b>

N\_RANGE (nominal range or nominal stroke) is used to define the length of the sensor. This value should usually be equal or higher than SYS\_RANGE.

#### 5.4.5 OFFSET:X (Sensor offset)

Command	Parameters	Unit	Group
OFFSET:X <b>x</b>	<b>x=</b> -100000... 100000	µm	IO_CONFIG

Adjustment of the zero point of the sensor. This parameter is internally limited by SYS\_RANGE.

#### 5.4.6 Using of the commands SYS\_RANGE, N\_RANGE:X and OFFSET:X

The application scaling will be done by these three commands. In this example the system is defined by a length of 120 mm of the sensor, a working stroke of 100 mm of the cylinder and an offset of 5 mm. These parameters have to be typed in and the axis is driving between 5 mm and 105 mm of the sensor stroke and between 0 mm and 100 mm of the cylinder stroke.

Correct scaling:

SYS\_RANGE = 100 (mm)

N\_RANGE:X = 120 (mm)

OFFSET:X = -5000 (µm)

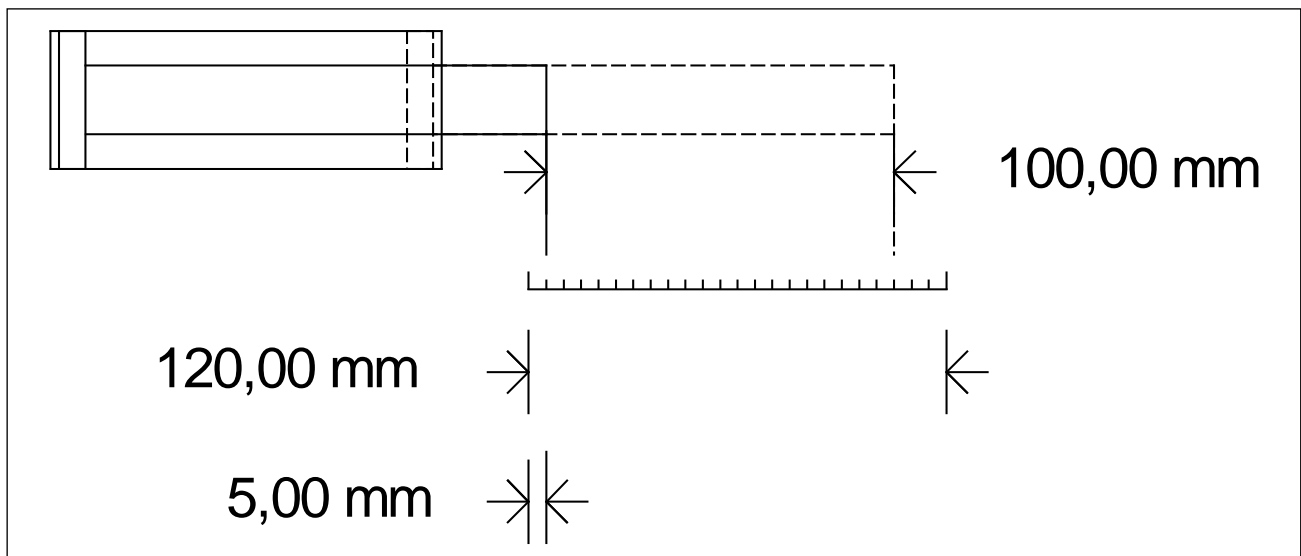


Figure 1 (Input scaling of the sensor)

#### 5.4.7 SSI:POL (Signal direction)

Command	Parameters	Unit	Group
SSI:POL    x	x= + -	-	IO_CONFIG

This command serves to reverse the sensor's working direction.

#### 5.4.8 SSI:RES (Signal resolution)

Command	Parameters	Unit	Group
SSI:RES    x	x= 10... 10000	0,01 µm	IO_CONFIG

The sensor signal resolution is defined with this parameter. Data is entered with the resolution of 10 nm (nanometer or 0,01 µm). This means that a value of 100 defines a sensor with 1 µm resolution. This also makes it possible to scale rotational sensors.

The appropriate data can be found in the sensor data sheet.

#### 5.4.9 SSI:BITS (Number of data bits)

Command	Parameters	Unit	Group
SSI:BITS    x	x= 8... 31	bit	IO_CONFIG

The number of data bits is entered with this parameter.

The appropriate data can be found in the sensor data sheet.

#### 5.4.10 SSI:CODE (Signal coding)

Command	Parameters	Unit	Group
SSI:CODE    x	x= GRAY BIN	-	IO_CONFIG

The data coding is entered with this parameter.

The appropriate data can be found in the sensor data sheet.

#### 5.4.11 SSI:ERRBIT (Position of the "out of range" bit)

Command	Parameters	Unit	Group
SSI:ERRBIT    x	x= 0... 31	bit	IO_CONFIG

The position of the error bit will be defined by this parameter.

The appropriate data can be found in the sensor data sheet.

In case of no error bit, the default value is 0.

#### 5.4.12 PS\_RANGE (System pressure)

Command	Parameters	Unit	Group
PS_RANGE X	x= 10... 1000	bar	IO_CONFIG

This command defines the pressure which corresponds to 100 % of the input signal. If the demand is set incorrectly, this leads to incorrect system settings, and the dependent parameters cannot be calculated correctly.

#### 5.4.13 N\_RANGE X1/X2 (Nominal range of the pressure sensors)

Command	Parameters	Unit	Group
N_RANGE:X1 x	x= 10... 1000	bar	IO_CONFIG
N_Range:X2 x	x= 10... 1000	bar	

N\_RANGE (nominal range) is used to define the nominal value of the sensor. This value should always be equal or higher than SYS\_RANGE / PS\_RANGE. The control parameter cannot be calculated correctly in case of wrong values.

#### 5.4.14 SIGNAL X1/X2 (Type of input signal)

See: description of the SIGNAL:X command

#### 5.4.15 SIGNAL:U (Type and polarity of the output signal)

Command	Parameters	Unit	Group
SIGNAL:U x	x= U+-10 I4-12-20 U--+10 I20-12-4	-	IO_CONFIG

This command is used to define the output signal (voltage or current) and to change the polarity.

Differential output  $\pm 100$  % corresponds with  $\pm 10$  V (0... 10 V at PIN 15 and PIN 16).

Current output  $\pm 100$  % corresponds with 4... 20 mA (PIN 15 to PIN 12). 12 mA (0 %) = center point of the valve.

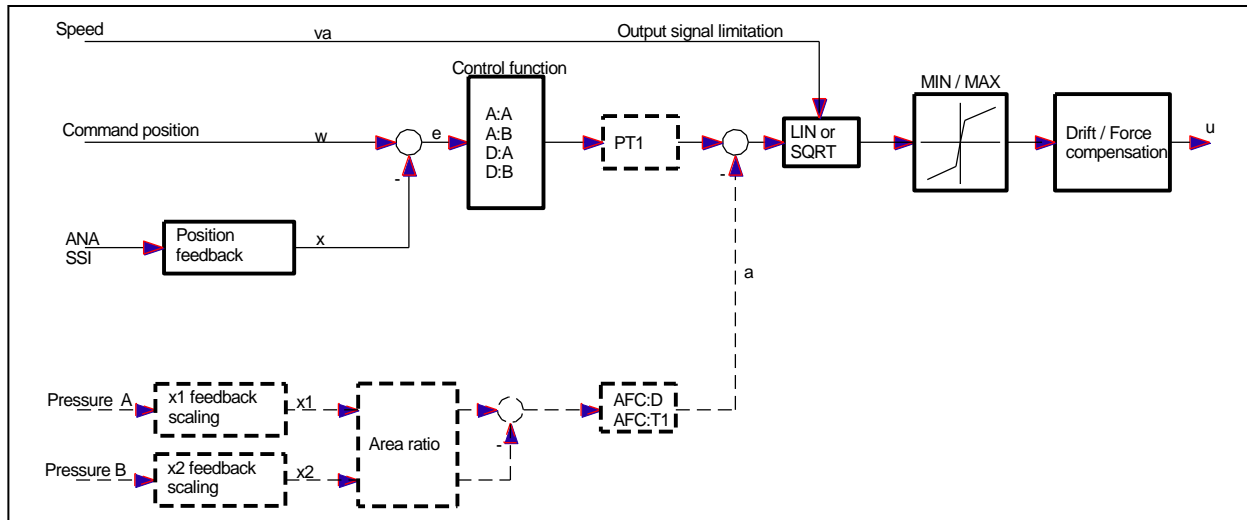


Current output: An output current of  $\ll 4$  mA indicates an error and the module is disabled. The current input of the proportional valves should be monitored by the valve. The valve has to be deactivated in case of  $< 4$  mA input signal. Otherwise the EOUT command can be used to get a defined output signal.

## 5.5 Positioning controller

### 5.5.1 Control structure in SDD mode

The control structure in SDD mode is designed for a robust and simple positioning. The blocks with dashed lines are optionally present, the functions should be used only in case of advanced knowledge of control engineering.



### 5.5.2 VRAMP (Ramp time for external speed demand)

Command	Parameters	Unit	Group
VRAMP .....x	x= 10... 5000	ms	POSITION

The rate of change of speed demand can be limited by this ramp time. In case of NC mode, this parameter should be set to 10 ms.

### 5.5.3 A (Acceleration (ramp) time in SDD mode)

Command	Parameters	Unit	Group
A:i x	i= A B x= 1... 5000	ms	POSITION / SDD

Ramp function for the 1<sup>st</sup> and 3<sup>rd</sup> quadrant.

The acceleration time for positioning is dependent on the direction. "A" corresponds to connection 15 and "B" corresponds to connection 16 (if POL = +).

Normally A = flow P-A, B-T and B = flow P-B, A-T.

For the quadrants 2 and 4, parameters D:A and D:B are used as the deceleration distance demand.



#### 5.5.4 D (Deceleration / braking distance)

Command	Parameters	Unit	Group
D:i      x	i= A B x= 1... 10000	mm	POSITION / SDD

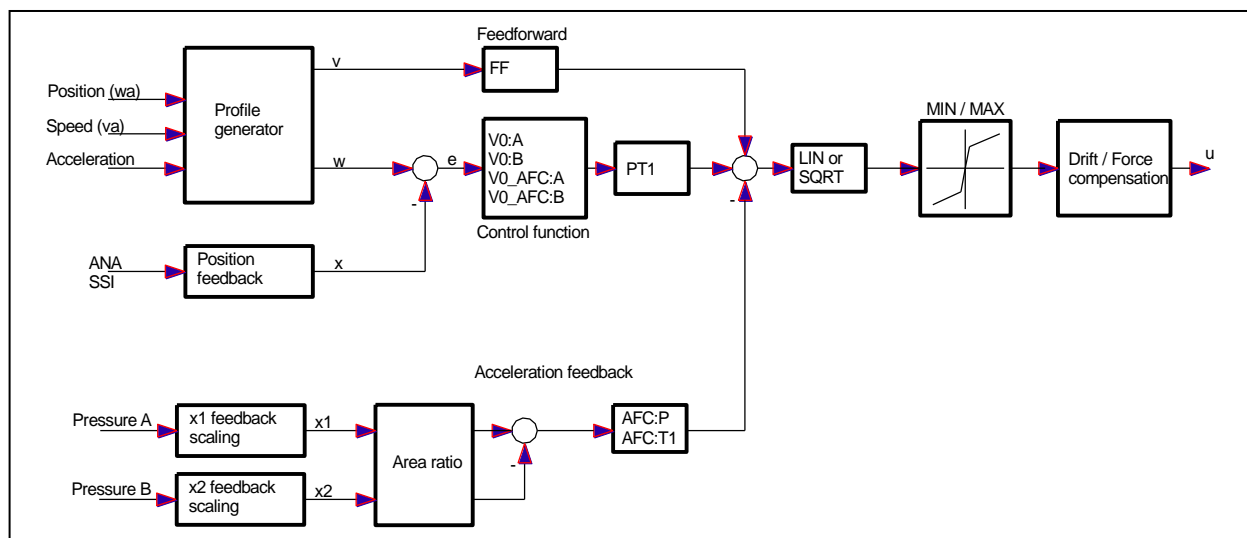
This parameter is specified in mm<sup>3</sup>.

The deceleration stroke is set for each direction of movement (A or B). The control gain is calculated internally depending on the deceleration distance. The shorter the deceleration distance, the higher the gain. A longer deceleration distance should be specified in the event of instability.

$$G_{Intern} = \frac{SYS\_RANGE}{D_i} \quad \text{Calculation of control gain}$$

#### 5.5.5 Control structure in NC mode

Advanced control functions in NC mode. By PT1 behavior, the feedforward control and the acceleration feedback critical drives can be controlled with very low natural frequency too.



<sup>3</sup> **CAUTION!** In older modules this parameter was specified in % of the maximum stroke. Since data specification for this module has now been converted to mm, the relationship between the stroke (SYS\_RANGE command) and these parameters must be taken into account.

### 5.5.6 ACCEL (Acceleration in NC mode)

Command	Parameters	Unit	Group
ACCEL <b>x</b>	<b>x=</b> 1... 20000	mm/s <sup>2</sup>	POSITION / NC

This command is used to define the acceleration in NC mode. The command is active if the VMODE has been parameterized to NC. The maximum acceleration has to be set to a value lower than the technically achievable acceleration in order to yield a stable and oscillation – free behavior.

### 5.5.7 VMAX (Maximum speed in NC mode)

Command	Parameters	Unit	Group
VMAX <b>x</b>	<b>x=</b> 1... 2000	mm/s	POSITION / NC

Specification of the maximum speed in NC mode. This value is defined by the drive system and should be specified as precisely as possible (not too high under any circumstances). The speed is scaled by means of the VELO value or via the external speed demand. The command is only active if the VMODE has been parameterized to NC. If the drive has different speeds between retracting and extending, the lower speed must be set.

### 5.5.8 V0:RES (Scaling of the loop gain)

Command	Parameters	Unit	Group
V0:RES <b>x</b>	<b>x=</b> 1 1/100	–	POSITION / NC

V0:RES = 1      loop gain in s<sup>-1</sup> (1/s) units.  
V0:RES = 1/100      loop gain in 0,01 s<sup>-1</sup> units<sup>4</sup>.



The increased resolution 1/100 should only be used in case of  $V_0 < 4$ .

### 5.5.9 V<sub>0</sub> (Loop gain setting)

Command	Parameters	Unit	Group
V0:i <b>x</b>	<b>i=</b> A B		POSITION
V0_AFC:i <b>x</b>	<b>x=</b> 1... 400	s <sup>-1</sup>	

This parameter is specified in s<sup>-1</sup> (1/s). The directions can be entered separately.  
In NC Mode normally the loop gain is specified rather than the deceleration stroke<sup>5</sup>.  
The internal gain is calculated from this gain value together with the parameter VMAX.

<sup>4</sup> In case of very low loop gains (1 s<sup>-1</sup> to 3 s<sup>-1</sup>) the better resolution of the adjustment should be selected.

<sup>5</sup> The loop gain is alternatively defined as a KV factor with the unit (m/min)/mm or as V<sub>0</sub> in 1/s. The conversion is  $KV = V_0/16,67$ .

$$D_i = \frac{v_{\max}}{V_0}$$

$$G_{Intern} = \frac{SYS\_RANGE}{D_i}$$

Calculation of the internal control gain

In NC Mode the following error at maximum speed is calculated by means of the loop gain. This following error corresponds to the deceleration stroke with stroke-dependent deceleration. The conversion and therefore also the correct data demands related to the closed loop control system are relatively simple if the relationship described here is taken into account.

### 5.5.1 D:S (Stop - Overtravel)

Command	Parameters	Unit	Group
D:S <b>x</b>	<b>x=</b> 1... 10000	mm	<b>POSITION</b>

If the ENABLE signal is switched off, the output signal is always abruptly removed. If only the START bit is switched off before a movement is completed, the controller brakes the axis with a defined deceleration. This is set by the parameter D:S as the overtravel. After deactivating START, a new target position in relation to the speed (current position plus D:S) is calculated and specified as the setpoint. Higher values lead to smoother braking.

If the NC mode is selected, braking is compatible with previous versions for input values ≤ 10 mm. In this case, the lag distance serves as overtravel, i.e. the axis decelerates by immediately stopping the profile generator. This is usually a relatively hard reaction, which can be made softer by entering larger values.

### 5.5.2 PT1 (Transfer function of the controller)

Command	Parameters	Unit	Group
PT1 <b>x</b>	<b>x=</b> 1... 300	ms	<b>POSITION</b>

This parameter can be used to adapt the transfer function of the control function.

Hydraulic drives are often critically to control, especially in case of very fast valves. The PT<sub>1</sub> filter can be used to improve the damping rate and allows therefore higher loop gains.

Requirements for the use are: The natural frequency of the valve should be equal or higher than the natural frequency of the drive.

### 5.5.3 CTRL (Deceleration characteristics)

Command	Parameters	Unit	Group
CTRL <b>x</b>	<b>x=</b> lin sqrt1 sqrt2	-	<b>POSITION</b>

The deceleration characteristic is set with this parameter. In case of positively overlapped proportional valves the SQRT function should be used. The non-linear flow function of these valves is linearized by the SQRT<sup>6</sup> function.

In case of zero lapped valves (control valves and servo valves) the LIN or SQRT1 function should be used depending on the application. The progressive characteristic of the SQRT1 function has a better positioning

<sup>6</sup> The SQRT function generates constant deceleration and thus reaches the target position faster. This is achieved by increasing the gain during the deceleration process.

accuracy but can also lead to longer positioning times in individual cases.

**LIN:** Linear deceleration characteristic (gain is increased by a factor of 1).

**SQRT1:** Root function for braking curve calculation. The gain is increased by a factor of 3 (in the target position). This is the default setting.

**SQRT2:** Root function for braking curve calculation. The gain is increased by a factor of 5 (in the target position). This setting should only be used with a significantly progressive flow through the valve.

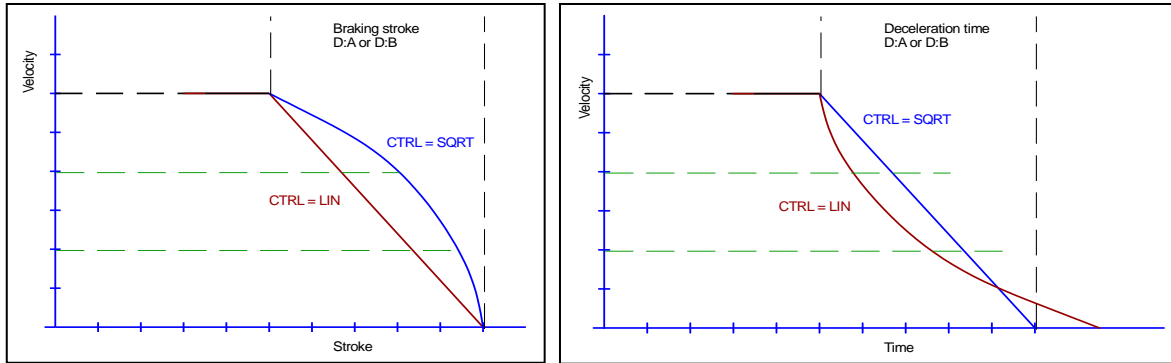


Figure 2 (Braking function with respect to stroke and time)

#### 5.5.4 MIN (Deadband compensation)

#### 5.5.5 MAX (Output scaling)

#### 5.5.6 TRIGGER (Response threshold for the MIN parameter)

Command		Parameters	Unit	Group
<b>MIN:i</b>	<b>x</b>	i= A B x= 0... 6000	- 0,01 %	<b>POSITION</b>
<b>MAX:i</b>	<b>x</b>	x= 3000... 10000	0,01 %	
<b>TRIGGER</b>	<b>x</b>	x= 0... 4000	0,01 %	

The output signal to the valve is adjusted by means of these commands. A kinked volume flow characteristic is used instead of the typical overlap step for the position controls. The advantage is a better and more stable positioning behavior. At the same time, kinked volume flow characteristics can also be adjusted with this compensation<sup>7</sup>.

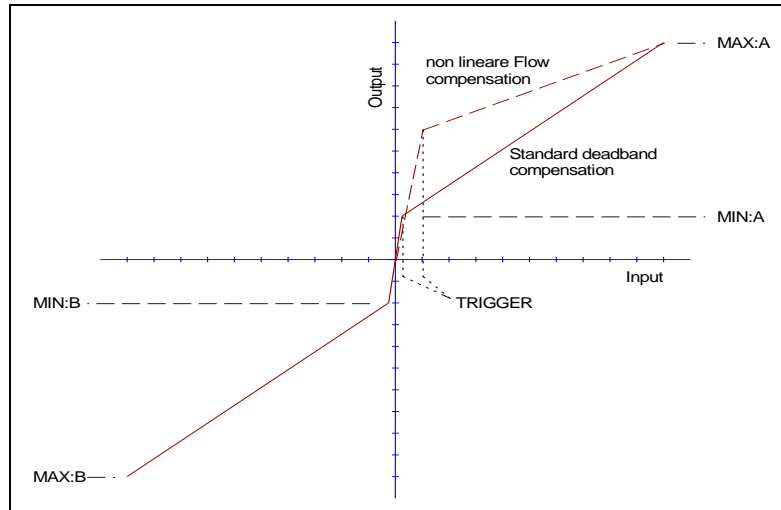
<sup>7</sup> Various manufacturers have valves with a defined nonlinear curve: e.g. a kink at 40 or 60 % (corresponding to 10 % input signal) of the nominal volume flow. In this case the TRIGGER value should be set to 1000 and the MIN value to 4000 (6000).

If zero lapped or slightly underlapped valves are used, the volume flow gain in the zero range (within the underlap) is twice as high as in the normal working range. This can lead to vibrations and jittery behavior. To compensate this, the TRIGGER value should be set to approximately 200 and the MIN value to 100. The gain in the zero point is thus halved and an overall higher gain can often be set.



**CAUTION:** If there should also be adjustment options for deadband compensation on the valve or valve amplifier, it must be ensured that the adjustment is performed either at the power amplifier or in the module.

If the MIN value is set too high, this has an effect on the minimum speed, which can then no longer be adjusted. In extreme cases this leads to oscillation around the controlled position.



### 5.5.7 OFFSET (Valve zero point adjustment)

Command	Parameters	Unit	Group
OFFSET <b>x</b>	<b>x=</b> -4000... 4000	0,01 %	<b>POSITION</b>

This parameter is entered in 0,01 % units.

The offset value is added to the output value. Valve zero offsets can be compensated with this parameter.

## 5.6 Pressure controller

### 5.6.1 Operating modes / controller structure

The pressure controller in the UHC can perform the following functions:

- None, i.e. the unit operates as a pure positioning module.
- Exclusive pressure control (PQ mode), no positioning
- Pressure limiting control, i.e. as soon as the specified pressure setpoint is reached, the pressure controller takes over.

Since the operating mode is selected via control bits of the fieldbus interface, it is possible to switch between these variants during operation.



**ATTENTION:** Avoid unnecessary switching by the higher-level control system.

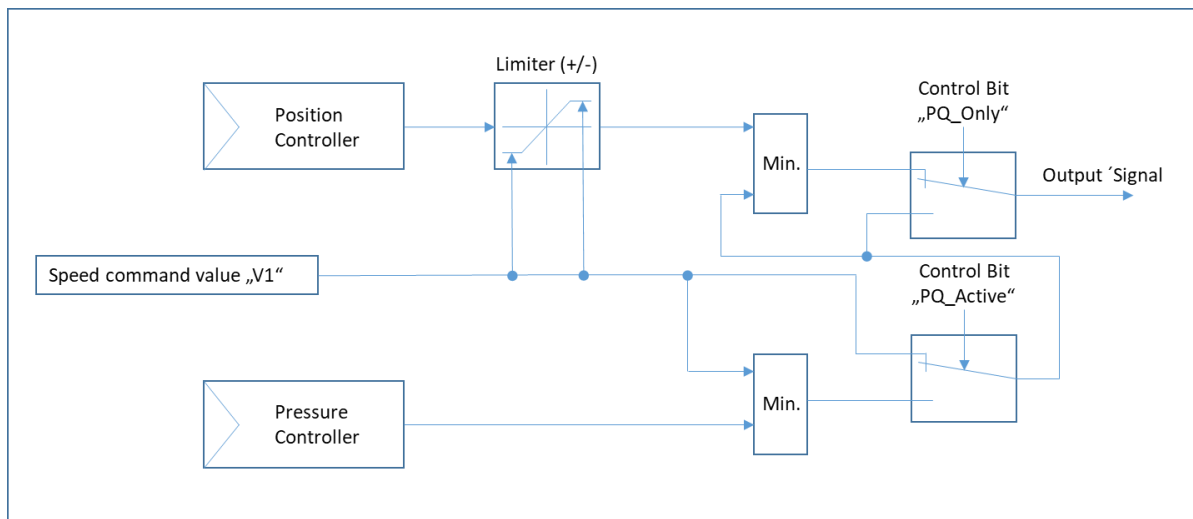
Example: If a positioning movement is performed against a stop or a workpiece and it is clear that first a positioning process in NC mode at a specified speed and later a transition to pressure control is made, the pressure controller should be activated from the beginning. In this way the UHC with its fast cycle times can optimally perform the transition between the two controllers.

Control of the operating mode:

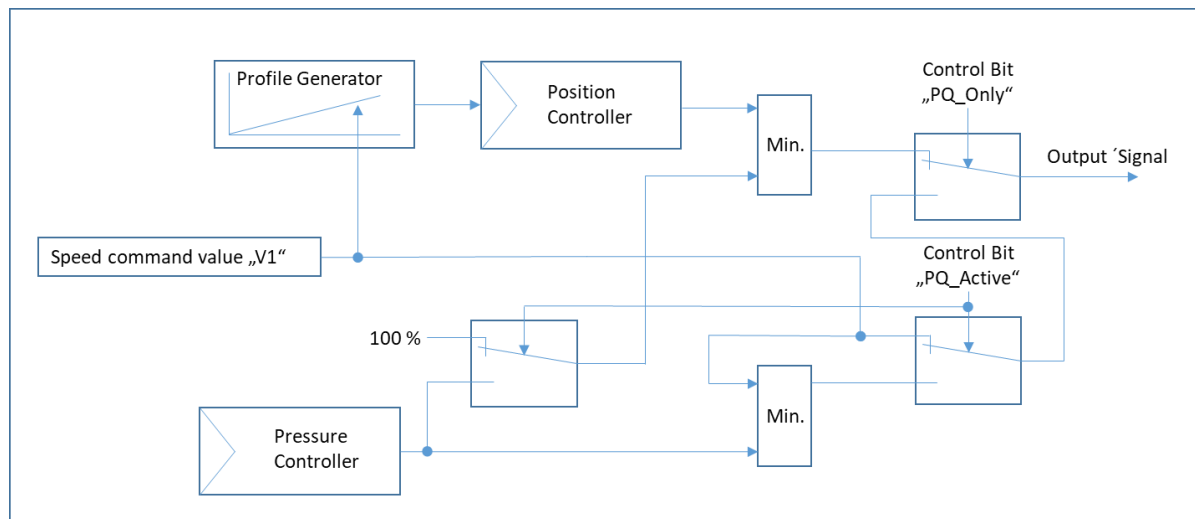
Mode	Bit „PQ_Active“	Bit „PQ_only“
pure positioning	FALSE	FALSE
PQ – mode, no positioning	TRUE	TRUE
limiting control	TRUE	FALSE
direct control of the output	FALSE	TRUE

Controller schema:

SDD - Mode

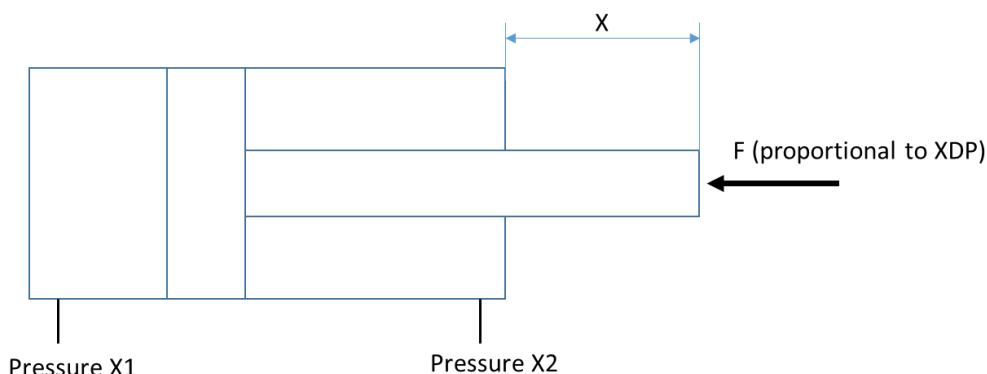


NC – Mode:



### 5.6.2 Operating direction / Inverting

In order to achieve a correct function in the interaction between pressure and position control, it is important that the direction of the actual value signals is determined according to this specification:



- A pressure at the measuring point "X1" causes the cylinder to extend (in this example) or to increase the measured displacement signal "X"
- A pressure at measuring point "X2" causes the cylinder to retract or produce a reduction of the measured displacement signal "X", if signal X2 is present (omission e.g. in the case of plungers)
- A positive differential pressure XDP with "PQ Inverse" not set therefore corresponds to a force against the direction of movement of increasing actual position values X.

In a specific case, the sensors, the effective direction of the cylinder or the area ratio can deviate as long as these three principles are observed.

If, for example, the sensor polarity of the position measurement is inverted, it may be necessary to swap the connections of the pressure sensors on the module and change the parameter ARATIO to its reciprocal value.

Control of the pressure controller function by the bit "PQ\_Inverse:

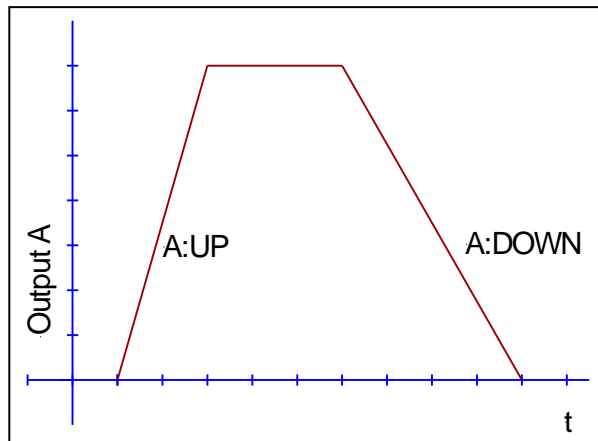
This bit is not suitable to enable a different assignment of the signals (see above). Instead, this bit can be used to determine whether the pressure controller should respond when the cylinder is extended or retracted (more precisely: during a movement with rising or falling "X").

If the bit is set, the calculation of XDP is inverted -> a positive value now corresponds to a force that is opposite to the retraction. At the same time, the coupling of the pressure controller signal into the signal path is carried out via a maximum value selection, so that the controller can influence the activation of the valve in the negative direction.

### 5.6.3 RA (Command signal ramp time)

Command	Parameters	Unit	Group
RA:i x	i= UP DOWN x= 1... 600000	ms	PRESSURE

The ramp times for the pressure command value are defined here in ms. Two separate time values are entered for increasing and decreasing pressure.



### 5.6.4 P\_OFFSET (pressure offset)

Command	Parameters	Unit	Group
P_OFFSET x	x= -50000... 50000	mbar	PRESSURE

This parameter is entered in mbar.

This parameter adds an offset value to the resulting feedback signal. This serves for example to compensate external force differences (suspended loads, spring forces etc.).

### 5.6.5 ARATIO (Cylinder area ratio)

Command	Parameters	Unit	Group
ARATIO x	x= 200... 5000	-	PRESSURE

In order to limit the output force in either direction correctly, the parameter ARATIO provides the ratio of the two areas of the cylinder (bore side / piston side).

Accordingly, a corresponding value of 1000 defines a ratio of 1.

For example:

Area ratio = 2.08:	ARATIO has to be set to 2080
Area ratio = 0,5:	ARATIO has to be set to 500
Area ratio = 1:	ARATIO has to be set to 1000



## 5.6.6 C1/C2 (PID control parameters)

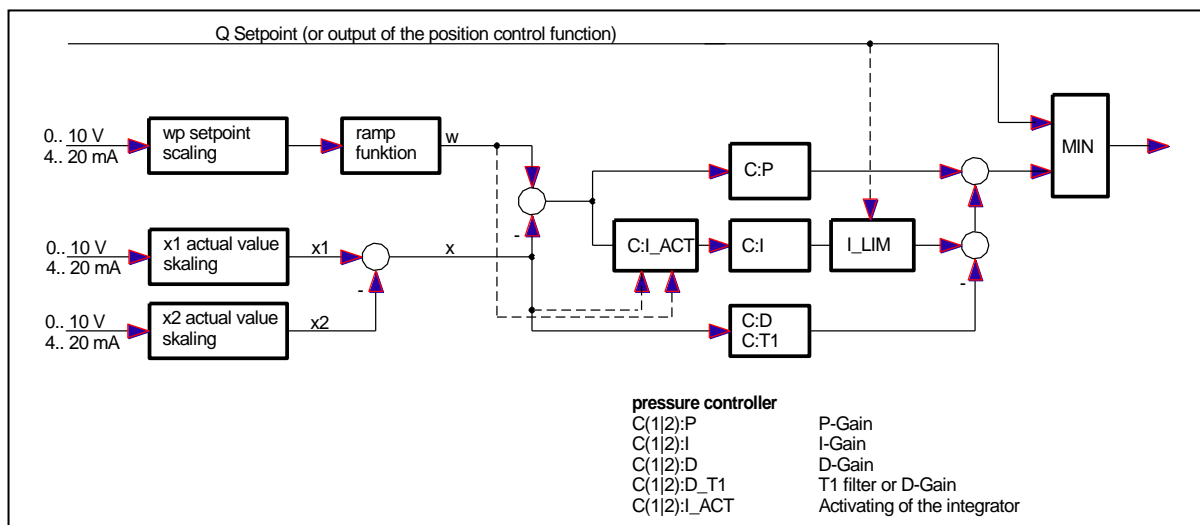
Command	Parameters	Unit	Group
<b>Cx:i</b> <b>x</b>	<b>X = 1 2 (parameter set)</b> <b>i= P I D D_T1 I_ACT</b>		<b>PRESSURE</b>
	<b>:P</b> <b>x= 1... 10000</b>	<b>0,01</b>	
	<b>:I</b> <b>x= 0... 30000</b>	<b>0,1 ms</b>	
	<b>:D</b> <b>x= 0... 1200</b>	<b>0,1 ms</b>	
	<b>:D_T1</b> <b>x= 10... 1000</b>	<b>0,1 ms</b>	
	<b>:I_ACT</b> <b>x= 0... 10000</b>	<b>0,01 %</b>	

The control function will be parameterized via this command. The two parameters sets can be selected by a fieldbus bit.

The P, I and D gains are similar to a standard PID controller. The T1 factor is used for the D-gain in order to suppress high-frequency noise.

I\_ACT controls the integrator function. To reduce pressure overshoots, an activation point for the integrator can be programmed via the I\_ACT value. The integrator is activated if the actual pressure is higher than the programmed threshold.

The integrator function of the controller can be disabled in special cases by setting C:I to zero.



## 5.7 Advanced functions

### 5.7.1 FF (Feed forward in NC mode)

Command	Parameters	Unit	Group
FF:i      x	I= A B x= 0... 10000	0,01	EXTRA

With this command a feed forward value is parameterized for the compensation of the following distance. The function is activated via the corresponding control bit (fieldbus).

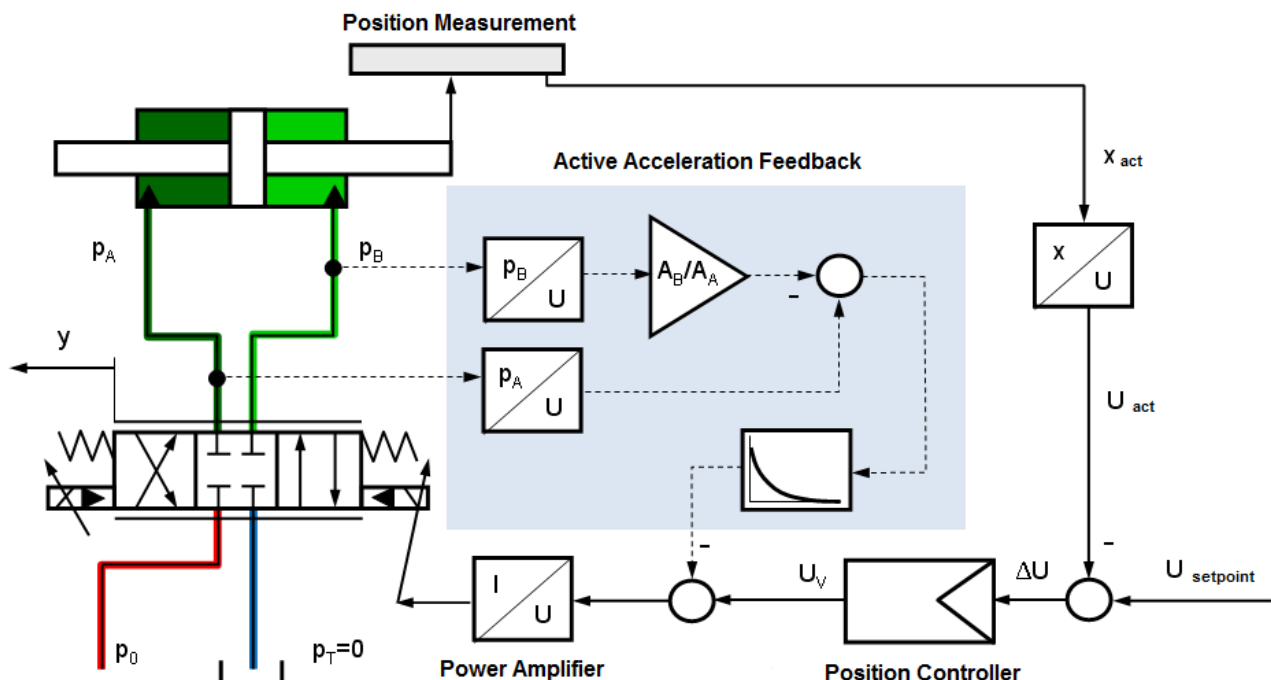
### 5.7.2 AFC:P (Gain of the acceleration feedback)

### 5.7.3 AFC:T1 (Filter time for acceleration feedback)

Command	Parameters	Unit	Group
AFC:i      x	i= P T1 P      x= 0... 10000 T1     x= 10... 1000	0,01 ms	EXTRA

This command is used to define the filter time constant and gain of the acceleration feedback. The acceleration is measured by the differential pressure together with a kind of D-filter to compensate a constant external force (pressure).

The acceleration feedback can be activated by a control bit over the fieldbus. The loop gain parameters are switched over simultaneously between V0 and V0\_AFC.



#### 5.7.4 AFC\_V0:A/B (Loop gain with active acceleration feedback)

Command	Parameters	Unit	Group
AFC_V0:i    x	i= A B x= 1... 400	s <sup>-1</sup>	EXTRA

This parameter is specified in s-1 (1/s). The directions can be entered separately.



In case of a defective pressure sensor, the loop gain V0 should be used by the deactivation of the corresponding fieldbus bit. Typically a lower loop gain is used without acceleration feedback.

#### 5.7.5 Drift compensation / high accurate positioning

The high accurate positioning or the drift compensation can be used in case of external influence which is limiting the positioning accuracy. This function can be critical because limit cycling<sup>8</sup> could be caused by wrong parameterization.

Which positioning errors can be compensated<sup>9</sup>?

1. Zero point adjustment of the valve. By this kind of error a constant offset between command and feedback signal remains. This error is more or less constant.
2. Zero point deviation depending on the temperature. The same behavior as point 1, but the effect is increasing slowly (over the temperature).
3. Position error caused by an external force. All control and servo valves have a typical pressure gain characteristic. In case of external forces an output signal of 2...3 % has to be generated for the compensation of this force. And this signal is proportional to the positioning error. In opposite to point one and two the positioning error generated by forces can vary from cycle to cycle.

How does the drift compensation / high accurate positioning work?

The position errors should be compensated when the axis is near by the target position. The drift compensator generates a slowly changing output signal (integrating behavior) by which the a.m. errors can be eliminated.

To prevent instabilities, the integrator value will be frozen when the output value is lower than the deactivation limit (DC:DV).

##### **Drift compensation (zero point adjustment)**

By this function position errors described below point one and two are eliminated.

##### **High accurate positioning (external force compensation)**

To compensate positions errors as described below point three.

##### **Control bits via fieldbus:**

Through the fieldbus it is possible to activate drift compensation as well as high accurate positioning.

This can be accomplished by using the following control bits:

<sup>8</sup> The „limit cycling“ is a small and permanent oscillation around the target position. The main reason are static frictions and the hysteresis of the valve. By proper parameter setting, this can be avoided under the boundary condition that the desired accuracy is not achieved. In this case, the hydraulic system is the limiting factor in the accuracy.

<sup>9</sup> This is relevant for zero lapped control valves and servo valves.

**DC\_ACTIVE:** General activation of the drift compensation and high accurate positioning<sup>10</sup>.

**DC\_FEEZE:** Freezing of the static drift compensation value.

**DC\_F\_POS:** Activation of the high accurate positioning (dynamic drift compensation).

### Typical setup

Valve pressure gain: 2,5 %; the activation point has to be set to 3... 5 % (DC:AV 300... 500).

Valve hysteresis: 0,5 %; the deactivation point has to be set to 0,7... 1,0 % (DC:DV 70... 100). The lower the value the better the accuracy.

DC:CR should be equal to DC:AV. Limiting the control range of the integrator is necessary to avoid long settlement durations.

The optimum integrator time has to be determined experimentally. Starting with higher values is recommended.

The integration time usually has to be determined by experiments. For this it is recommended to start with a long time (1500 ms) and to reduce it gradually. If overshooting or limit cycling occurs, the time setting has become too small.

### 5.7.6 DC:AV (Activation value)

### 5.7.7 DC:DV (Deactivation value)

### 5.7.8 DC:I (Integrator time)

### 5.7.9 DC:CR (Integrator limitation)

Command		Parameter	Unit	Group
DC:I	x	x= 0... 2000	ms	EXTRA
DC:AV	x	x= 0... 2000	0,01 %	
DC:DV	x	x= 0... 1000	0,01 %	
DC:CR	x	x= 0... 500	0,01 %	

DC:I This parameter is used to define the integrator time. The lower this value the faster the compensation. Low values will result in „limit cycling“.

DC:AV This parameter is used to define the activation point (activation value). The DC function is completely deactivated in case of DC:AV = 0.

DC:DV This parameter is used to define the deactivation point (DV = deactivation value) Within the deactivation window no compensation value will be calculated (frozen state).  
DC:AV = 0 should be used for best positioning, but „limit cycling“ can occur. This value should be set to 50 % of an acceptable error.

DC:CR The output range of the DC function will be limited (CR = control range) by this parameter.

<sup>10</sup> The static drift compensation to adjust the zero point and the freezing of this value should always be carried out at first. Only by this it is possible to avoid or minimise overshooting of the target position.

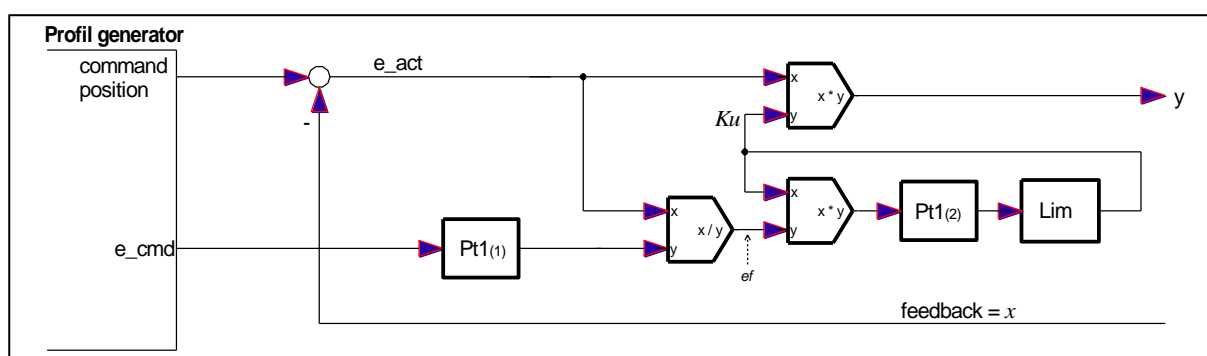
## 5.7.10 MR-Controller

Command	Parameters	Unit	Group
MR:T1 x	x= 0... 1000	ms	EXTRA
MR:T2 x			

The MR controller is a subordinate controller that linearises the hydraulic drive's behavior. The drive moves with a lag defined by the loop gain and the specified maximum speed (independent of external load forces).



**ATTENTION!** The MR controller can only be used in NC mode.



The controller is parameterized via the time constants T1 and T2.

The procedure for controller optimization is:

1. Disable MR controller
2. Optimize the loop gain in NC mode. It is advisable to reduce the loop gain slightly because the MR-controller is an additional dynamic element in the control loop.
3. Parameterize the MR controller:  $T1 = 1 / V0$  and  $T2 = T1 * 1.6$   
With this default setting, satisfactory results should be achievable.  
The correct parameterization is of course application-dependent.
4. Activate the MR controller by setting the appropriate bit via the fieldbus

## 5.7.11 SELPLUS (additionally transmitted bus signals)

Command	Parameter	Unit	Group
SELPLUS:i X	I= 1 2 x= - E_S CS WP EP CP U VACT	-	EXTRA

Bytes 22 - 25 of the output signals to the fieldbus can be freely connected to two of the internal process variables. These parameters are used to determine the assignment.

The following table on the next page gives an overview of the adjustable signals, their value ranges and scaling.

Signal	Description	Range	Unit
E_S	Target - lag distance	+/- 30000	0,01 mm
CS	Control signal of the position controller	+/- 10000	0,01 %
WP	Pressure setpoint after ramp	0... 10000	0,1 bar
EP	Pressure setpoint minus actual pressure value	+/- 10000	0,1 bar
CP	Control signal of the pressure controller	+/- 10000	0,01 %
U	Output signal of the module	+/- 10000	0,01 %
VACT	Measured actual speed	+/- 30000	0,1 mm/s

### 5.7.12 Limits of the pressure Controller

Command	Parameter	Unit	Group
CP:I_ULIM X	x= 0... 10000	0,01 %	EXTRA
CP:I_L LIM X	x= -10000... 0	0,01 %	

These parameters can be used to define the limits of the pressure controller or its integral part.

The upper limit is used to realize a continuous transition from position to pressure control. If values < 10000 are entered here, this means that the integrator no longer covers the complete output range of the position controller. If the actual pressure value approaches the setpoint when the position controller is under full control, the P component is reduced and the pressure controller takes over continuously as soon as the sum of this component and the limited integral component falls below the output signal of the position controller.

If you want to prevent or limit the pressure controller from controlling the valve in the opposite direction beyond zero (active pressure reduction), you can use the ...LLIM parameter. If it is set to the value "0" this is completely suppressed.

### 5.7.13 PROFSTOP (Stop of the profile generator)

Command	Parameter	Unit	Group
PROFSTOP X	x= ON OFF	-	EXTRA

If the device is operated in NC mode with the pressure controller activated, the profile generator will continue to run when the pressure controller intervenes, thus increasing the lag between the actual value and the setpoint. If the operating situation then changes and the position controller takes over the guidance again, this is accompanied by a fast movement in the setpoint direction which does not follow the profile. To avoid this behavior, the device can be set up via the parameter "PROFSTOP = ON" in such a way that the profile generator stops as soon as it has lost its guidance over the movement due to the intervention of the pressure controller. If the pressure regulator does not intervene any more, the profile is automatically released again.

## 5.8 Special commands

Please contact W.E.St. in case of using these commands.

### 5.8.1 AINMODE (Input scaling mode)

Command	Parameter	Unit	Group
AINMODE    x	x= EASY MATH	–	TERMINAL

This command is used to switch over the kind of input scaling.

The AINMODE is used to define the kind of parameterizing of the analogue inputs. The EASY mode (DEFAULT) supports a simple and application oriented input scaling.

The MATH mode supports the free input scaling by a linear equation. This mode is compatible to our older modules.



Attention: This command can be executed in the terminal window only. In case of switching back, DEFAULT data should be reloaded.

### 5.8.2 AIN (Analogue input scaling)

Command	Parameters	Unit	Group
AIN:X	a= -10000... 10000	–	MATH / IO_CONFIG
AIN:X1	b= -10000... 10000	–	
AIN:X2	c= -10000... 10000	0,01 %	
	x= V C	–	

This command offers an individual scalable input. The following linear equation is used for the scaling.

$$\text{Output} = A/B \cdot (\text{Input} - C)$$

The “**C**” value is the offset (e.g. to compensate the 4 mA in case of a 4... 20 mA input signal).

The variables **A** and **B** are defining the gain factor with which the signal range is scaled up to 100 % (e.g. 1.25 if using 4... 20mA input signal, defined in default current settings by A = 1250 and B = 1000). The internal shunt for the current measuring is activated with switching the **X** value.

The gain factor is calculated by setting the usable range (**A**) in relation to the real used range (**B**) of the input signal. Usable are 0... 20mA, means (**A**) has the value **20**. Really used are 4... 20mA, means (**B**) has a value of **16** (20-4). Not used are 0... 4mA. In a range of 20mA this is an offset of 20%, means a value of **2000** for (**C**). Last but not least (**X**) has to be set to **C** choosing current signal.

In this case AIN command would look like this:

AIN:I 20 16 2000 C or AIN:I 1250 1000 2000 C.

#### Typical settings:

Command	Input	Description
<b>AIN_1:X</b> 1000    1000    0 V	0... 10 V	Range: 0... 100 %
<b>AIN_1:X</b> 10        8        1000 V OR <b>AIN_1:X</b> 1000    800    1000 V	1... 9 V	Range: 0... 100 %; 1 V = 1000 used for the offset and gained by 10 / 8 (10 V divided by 8 V (9 V -1 V))
<b>AIN_1:X</b> 10        4        500 V OR <b>AIN_1:X</b> 1000    400    500 V	0,5... 4,5 V	Range: 0... 100 %; 0,5 V = 500 used for the offset and gained by 10 / 4 (10 V divided by 4 V (4,5 V -0,5 V))
<b>AIN_1:X</b> 20        16        2000 C OR <b>AIN_1:X</b> 2000    1600    2000 C OR <b>AIN_1:X</b> 1250    1000    2000 C	4... 20mA	Range: 0... 100 %  The offset will be compensated on 20 % (4 mA) and the signal (16 mA = 20 mA – 4 mA) will be gained to 100 % (20 mA).  Each of this parameterization for 4... 20 mA is setting the range to 0... 100 %.

### 5.8.3 ETC\_LOOP (Transfer rate)

Command	Parameters	Unit	Group
ETC_LOOP    X	x= NORMAL   FAST		<b>TERMINAL</b>

#### Only available when using EtherCAT devices!

In the default setting, the data is sent and received every 6 ms. The setting "FAST" shortens the data rate to 3 ms. A fieldbus parameterization is not possible if this rate has been chosen.

### 5.8.4 MR (Activation of the MR-Controller)

Command	Parameters	Unit	Group
MR            X	x= ON   OFF		<b>TERMINAL</b>

Like the activation via the fieldbus, the MR controller can be activated by this command as described in the chapter MR-controller. The control bit "MR" of the fieldbus control is overwritten, if this command has been parameterized to "ON". The purpose of this function is to be able to activate the MR – controller without fieldbus connection. So it is possible to operate it during the commissioning using the remote – control function in the monitor window of the WPC program.



### 5.8.5 Remote control square - wave generator

Command	Parameters	Unit	Group
ACA:i      x	i= CYCLE POS1 POS2  :CYCLE    x= 0... 30000 :POS1     x= 0... 10000 :POS2     x= 1... 10000	  ms mm mm	<b>TERMINAL</b>

Using remote control (a WPC function), a square-wave generator can facilitate commissioning by holding the axis in motion cyclically between two positions. The lower position is determined by the command "ACA: POS1" in mm. The upper position is corresponding to "ACA: POS2".

The generator is only started if the parameter "ACA: CYCLE" is set to a time above zero. The value should be chosen appropriately according to the axis speed.

### 5.8.6 PCTRLOLD (Compatibility mode)

Command	Parameter	Unit	Group
PCTRLOLD    X	x= ON OFF	-	<b>TERMINAL</b>

With this command it can be achieved that the pressure controller behaves with regard to its tracking as it did up to and including version 2140: When compatibility mode is enabled, the tracking is inactive.

### 5.8.7 DIAG (Query of the last switch-off causes)

If this command is entered in the terminal window, the last 10 shutdowns ( loss of Ready when Enable is present) are displayed. However, the causes of the shutdown are not stored when the supply voltage is switched off. The last cause is displayed in the bottom line of the list. Entries "---" indicate unused memory cells.

An example:

```
>DIAG
---
---
---
---
---
---
---
---
SSI-Sensor
INPUT PIN 6
>|
```

### 5.8.8 SSI:BITMASK

Kommando	Parameter	Einheit	Gruppe
SSI:BITMASK    X	x= - 2147483647 ... 2147483647	-	<b>TERMINAL</b>

Some SSI sensors provide several bits with diagnostic information. Via the parameter SSI:ERRBIT one of these bits can be selected for error detection and removed from the conversion of the measured value. If several bits must be blanked out, this can be done via this mask. Convert the bit pattern, in which a "1" marks the bits to be blanked, into a decimal number and enter this number here.

### 5.8.9 PROCESS DATA (Monitoring)

Command	Description	Unit
<b>WA</b>	Demand value (input signal)	mm
<b>W</b>	Demand value (according to the profile generator)	mm
<b>VA</b>	Speed input	%
<b>X</b>	Actual position value	mm
<b>E</b>	Position error value	mm
<b>E_S</b>	Lag setpoint <sup>11</sup>	mm
<b>CS</b>	Output of the position controller	%
<b>WAP</b>	Command pressure	%
<b>WP</b>	Command pressure (after ramp)	bar
<b>X1</b>	Actual pressure value 1	bar
<b>X2</b>	Actual pressure value 2	bar
<b>XDP</b>	Pseudo differential pressure <sup>12</sup>	bar
<b>EP</b>	Pressure error value	bar
<b>CP</b>	Output signal of the pressure controller	%
<b>U</b>	Output signal of the module	%
<b>VACT</b>	Actual measured speed	mm/s

The process data are the variables which can be observed continuously on the monitor or on the oscilloscope.

<sup>11</sup> The lag setpoint is calculated on the basis of the adjusted controller gain, the maximum speed of the axis and the actual speed setpoint (only in NC mode). If the MR controller is activated it is possible to compare E and E\_S during the movement and by this to evaluate the transient response of the algorithm.

<sup>12</sup> This represents the process value of the pressure controller.  $XDP = X1 - ARATIO * X2$  or if PQ\_Inverse is set:  $XDP = ARATIO * X2 - X1$

## 6 Common device functions

### 6.1 Failure monitoring

Following possible error sources are monitored continuously when SENS = ON/AUTO:

Source	Fault	Characteristic
Feedback signal pressure PIN 13 / PIN 6 - 4... 20 mA	Out of range or broken wire	The output is deactivated if the pressure controller is enabled via the control bit "PQ_Active". There is no reaction in pure positioning mode.
Feedback signal position PIN 14 - 4... 20 mA	Out of range or broken wire	The output will be switched off.
SSI-Sensor Sensor value	Out of range or broken wire	The output will be switched off.
EEPROM (when switching on)	Data error	The output is deactivated. The module can only be activated by saving the parameters again!
RC - Mode	The WPC connection (since WPC-V4.0 ) is disconnected during RC operation, e.g. by exiting the program or pulling the USB plug.	The output will be switched off.



**CAUTION:** Take care of the EOUT command. Changes will influence the behavior.

### 6.2 Troubleshooting

It is assumed that the device is in an operable state and there is communication between the module and the WPC-300. Furthermore, the valve control parameterization has been set with the assistance of the valve data sheets.

The RC in monitor mode can be used to analyze faults.



**CAUTION:** All safety aspects must be thoroughly checked when working with the RC (Remote Control) mode. In this mode the module is controlled directly and the machine control cannot influence the module.

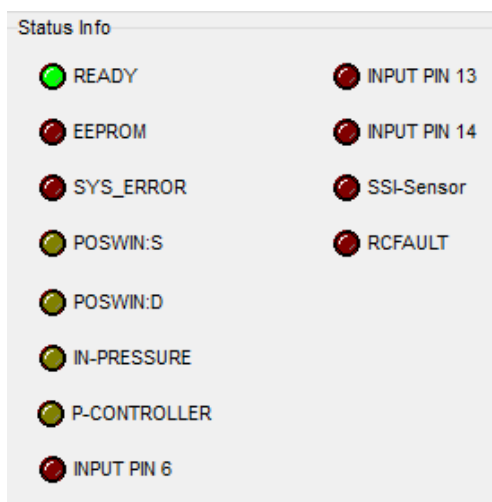
FAULT	CAUSE / SOLUTION
ENABLE is active, the module does not respond and the READY LED is off.	<p>There is presumably no power supply or the ENABLE signal (PIN 8) is not present. If there is no power supply, there is also no communication via our operating program. If a connection has been made to the WPC-300, then a power supply is also available.</p> <p>If the power supply exists, an attempt should be made to see whether the system can be moved by means of the HAND+ and HAND- inputs (measuring the output signal to the valve is helpful).</p>
ENABLE is active, the READY LED is flashing.	<p>The flashing READY LED signals that a fault has been detected by the module. The fault could be:</p> <ul style="list-style-type: none"> <li>• A broken cable or no signal at the input (PIN 13 or PIN 14), if 4... 20 mA signals are parameterized.</li> <li>• No SSI sensor</li> <li>• Internal data error: press the command/SAVE button to delete the data error. The system reloads the DEFAULT data.</li> </ul> <p>With the WPC-300 operating program the fault can be localized directly via the monitor.</p>
ENABLE is active; the READY LED is on, the system moves to an end position.	<p>The control circuit polarity is incorrect. The polarity can be changed with the POL command or by reversing the connections to PIN 15 and PIN 16.</p>
ENABLE is active, the READY LED is on, the STATUS LED is not on, the system moves to the target position but doesn't reach it (positioning error).	<p>Serious positioning errors can result from incorrect parameterization or incorrect system design.</p> <ul style="list-style-type: none"> <li>• Is the cylinder position specified correctly?</li> <li>• Are the deceleration strokes correct (to start the system the deceleration distances should be set to approx. 20... 25 % of the cylinder position<sup>13</sup>)?</li> <li>• Is the valve a zero lapped control valve or a standard proportional valve? In case of a proportional valve, the valve overlap which may be present should be compensated for with the MIN parameters. Typical values can be found in the valve data sheet.</li> </ul>
ENABLE is active, the READY LED is on and the system oscillates on the target.	<p>The system is working and also actuating the valve.</p> <p>Various potential problems could be:</p> <ul style="list-style-type: none"> <li>• The parameterization is not yet adjusted to the system (gain too high).</li> <li>• There is severe interference on the power supply.</li> <li>• Very long sensor cables (&gt; 40 m) and sensor signal interference.</li> <li>• The MIN setting to compensate the valve overlap is too high.</li> </ul> <p>As a basic principle, the parameterization of the sensor data and the controller settings must be carried out first (before switching on). An incorrect demand is equivalent to an incorrect system design which then leads to incorrect operation. If the system oscillates, the gain should first be reduced (longer deceleration distances for D:A and D:B) and in case of overlapped valves the MIN parameter should also be reduced.</p>
Speed too low	<p>The drive may be able to move to position but the speed is too low.</p> <ul style="list-style-type: none"> <li>• Check the control signal to the valve <ul style="list-style-type: none"> <li>• via the integrated oscilloscope (U variable)</li> <li>• measure the signal to the valve with an external oscilloscope/voltmeter.</li> </ul> </li> <li>• If the control is within the range of <math>\pm 100\%</math> (<math>\pm 10\text{ V}</math>), the fault must be sought in the hydraulics.</li> <li>• If the control signal is relatively low, the following points should be checked: <ul style="list-style-type: none"> <li>• Is the internal/external speed signal limiting the speed?</li> <li>• Which setting has been specified for the deceleration distance in relation to the POSITION?</li> </ul> </li> </ul>

<sup>13</sup> The stability criterion of the hydraulic axis must be taken into account.

FAULT	CAUSE / SOLUTION
Speed too high	<p>The drive should move to position. The drive moves in and out too fast leading to uncontrolled behavior. Reducing the speed (MAX or VELO parameter) has very little or no effect.</p> <ul style="list-style-type: none"> <li>The hydraulic system is over-sized. The entire parameterization of the movement cycle cannot be reproduced (overlap and deceleration distance settings)</li> </ul>

### 6.3 Status Information

In the monitor section of the WPC program status information is displayed about the state of inputs, outputs the controllers and the unit itself. Green lights display positive information (ready states), yellow indicates that definable monitoring ranges have been reached and red indicates that faults have been detected. Tool tip texts appear when hovering the mouse over the indicators.



READY	General operational readiness
EEPROM	data error, press SAVE to store the values
SYS_ERROR	system error
POSWIN:S	the axis is in the stationary target window
POSDWIN:D	the axis is in the dynamic target window
IN-PRESSURE	the pressure is in the target window
P-CONTROLLER	the pressure controller has taken over
INPUT PIN 6	input error of the 4... 20 mA signal
INPUT PIN 13	input error of the 4... 20 mA signal
INPUT PIN 14	input error of the 4... 20 mA signal
SSI-SENSOR	input error of the SSI interface
RCFAULT	separation of WPC when RC mode is active

## 7 EtherCAT IO interface

### 7.1 *ETHERCAT CoE*

EtherCAT is an ethernet-based field bus system, developed by Beckhoff and the EtherCAT Technology Group (ETG). EtherCAT is an open technology standardized in the international standards IEC 61158 and IEC 61784 as well as in ISO 15745-4. EtherCAT can provide the same communication mechanisms as are known from CANopen: object directory, PDO (process data objects) and SDO (service object objects). Even network management is comparable. For example, EtherCAT can be implemented on devices that were previously equipped with CANopen with minimal effort; large parts of the CANopen firmware are reusable. The objects can optionally be expanded to take account of the larger bandwidth of EtherCAT.

In order to create a user-friendly interface for device operation, different organizations have created various standards in which the following are defined:

- The device classes that exist (e.g.: class 'rotary encoder', 'analogue input module').
- The parameters that each representative of such a class has (obligatory and optional elements).
- The place where these parameters are to be found and the mechanism with which they are to be changed.

EtherCAT follows the so called CoE standard here: Can-Application-protocol-over-EtherCAT.

The process data objects (PDO) are used for the fast and efficient exchange of real-time data (for example I / O data, setpoints or actual values). In the EtherCAT telegram, no objects are addressed but the contents of the process data are sent directly from previously mapped parameters.

### 7.2 *EtherCAT installation*

EtherCAT supports almost any topology, Line, tree or star. The bus or line structure known from the fieldbuses thus also becomes available for Ethernet. Particularly useful for system wiring is the combination of line and junctions or stubs. The required interfaces exist on the couplers; no additional switches are required. Naturally, the classic switch-based Ethernet star topology can also be used.

The permissible cable length between two EtherCAT devices must not exceed 100 meters. This results from the FastEthernet technology, which mainly for reasons of signal attenuation over the Line length allows a maximum link length of 5 + 90 + 5 m if lines with appropriate properties.

To connect EtherCAT devices, use only Ethernet (cable + plug) connections at least of category 5 (CAT5) according to EN 50173 or ISO / IEC 11801. EtherCAT uses four wires of the cable for signal transmission. EtherCAT uses RJ45 connectors, for example. The contact assignment is the Ethernet standard (ISO / IEC 8802-3) is compatible.

### 7.3 *EtherCAT access handling*

The input and output data of the EtherCAT slave are displayed as CANopen Process Data Objects (PDO). The process data (PDOs) cyclically transmitted by an EtherCAT slave are the user data. They are expected or sent to the slave in the application. For this purpose, the EtherCAT Master (Beckhoff TwinCAT) parameterizes each EtherCAT slave during the start-up phase. It specifies the process data (size in bits / bytes, source location, transmission type) from or to the slave would like.

With so-called "intelligent" EtherCAT devices, the process data information is also available in the CoE directory. However, any changes in this CoE directory which lead to deviating PDO settings prevent the slave from booting successfully. It is not recommended to configure other than the intended process data, since the device firmware (if available) is tuned to these PDO combinations.

Object list:

- Index            objectindex PDO
- Subindex       subindex PDO
- Name            surname of PDO
- Flag RW        read or write status of PDO
- Flag RO        read only status of PDO, it is not possible to write data to the object
- Flag P         an additional P characterizes the object as a process data object
- Value          value of the object

## **7.4    EtherCAT device profiles (ESI)**

The 'ESI file (CoE directory) is provided by the manufacturer of an EtherCAT device.

It is create in the description language XML and has a standardized format for the description of devices.

The ESI file contains information about:

- Description of the file (name, version, creation date, etc.)
- General device information (manufacturer name and code)
- Device name and type, versions
- Description of the supported objects by their attributes

### **Localization in the EtherCAT Slave:**

The CoE directory as a parameter system must be administrated in the device in the firmware (FW) in the local controller. This is the so-called online directory, because it is only available to the user if the EtherCAT slave is in operation with operating voltage supplied and, if applicable, can be manipulated via EtherCAT communication. So that the parameters can be viewed and changed in advance without the presence of a slave, a default copy of the entire directory is usually stored in the device description file ESI (XML). This is called the offline directory. Changes in this directory do not affect the later operation of the slave with Twin-CAT.

The ESI description also defines the process image, the communication type between master and slave/device and the device functions, if applicable. The physical device (firmware, if available) has to support the communication queries/settings of the master. This is backward compatible, i.e. newer devices (higher revision) should be supported if the EtherCAT master addresses them as an older revision.

The ranges in the Slave CoE that are important for the application-oriented EtherCAT fieldbus user are

- 0x1000: This is where fixed identity information for the device is stored, including name, manufacturer, serial number etc., plus information about the current and available process data configurations.
- 0x8000: This is where the operational and functional parameters for all channels are stored, such as filter settings or output frequency. The following ranges are also of interest
- 0x4000: In some EtherCAT devices the channel parameters are stored here (as an alternative to the 0x8000 range).
- 0x6000: Input PDOs ("input" from the perspective of the EtherCAT master)
- 0x7000: Output PDOs ("output" from the perspective of the EtherCAT master)

This device series uses a universal gateway in which all data is transferred to the input PDO and output PDO area. The parameterization of individual parameters can also be done via this. This keeps the interfaces compatible with other fieldbus topologies.

## 7.5 Standard Objects

Index Subi.	Name	Description	Type	Flags	Default
1000	Device Type	Device type of the EtherCAT slave	UINT32	RO	0x00000000
1008	Manufacturer Device Name	Device name of the EtherCAT slave	STRING	RO	UHC-126-U-ETC
1009	Hardware version	Hardware version of the EtherCAT slave	UINT16	RO	0x0014
100A	Software version	Software version of the EtherCAT slave	UINT16	RO	0x001e
1018:0	Identity	Information to identify the slave	UINT8	RO	0x04
1018:1	Vendor ID	Manufacturer ID of the EtherCAT slave	UINT32	RO	0x000005ae
1018:2	Product code	Product code of the EtherCAT slave	UINT32	RO	0x00000020
1018:3	Revision number	Revision number of the EtherCAT slave	UINT32	RO	0x00000001
1019:4	Serial number	Serial number of the EtherCAT slave	UINT32	RO	0x00000000



## 8 ProfiNet IO RT interface

### 8.1 PROFINET IO function

*PROFINET is the standard* for industrial ethernet based on IEEE 802.xx. PROFINET is based on the 100 Mb/s-version of full-duplex and switched Ethernet. PROFINET IO is designed for the fast data exchange between Ethernet-based controllers (master functionality) and field devices (slave functionality) with cycle times up to 8 ms.

### 8.2 ProfiNet Installationguide

The ProfiNet IO field devices are connected exclusively via switches as network components. A ProfiNet IO network can be set up in star, tree, line or ring topology. ProfiNet IO is based on the Fast Ethernet standard transmission with 100 Mbit / s. The transmission media are copper cables CAT5.

For the IP20 environment in the control cabinet, the RJ45 connector CAT5 according to EN 50173 or ISO / IEC 11801 is used. The pin assignment is compatible with the Ethernet standard (ISO / IEC 8802-3).

The connection between ProfiNet participants is called ProfiNet Channel. In most cases, ProfiNet channels are built with copper cables to IEC 61784-5-3 and IEC 24702. The maximum length of a ProfiNet channel, which is constructed with copper cables, is 100 m.

### 8.3 PROFINET address assignment

All PROFINET IO slave devices need name and IP address to initiate communication.

Both are assigned to the device by the ProfiNet-IO-controller (PLC). The device name of the PROFINET IO device is stored in persistent memory in the device. It can be modified by a Profinet IO supervisor, e.g. the programming system of the belonging PLC.

Default address:

IP Address:	0.0.0.0
Subnet-Mask:	0.0.0.0
IP Address Gateway:	0.0.0.0

Address Example.:

IP Address:	192.168.1.111
Subnet-Mask:	255.255.255.0
IP Address Gateway:	192.168.1.111

### 8.4 Device data file (GSDML)

The characteristics of an IO device are described by the device manufacturer in a General Station Description (GSD) file. The language used for this purpose is the GSDML (GSD Markup Language) - an XML based language. For I/O data, the GSDML file describes the structure of the cyclic input and output data transferred between the Programmable Controller and the PROFINET IO device. Any mismatch between the size or structure of the input and output data and the actual internal device structure generates an alarm to the controller.

In the configuration of transmission data select 32 bytes for input and 32 bytes for output.

## 9 Profibus Interface

### 9.1 Profibus function

The Profibus module supports all baud rates from 9,6 kbit/s up to 12000 kbit/s with auto detection of the baud rate. The functionality is defined in IEC 61158. The Profibus address can be programmed by a terminal program, WPC-300 or online via the Profibus. A diagnostic LED indicates the online status.

### 9.2 Installation

A typical screened Profibus plug (D-Sub 9pol with switchable termination) is mandatory. Every Profibus segment must be provided with an active bus termination at the beginning and at the end. The termination is already integrated in all common Profibus plugs and can be activated by DIL switches. The bus determination needs a 5 Volt power supply for the correct function, which is supplied at PIN 6 of the D-sub-socket. The Profibus cable has to be screened at the determined contact clips in the Profibus plug.

### 9.3 Device data file (GSD)

The Profibus-DP features are documented in a device-data-file. Structure, content and code of this file (GSD) are standardized. They allow the projecting of any DP-slaves with projecting devices of several producers.

The GSD-data are read by a PROFIBUS-Master-configuration software and the correspondent settings are given to the master.

Enclosed is also the identification number of the Profibus knot. It is necessary for a master without significant report overhead to identify the types of the connected devices.

The GSD-file is available at the address: [https://www.w-e-st.de/files/software/hms\\_1810.gsd](https://www.w-e-st.de/files/software/hms_1810.gsd)

File: **hms\_1810.gsd**

In the setting of the transfer bytes, 32 bytes (16 words consistent) are necessary as IN/OUT variables.

## 10 Process data

Positioning resolution of 1  $\mu\text{m}$  (independent from the real sensor resolution), max. 0x989680 (10.000.000) is used. The command position is limited by the parameter SYSRANGE.

The command speed is interpreted in percentage of the programmed speed or of the output signal. The value of 0x3fff corresponds with 100 % speed.

### 10.1 Input from Fieldbus

The module is control with control PDO consisting of following bytes, a 32 Byte data frame is in use.

Index Subi.-ETC	Name	Description
7000:1	Control_1	Control bits for enabling, starting and motion control of the axis.
7000:2	Control_2	Control bits to the used controllers.
7000:3	Control_3	Control bits mainly for positioning behavior (driftcomposition, fine positioning ...).
7000:3	Control_4	Parameter functions
7010:1	Position_1	Position that is approached after "START". (Resolution 1 $\mu\text{m}$ ).
7010:2	Speed_1	Specifies the maximum possible velocity of the axis. 3FFF allow 100%, if it allows the controller parameterization. The limitation also applies to manual operation. If the limit here is lower, the set hand speed is not reached.
7010:3	Position_2	Second position, which is approached after reaching the first position in the rapid creep speed, if this function is desired.
7010:4	Speed_2	This value defines the maximum speed of the axis between Position_1 and Position_2 if an intermediate position is used. 3FFF allow 100% of the parametrised value.
7010:5	Pressure	Pressure setpoint with a resolution of 0.1 bar
7030:1...10	R-Byte	not in use
7040:1	PARA- VALUE	New value of a parameter to be changed via the bus
7040:2	PARA- INDEX	Address of the parameter to be changed

No.	Byte	Function	Type	Range	Unit
1	0	Control_1	UINT8		
2	1	Control_2	UINT8		
3	2	Control_3	UINT8		
4	3	Control_4	UINT8		
5	4	Position 1 High (MSB)	UINT32	0... 10000000	0,001 mm
6	5	---			
7	6	---			
8	7	Position 1 Low (LSB)			
9	8	Velocity 1 High	UINT16	0... 0x3fff (0... 100 %)	-
10	9	Velocity 1 Low			
11	10	Position 2 High (MSB)	UINT32	0... 10000000	0,001 mm
12	11	---			
13	12	---			
14	13	Position 2 Low (LSB)			
15	14	Velocity 2 High	UINT16	0... 0x3fff (0... 100 %)	-
16	15	Velocity 2 Low			
17	16	Command pressure High	UINT16	0,1...10000	0,1 bar
18	17	Command pressure Low			
19	18				
20	19				
21	20				
22	21				
23	22				
24	23				
25	24				
26	25				
27	26	Parameter value High (MSB)	UINT32	value of a parameter to be changed via the bus	Parameter- dependent
28	27	---			
29	28	---			
30	29	Parameter value Low (LSB)			
31	30	Parameter address High	UINT16		hex
32	31	Parameter address Low			

**Description of the control byte 1**

No	Bit	Name	Description	Type	Default
1	0	DIRECT	In direct mode new command positions are taken over directly from the controller while START signal is available.	BOOL	0
2	1	FF_ENABLE	Activation of feedforward control to reduce the lag	BOOL	0
3	2	A_ENABLE	Activation acceleration feedback	BOOL	0
4	3	---		BOOL	0
5	4	HAND:B	Manual mode. The axis is driven with the preset speed (parameter with the same name). This mode can only be used when ENABLE is available and the START comand is not set.	BOOL	0
6	5	HAND:A	Manual mode, see HAND:B. Two parameters are available for this mode in order to provide different speeds for both directions	BOOL	0
7	6	START	Start signal for positioning. The actual transmitted position value is taken over and the output will be controlled relating to the parameterization.	BOOL	0
8	7	ENABLE	General activation of the axis. Malfunction monitoring and output signal get activated (in combination with the hardware enable)	BOOL	0

**Description of the control byte 2**

No	Bit	Name	Description	Type	Default
1	0	---		BOOL	0
2	1	---		BOOL	0
3	2	---		BOOL	0
4	3	MR	Aktivation of the MR controller	BOOL	0
5	4	PQ_Only	The position controller in deactivated. The maximum output (to influence the speed) is set via speed setpoint 1.	BOOL	0
6	5	PQ_Sel	Changeover between parameter set 1 (signal 0) and 2 (signal 1).	BOOL	0
7	6	PQ_Inverse	Inverts the effective direction of the pressure controller	BOOL	0
8	7	PQ_Active	Activates the pressure controller	BOOL	0

**Description of the control byte 3**

No	Bit	Name	Description	Type	Default
1	0	LIVEBIT	Starts communication and serves as watchdog	BOOL	0
2	1	---		BOOL	0
3	2	---		BOOL	0
4	3	---		BOOL	0
5	4	---		BOOL	0
6	5	DC_FREEZE	Storing of the drift compensation value as offset for the output.	BOOL	0
7	6	DC_ACTIVE	Drift compensation function (look at chapter drift compensation).	BOOL	0
8	7	F_POS	Fine positioning function (look at chapter drift compensation).	BOOL	0

**Description of the control byte 4**

No	Bit	Name	Description	Type	Default
1	0	---		BOOL	0
2	1	---		BOOL	0
3	2	---		BOOL	0
4	3	---		BOOL	0
5	4	---		BOOL	0
6	5	PARAREAD	Read out a parameter value. Reads out the value of the parameter which is determined by PARA ADDRESS and returns this value in PARA VALUE of the data sent to the fieldbus. If the address is not valid the function will return „0xffffffff“.	BOOL	0
7	6	PARAVALID	Parameter valid for programming (change low to high)	BOOL	0
8	7	PARAMODE	Activation of the parameterizing mode	BOOL	0

**Description of the LIVEBIT**

The fieldbus communication can be monitored with the Livebit functionality.

If this bit is set to "TRUE", an internal monitoring function is activated.

After a single triggering of this control bit, a permanent change of the value must take place. It is monitored cyclically that this input value is changed at least once per second by the fieldbus. After expiration of this time without data change the READY state of the module is exited. The state of the bit is continuously reported back via LIVEBIT OUT.

## 10.2 DATA sent to Fieldbus

Process data such as current position, internal position, a 32 Byte data frame is in use.

Index Subi.- ETC	Name	Description
6000:1	Status_1	The state of the module is reported via status bits. The status byte 1 contains information about the position controller.
6000:2	Status_2	The status bit field displays information about the status of the pressure regulator.
6000:3	Status_3	Bit field 3 shows general errors.
6000:4	Status_4	Livebit / parameter write flags
6010:1	Feedback_Position	The position sensor of the axis is placed on this PDO in a resolution of 1 $\mu\text{m}$ .
6010:2	Internal_Position	The position setpoint generated in the module is applied to this PDO. Resolution 1 $\mu\text{m}$ .
6010:3	Control_Error	Control deviation of the position in a resolution of 1 $\mu\text{m}$
6010:4	Differential_Pressure	Differential pressure of both pressure sensors Pressure (X1-X2) considering the cylinder area ratio
6010:5	Feedback_Pressure_X1	Actual value of the first pressure sensor X1 (resolution 0.1 bar).
6010:6	Feedback_Pressure_X2	Actual value of the second pressure sensor X2 (resolution 0.1 bar).
6020:1	Additional_Value_1	Optional value, selection by command "SELPLUS:1 x
6020:2	Additional_Value_2	Optional value, selection by command "SELPLUS:2 x
6030:1...2	R-Byte	not in use
6040:1	PARAMETER	Retrieved value of the parameter to be read

No.	Byte	Function	Type	Range	Unit
1	0	Status_1	UINT8		
2	1	Status_2	UINT8		
3	2	Status_3	UINT8		
4	3	Status_4	UINT8		
5	4	Feedback position Hi (MSB)	UINT32	0... 10000000	0,001 mm
6	5	...			
7	6	...			
8	7	Feedback position Lo (LSB)			
9	8	Internal command position Hi (MSB)	UINT32	0... 10000000	0,001 mm
10	9	...			
11	10	...			
12	11	Internal command position Lo (LSB)			
13	12	Control error Hi (MSB)	UINT32	0... 10000000	0,001 mm
14	13				
15	14	...			
16	15	Control error Lo (LSB)			
17	16	Differential pressure feedback High	UINT16	+/- 10000 0xc000... 0x3fff	0,1 bar %
18	17	Differential pressure feedback Low			
19	18	Feedback pressure X1 (MSB)	UINT16	0...10000 0... 0x3fff	0,1 bar %
20	19	Feedback pressure X1 (LSB)			
21	20	Feedback pressure X2 (MSB)	UINT16	0...10000 0... 0x3fff	0,1 bar %
22	21	Feedback pressure X2 (LSB)			
23	22	Additional output value 1 (MSB)	INT16	See Command Table in 5.7.11	
24	23	Additional output value 1 (LSB)			
25	24	Additional output value 2 (MSB)	INT16	See Command Table in 5.7.11	
26	25	Additional output value 2 (LSB)			
27	26				
28	27				
29	28	Read out parameter value Hi	UINT32		Same as parameter
30	29	...			
31	30	...			
32	31	Read out parameter value Lo			



**Description of the status byte 1:**

No	Bit	Name	Description	Type	Default
1	0	---		BOOL	0
2	1	---		BOOL	0
3	2	---		BOOL	0
4	3	---		BOOL	0
5	4	PROFIL_2	2nd speed (position) segment is active	BOOL	0
6	5	POSWIN:S	position within the target window	BOOL	0
7	6	POSWIN:D	In-Position-Window (in NC-mode, following error window)	BOOL	0
8	7	READY	System is enabled and no errors are detected	BOOL	0

**Description of the status byte 2:**

No	Bit	Name	Description	Type	Default
1	0	---		BOOL	0
2	1	---		BOOL	0
3	2	---		BOOL	0
4	3	---		BOOL	0
5	4	---		BOOL	0
6	5	---		BOOL	0
7	6	PRESSWIN	Pressure control error within the programmed boundary	BOOL	0
8	7	PQ-ACTIVE	Pressure limitation control is active, the position loop is overridden	BOOL	0

**Description of the status byte 3:**

No	Bit	Name	Description	Type	Default
1	0	-		BOOL	0
2	1	P_ERROR_2	Error at the analog pressure sensor (no 4...20 mA) <b>Attention:</b> Inverted signal, an error exists if the bit is <b>not</b> set.	BOOL	0
3	2	P_ERROR_2	Error at the analog pressure sensor (no 4...20 mA) <b>Attention:</b> Inverted signal, an error exists if the bit is <b>not</b> set.	BOOL	0
4	3	SSI_ERROR	Error at the digital position encoder (SSI) <b>Attention:</b> Inverted signal, an error exists if the bit is <b>not</b> set.	BOOL	0
5	4	X_ERROR	Error at the analog position sensor (no 4...20 mA) <b>Attention:</b> Inverted signal, an error exists if the bit is <b>not</b> set.	BOOL	0
6	5	BUFF_OVF	Data overflow in the fieldbus (signal 0) <b>Attention:</b> Inverted signal, an error exists if the bit is <b>not</b> set.	BOOL	0
7	6	CHKERROR	Check sum error in the data transmission (signal 0) <b>Attention:</b> Inverted signal, an error exists if the bit is <b>not</b> set.	BOOL	0
8	7	DERROR	EEPROM error (signal 0) <b>Attention:</b> Inverted signal, an error exists if the bit is <b>not</b> set.	BOOL	0

**Description of the status byte 4:**

No	Bit	Name	Description	Type	Default
1	0	LIVEBIT_OUT	Feedback (= LIVEBIT), monitoring of the communication	BOOL	0
2	1	---		BOOL	0
3	2	---		BOOL	0
4	3	---		BOOL	0
5	4	---		BOOL	0
6	5	---		BOOL	0
7	6	PARAM-RDY	A parameter value has been transferred correctly	BOOL	0
8	7	PARAM-ACT	The parameter mode is active	BOOL	0

## 11 Parameterization via Fieldbus

### 11.1 Procedure

Preparation:

- Power supply of the different sections has to be available.
- For safety issues the system should not be active.  
If active, the ENABLE bit in the control word has to be reset.

**Attention:** Parameterization via fieldbus can also be done having an active system. In this case it should be done very carefully because changes are directly operative.

Parameterization:

- At first the **PARA MODE** bit has to be set to enable parameterizing via ProfiNet.  
This will be reported via the **PARA ACTIVE** bit.
  - Pretend **address** and new **value** of the parameter which should be changed.
  - Setting the **PARA VALID** bit to high will transmit the data.  
The **PARA READY** bit will report a successful parameterization.
- Attention:** A missing **para ready** bit means parameterization was not done.

Storing:

- Same procedure as parameterizing standard parameters.
- Selecting **2100** as **address**, written **value** does not matter (below 60000).

Password protection:

- If a password was set this has to be entered first for enabling parameterization. Procedure is the same as when parameterizing standard parameters.
- Select **2200** as **address** and send the password (PASSFB) as **value**.
- After **PARA READY** reports success, subsequently parameterizing can be done as long as **PARA MODE** stays active. After resetting it password has to be renewed when it gets activated again.



If the password was transferred incorrect three times, the parameterization mode gets locked (reported by deactivated **PARA ACTIVE** bit). Only restarting the device enables three new attempts for enabling.



Please note that a storage of the parameterization via the Profinet is limited in the number of writing cycles. Means it should be done only when necessary.

## 11.2 Parameterlist

The following table shows the parameter which can be changed through the fieldbus and their addresses:

Parameter table			
No.	Index	Parameter	Description
1	0x2000	A:A	Acceleration direction A
2	0x2001	A:B	Acceleration direction B
3	0x2002	D:A	Deceleration direction A
4	0x2003	D:B	Deceleration direction B
5	0x2010	V0:A	Loop gain direction A
6	0x2011	V0:B	Loop gain direction B
7	0x2012	V0:A_R	Loop gain direction A (if pressure feedback is active)
8	0x2013	V0:B_R	Loop gain direction B (if pressure feedback is active)
9	0x2021	CTRL	Deceleration behavior: 1 = LIN; 2 = SQRT1, 3 = SQRT2
10	0x2022	FF:A	Speed feed forward direction A
11	0x2023	FF:B	Speed feed forward direction B
12	0x2024	PT1	PT1 filter position controller
13	0x2025	C:KPR	Gain pressure feedback
14	0x2026	C:PT1	PT1 pressure feedback
15	0x2040	F_OFFSET	Offset pressure input
16	0x2041	RA:UP	Ramp up for pressure setpoint
17	0x2042	RA:DOWN	Ramp down for pressure setpoint
18	0x2043	ARATIO	Cylinder area ratio
19	0x2050	C1:P	P- value for pressure controller, Set 1
20	0x2051	C1:I	I- value for pressure controller, Set 1
21	0x2052	C1:D	D- value for pressure controller, Set 1
22	0x2053	C1:D_T1	PT1-filter, Set 1
23	0x2054	C1:I_ACT	Activation value in %, Set 1
24	0x2055	C2:P	P-value for pressure controller, Set 2
25	0x2056	C2:I	I- value for pressure controller, Set 2
26	0x2057	C2:D	D-value for pressure controller, Set 2
27	0x2058	C2:D_T1	PT1-filter, Set 2
28	0x2059	C2:I_ACT	Activation value in %, Set 2
29	0x2070	MIN:A	Deadband compensation, direction A
30	0x2071	MIN:B	Deadband compensation, direction B
31	0x2074	TRIGGER	Response threshold for the MIN parameter
32	0x2075	OFFSET	Valve adjustment
33	0x2076	SELPLUS:1	Selection of additional signals via fieldbus:
34	0x2077	SELPLUS:2	empty = 1   E_S = 2   CS = 3   WP = 4   EP = 5   CP = 6   U = 7   VACT = 8
35	0x2100	SAVE	Save the parameter set
36	0x2200	PW	Password for parameterization

## 12 Profinet – Driver Blocks for Simatic – Controllers

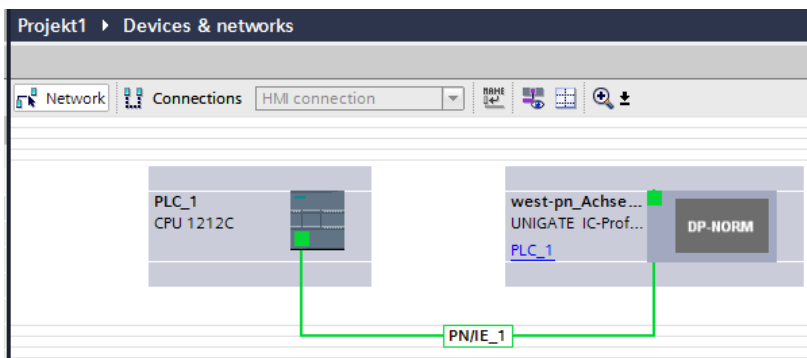
### 12.1 TIA – Portal

For use within the „TIA Portal“ software we provide two driver blocks that enable a convenient access out of the application program:

- The source WEST\_UHC126U\_PFN.scl for controllers of the S7-1200 and -1500 series
- The source WEST\_UHC126U\_PFN\_TIA\_KLASSIK.scl for controllers of the S7-300 and -400 series

Below their integration in the TIA project and the interconnections are explained.

- Import the GSDML – file
- Project the connection between PLC and controller card via Profinet:



- Assemble a module „IN/OUT 32 bytes“:

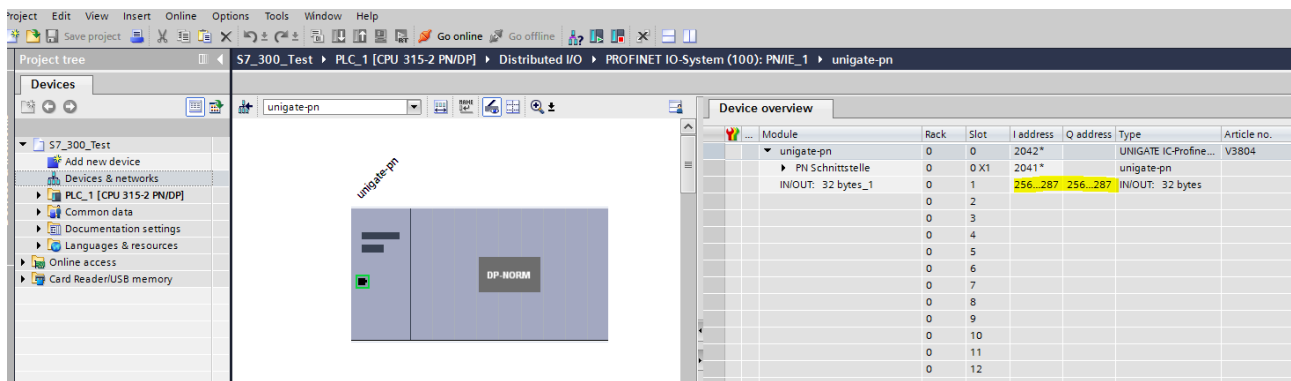
Device overview					
Module	Rack	Slot	I address	Q address	Type
west-pn_Achse_1	0	0			UNIGATE IC-Profine...
PN interface	0	0 X1			unigate-pn
IN/OUT: 32 bytes	0	1	68...99	64...95	INI/OUT: 32 bytes

The addresses will be assigned automatically. Important for the link of the program block is the hardware identifier, which is also assigned automatically. This only applies if a S7-1200 / -1500 controller is used.

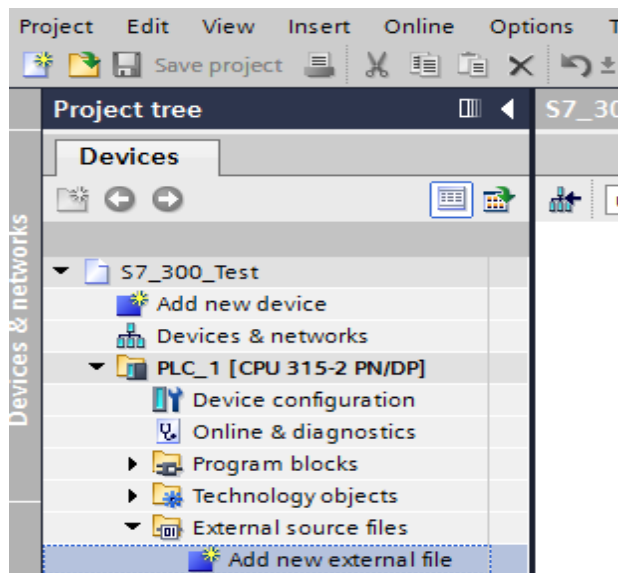
To determine the identifier right – click in the project tree on the device, choose “properties” and take over the number which is displayed in the tab “System constants”:

Name	Type	Hardware identi.	Used by	Comment
gtw-pfn-PN_Schnittstelle-Port_1	Hw_Interface	274	PLC_1	
gtw-pfn-PN_Schnittstelle-Port_2	Hw_Interface	275	PLC_1	
gtw-pfn-PN_Schnittstelle	Hw_Interface	273	PLC_1	
gtw-pfn-Proxy	Hw_SubModule	272	PLC_1	
gtw-pfn-Head	Hw_SubModule	276	PLC_1	
gtw-pfn-E_A_32_1	Hw_SubModule	277	PLC_1	

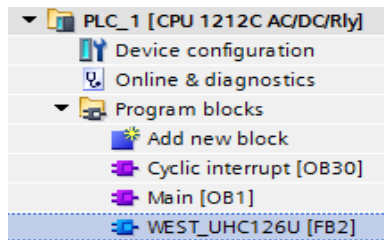
If a controller of the S7-300 and -400 series is used, the input and output addresses of the I/O – Module are the required information for the driver block, see over.



- 4.) The driver block is supplied as SCL – source. In order to assemble it into the project, the file has to be added to the TIA – Portal as “new external file”:

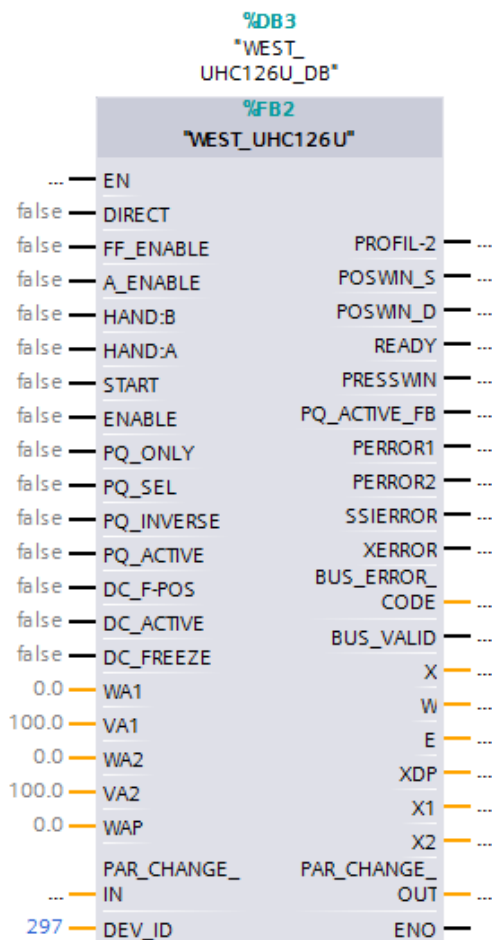


- 5.) Subsequently click on the imported file and chose "generate blocks from source". After this step the driver block can be found in the "blocks" folder. Its number may differ.

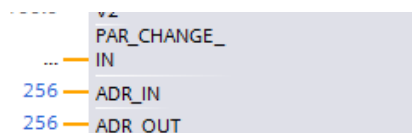


This FB can now be called out of the application program. This should happen in a cyclic interrupt with an execution time  $\geq 8$  ms.

View of the block in FUP w/o interconnection:



Address designation for S7-300 / -400 (example):



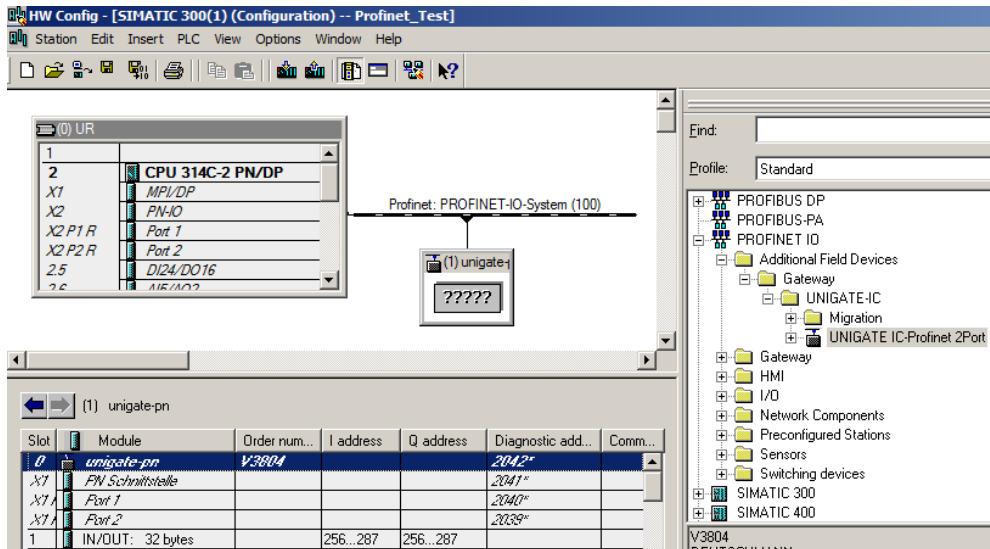
## 12.2 STEP7 – classic

If controllers of the S7-300/-400 series are used, their programming is usually done using the “Simatic Manager”.

First the GSDML – file has to be imported in the HW – configurator.

Then create a Profinet – system and choose the component „UNIGATE IC-Profinet 2Port“ from the catalogue folder “PROFINET IO / Additional Field Devices” and add it to the Profinet-IO-System.

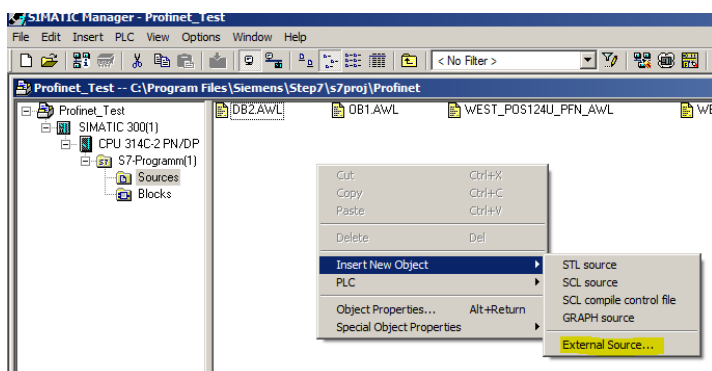
Then you can open up the device in the right window and take the element „IN/OUT: 32 bytes“ from the “bidi-rectional” subfolder and place it in the slot 1 of the device (window left / bottom).



The system will automatically assign addresses (I address / Q address).

These may be altered if required. The start addresses of both ranges need to be kept in mind because they have to be entered as fix input parameters for the driver block.

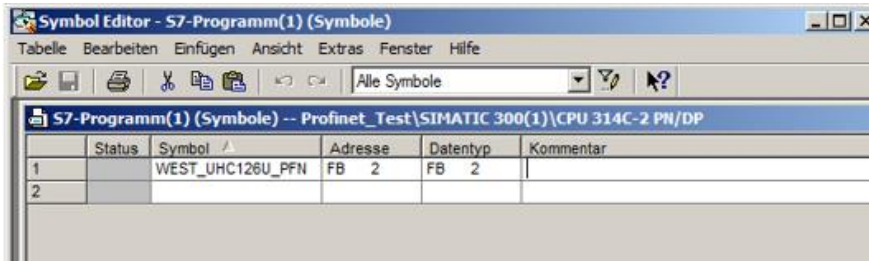
As driver we supply a STL source (\*.awl) which can be imported into the “Sources” folder:



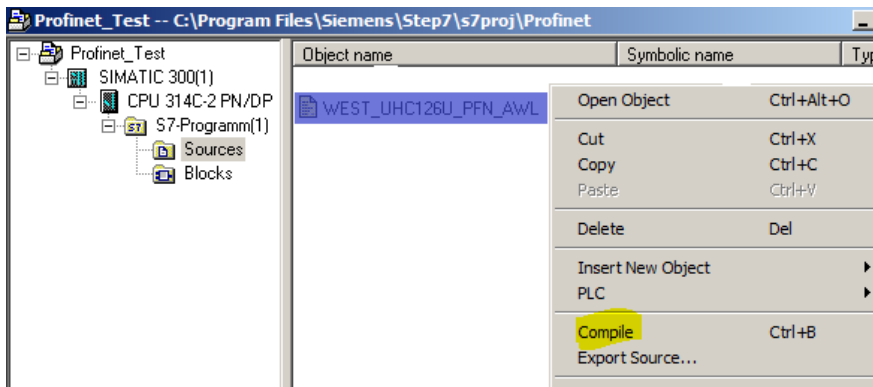


The source contains a symbolic name for the blocks which corresponds to the file name, here it is „WEST\_POS124U\_PFN“.

Prior to compiling them, a free block number has to be allotted to the name in the Symbol Editor:

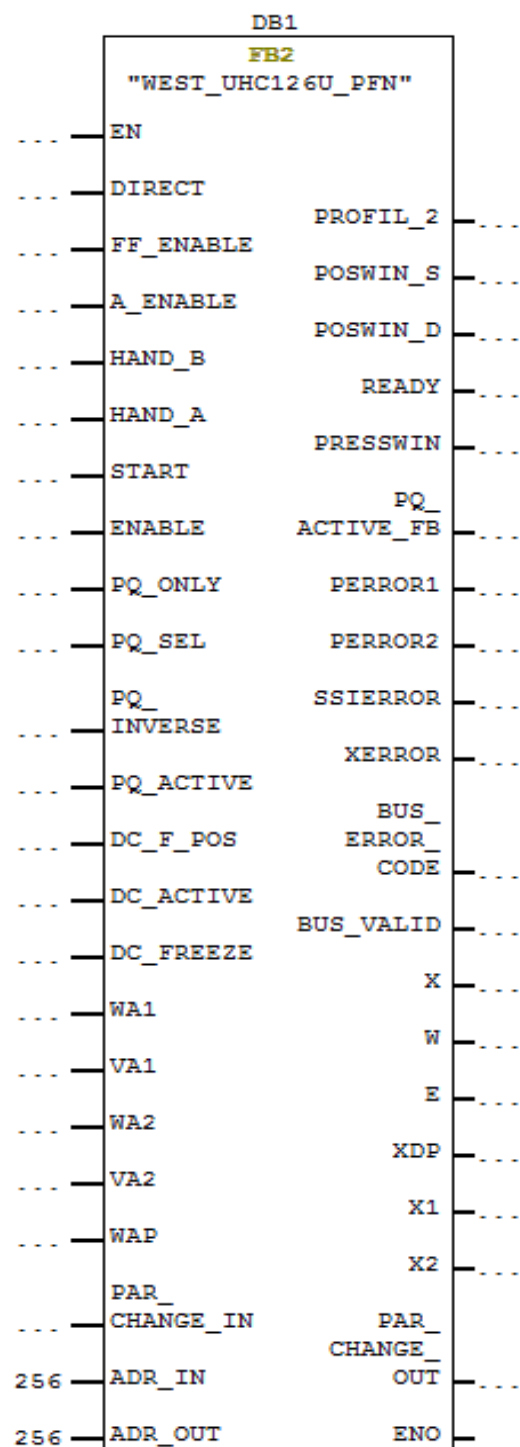


After saving the symbol list, the FB can be created by right button click on the source and choosing “Compile”:



The translation should terminate successfully and the block folder will then contain the new FB. This FB can now be called out of the application program. This should happen in a cyclic interrupt with an execution time  $\geq 8$  ms.

A view of the block in FUP w/o interconnection can be seen on the next page.



## 12.3 Common Properties

The connectors of the driver block correspond as far as possible to the description in the previous chapter. The following differences have to be considered:

- Transduction of setpoint positions in the number format "real" and unit [mm]
- Transduction of the speed setpoint in the number format "real" and [%] related to the parametrised value.
- Transduction of the setpoint pressure in the number format "real" and unit [bar]
- The Signals allowing to change parameters are bundled in structures (usage is optional).
- As parameter „DEV\_ID“ the Hardware Identifier of the IO Module has to be entered (TIA)
- As parameters ADR\_IN / ADR\_OUT the starting addresses (see HW config.) have to be entered (Step 7 classic).
- The values „PERROR1/2“, SSIERROR, XERROR are not inverted, which mean "TRUE" indicates the presence of an error.
- The bit "BUS\_VALID" signals the operation of the bus data transfer.
- If needed, the output „BUS\_ERROR\_CODR“ yields detailed diagnostic information:

BUS ERROR CODE		
Nr.	Bit	Funktion
1	0	Internal data error (DERROR)
2	1	Checksum error ProfiNet (CHKERROR)
3	2	Data overflow error ProfiNet (BUFFEROV)
4	3	Receiving error (access to the input addresses, module -> PLC)
5	4	Transmitting error (access to the output addresses, PLC -> module)
6	5	No data exchange (Watchdog)
7	6	
8	7	

- Feedback of the actual positions and internal setpoints in the number format "real" and unit [mm]
- Feedback of the pressures in the format "real" and unit [bar]

If the bus data exchange is faulty, the fed back values are not reliable. In most cases they will be frozen in that case. If the output values are processed and used to control further functions, the valid bit has also to be considered. In case of a bus failure adequate fall-back values have to be used so that the complete system is kept in a safe state.

## 13 Notes