



**Documentation of the PROFIBUS Interface of the following
Controllers:**

E1130-DP and E1130-DP-HC



PROFIBUS Interface 3.6

Usermanual

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1. System overview

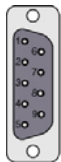
The LinMot PROFIBUS controllers E1130-DP are PROFIBUS-DP slaves.
Further information on PROFIBUS can be found under: <http://www.profibus.com>

All baud rates are supported and automatically detected.

2. Connecting to the PROFIBUS

Pinout of the DP Connector X9:

The PROFIBUS connector is a standard DSB9 9 female with the following pin assignment:



| | | | |
|-------|---------------|-------|--------------------------------|
| Pin 1 | not connected | Pin 6 | VP (+5VDC for bus termination) |
| Pin 2 | not connected | Pin 7 | not connected |
| Pin 3 | B | Pin 8 | A |
| Pin 4 | CNTR-P | Pin 9 | not connected |
| Pin 5 | GND | | |

3. PROFIBUS Parameters

The PROFIBUS Servo Controllers have an additional parameter tree branch, which can be configured with the distributed LinMot Talk 1100 software. With these parameters, the PROFIBUS behaviour can be configured. The software LinMot Talk 1100 can be downloaded from <http://www.linmot.com> under the section download, software & manuals.

Dis-/Enable

With the Dis-/Enable parameter the LinMot servo controller can be run without the PROFIBUS going online. So in first step the system can be configured and run without any bus connection.

PROFIBUS Interface\ Dis-/Enable

| | |
|---------|--|
| Disable | Servo controller runs without PROFIBUS. |
| Enable | Servo controller runs only with a PROFIBUS connection. |



IMPORTANT: To activate the PROFIBUS Interface, the Dip-Switch S3.4 "Interface" at the bottom of the drive has to be set to "ON"

S3

ON – OFF
Interface
CAN Term
RS485 Term
RS485/232



S3

Node Address

This directory contains the parameters defining the node address.

Node Address Selection

The node address parameter defines the source of the node address.

PROFIBUS Interface\ Node Address\ Node Address Selection

| | |
|-----------------|--|
| By Hex Switches | The node address is determined by the two Hex Switches S1 and S2 |
| By Parameter | The node address is determined by parameter setting |

On default the Node Address is set by the rotary switches S1 and S2.



IMPORTANT: The rotary switches are hexadecimal

Node Address Parameter Value

Defines the node address when "By Parameter" is selected.

Byte Order

Defines the used byte order.

PROFIBUS Interface\ Byte/Word Order\Byte Order

| | |
|--------------|---|
| Reversed | Byte order is reversed. For S7 PLC's select reversed. |
| Not reversed | Byte order is not reversed. |

Word Order

Defines the used word order.

PROFIBUS Interface\ Byte/Word Order\Word Order

| | |
|--------------|---|
| Reversed | Word order is reversed. For S7 PLC's select reversed. |
| Not reversed | Word order is not reversed. |

MC CMD Intf Par Order

Defines the used parameter word order.

PROFIBUS Interface\ Byte/Word Order\MC CMD Intf Par Order

| | |
|--------------|--|
| Reversed | Order is reversed. CMD Header - Par word 1 - Par word 0 - Par word 3 - Par word 2 - etc... |
| Not reversed | Order is not reversed. CMD Header - Par word 0 - Par word 1 - Par word 2 - Par word 3 - etc... |

Diagnose Priority

Defines the behaviour of the diagnostic telegram.

PROFIBUS Interface\ Diagnose Priority

| | |
|------|---|
| None | Only minimal diagnostic data is transmitted. |
| Low | The diagnostic data is sent as status information only. |
| High | The diagnostic data is sent high priority in the error state. |

Monitoring Channels

Defines the source variable by UPID of the four monitoring channels.

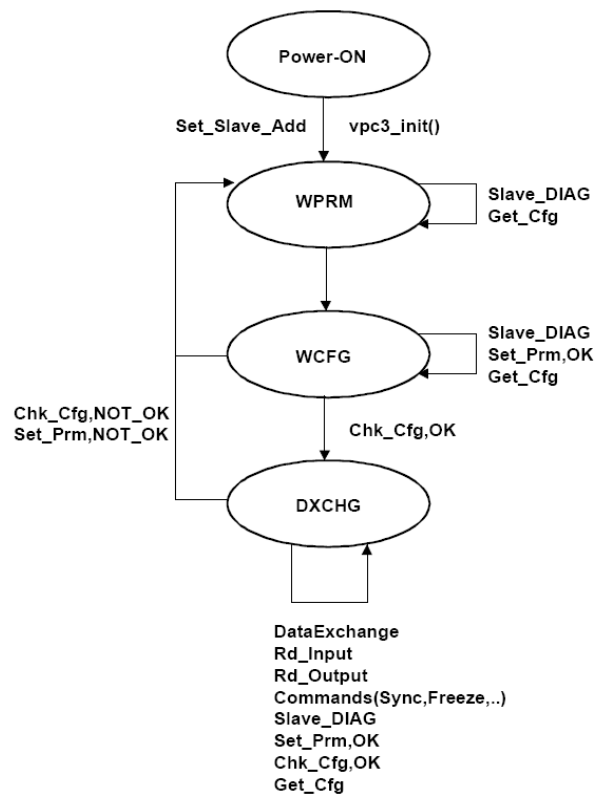
PROFIBUS Interface\ Monitoring Channels

| | |
|----------------|---------------------------------|
| Channel 1 UPID | Source for Monitoring Channel 1 |
| Channel 2 UPID | Source for Monitoring Channel 2 |
| Channel 3 UPID | Source for Monitoring Channel 3 |
| Channel 4 UPID | Source for Monitoring Channel 4 |

4. PROFIBUS Variables

In the Variables directory of LinMot Talk there is a section \PROFIBUS which contains some information of the actual state of the PROFIBUS interface:

- **Node Address:** This shows the used node address, which can be either configured by the two rotary hex-switches S1/S2 or by parameter settings, as a decimal number.
- **Baud Rate:** The baud rate is auto detect. This shows the baud rate, which was found on the bus. Zero means no baud rate found.
- **Bus Cycle Time:** This shows the actual cycle time in us.
- **DP State:** This shows the actual state of the LinMot internal DP-State machine:
 - (0) Initialise: The firmware is initialising the PROFIBUS Interface
 - (1) Searching Baudrate: The detection of the baud rate is in progress.
 - (2) Wait for Parameter Telegram: No valid parameter telegram was yet received.
 - (3) Wait for Configuration Telegram: No valid configuration telegram was yet received.
 - (4) Ready for DataExchange: The PROFIBUS is ready for DataExchange, but the master has not done the transition.
 - (5) DataExchange: The PROFIBUS is running and exchanging cyclic data with the master.



5. PROFIBUS Modules

The LinMot Controller is a PROFIBUS-DP slave. To configure it with a PROFIBUS master, the GSD file is used. You can find the GSD file LINM092D.GSD in the LinMot-Talk1100 installation directory (typically C:\Program Files\LinMot\LinTalk1100 3.x\Firmware\Profibus\GSD).

There are the following modules defined, to be configured according the demands of the desired application:

Control/Status [1 Word DI/DO]

This module should always be configured. It consists of the Control and Status word, which are described in the document "Usermanual Motion Control Software".

MC Cmd Interface [10 Word DO]

This maps the MC Command interface of the controller. Please refer to the documentation of the MC software.



Attention: Older Siemens S7 CPU firmware cannot directly write more than 4 byte consistent. In this case the data has to be sent by SFC15 (please refer to the corresponding Siemens documentation)

Get MC Header Echo [1 Word DI]

This echoes the Cmd Header of the MC Command interface of the controller. Please refer to the documentation of the MC software.

Get Actual Position [2 Word DI]

The actual position of the configured motor. It's a 32 Bit integer with a resolution of 0.1µm .

Get Demand Position [2 Word DI]

The demand position of the configured motor. It's a 32 Bit integer with a resolution of 0.1µm.

Get Current [1 Word DI]

The set current of the configured motor. It's a 16 Bit integer with a resolution of 1mA .

Get StateVar [1 Word DI]

Consists of MainState and SubState. Please refer to the table "State Var" on chapter 3 of the "Usermanual Motion Control Software".

The StateVar has all relevant flags and information for clean handshaking within one word and can therefore replace the modules "Get MC Header Echo" and "Get Error Code".

It's strongly recommended to use this module for handshaking.

Get WarnWord [1 Word DI]

1 Word Warnings. Please refer to chapter 9.

Get ErrorCode [1 Word DI]

1 Word ErrorCode. Please refer to chapter 8.

Monitoring Channel X [2 Word DI]

Transmits cyclic the value of the variable, which is defined by the Monitoring Channel Parameter (see chapter 3).

Parameter Channel [4 Word DI/DO]

Overview Parameter access:

| Word | DO | DI |
|------|---------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | Parameter UPID | Parameter UPID |
| 3. | Parameter Value Low | Parameter Value Low |
| 4. | Parameter Value High | Parameter Value High |

Overview Curve access:

| Word | DO | DI |
|------|-----------------------------------|-----------------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | Curve Number | Curve Number |
| 3. | Data Value Low / Info Block size | Data Value Low / Info Block size |
| 4. | Data Value High / Data Block size | Data Value High / Data Block size |

Start getting UPID List:

| Word | DO | DI |
|------|------------------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | Start UPID (search from this UPID) | - |
| 3. | - | - |
| 4. | - | - |

Get next UPID List item:

| Word | DO | DI |
|------|---------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | - | UPID found |
| 3. | - | Address Usage |
| 4. | - | - |

Address Usage:

| | | | Not used for Hash calculation | | | | Life Parameter | | | | | ROM Write | ROM Read | RAM Write | RAM Read |
|----|----|----|---|----|----|---|-------------------|---|---|---|---|-----------|----------|-----------|----------|
| 15 | 14 | 13 | 12 | 11 | 10 | 9 | 8 | 7 | 6 | 5 | 4 | 3 | 2 | 1 | 0 |

Start getting Modified UPID List:

| Word | DO | DI |
|------|------------------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | Start UPID (search from this UPID) | - |
| 3. | - | - |
| 4. | - | - |

Get next Modified UPID List item:

| Word | DO | DI |
|------|---------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | - | UPID found |
| 3. | - | Data Value Low |
| 4. | - | Data Value High |

Get Error Log Entry Counter:

| Word | DO | DI |
|------|---------------------------|---------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | - | - |
| 3. | - | Number of Logged Errors |
| 4. | - | Number of Occurred Errors |

Get Error Log Entry Error Code:

| Word | DO | DI |
|------|---------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | Entry Number (0..20) | Entry Number |
| 3. | - | Logged Error Code |
| 4. | - | - |

Get Error Log Entry Time Low:

| Word | DO | DI |
|------|---------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | Entry Number (0..20) | Entry Number |
| 3. | - | Entry Time Low Word |
| 4. | - | Entry Time Mid Low Word |

Get Error Log Entry Time High:

| Word | DO | DI |
|------|---------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | Entry Number (0..20) | Entry Number |
| 3. | - | Entry Time Mid High Word |
| 4. | - | Entry Time High Word |

The Error Log Entry Time consists of 32Bit hours (Time High) and 32Bit ms (Time Low).

Get Error Code Text Stringlet:

| Word | DO | DI |
|------|---------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | Error Code | Error code |
| 3. | Stringlet Number (0..7) | Stringlet Byte 0 and 1 |
| 4. | - | Stringlet Byte 2 and 3 |

Command Table: Save to Flash

| Word | DO | DI |
|------|---------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | - | - |
| 3. | - | - |
| 4. | - | - |

The MC software should be stopped (with command "35h: Stop MC and Application Software").
The PROFIBUS Interface will stay active while the MC software is stopped.

Command Table: Delete All Entries (RAM)

| Word | DO | DI |
|------|---------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | - | - |
| 3. | - | - |
| 4. | - | - |

Command Table: Delete Entry

| Word | DO | DI |
|------|---------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | Entry Number | Entry Number |
| 3. | - | - |
| 4. | - | - |

Command Table: Write Entry

| Word | DO | DI |
|------|-----------------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | Entry Number | Entry Number |
| 3. | Block Size (even number of bytes) | Block Size |
| 4. | - | - |

Command Table: Write Entry Data

| Word | DO | DI |
|------|---------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | Entry Number | Entry Number |
| 3. | Data | Data |
| 4. | Data | Data |

Command Table: Get Entry

| Word | DO | DI |
|------|---------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | Entry Number | Entry Number |
| 3. | - | Block Size |
| 4. | - | - |

Command Table: Get Entry Data

| Word | DO | DI |
|------|---------------------------|--------------------------|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | Entry Number | Entry Number |
| 3. | - | Data |
| 4. | - | Data |

Command Table: Get Entry List (0..7)

| Word | DO | DI |
|------|---------------------------|---|
| 1. | Parameter Channel Control | Parameter Channel Status |
| 2. | - | Offset in bytes |
| 3. | - | Bit field (Bit set= undefined / Bit cleared = used) |
| 4. | - | Bit field (Bit set= undefined / Bit cleared = used) |

Parameter Channel Control

| Parameter Command ID to Execute | | | | | | | | Command Count | | | | | | | |
|---------------------------------|----|----|----|----|----|---|---|---------------|---|---|---|---|---|---|---|
| 15 | 14 | 13 | 12 | 11 | 10 | 9 | 8 | 7 | 6 | 5 | 4 | 3 | 2 | 1 | 0 |

The header of the Motion command is split in two parts:

Parameter Command ID to Execute

- Command Count

Parameter Channel Status

| Parameter Command Status | | | | | | | | Command Count Resp. | | | | | | | |
|--------------------------|----|----|----|----|----|---|---|---------------------|---|---|---|---|---|---|---|
| 15 | 14 | 13 | 12 | 11 | 10 | 9 | 8 | 7 | 6 | 5 | 4 | 3 | 2 | 1 | 0 |

The header of the Motion command is split in two parts:

- Executed Parameter Command ID
- Command Count

Command Count

A new command is only evaluated, if the value of the command count changes. In the easiest way bit 0 could be toggled.

Parameter Command ID

This selects the command.

Possible Commands are:

| Command ID | Description |
|-------------------------------|---|
| 00h | No Operation |
| Parameter Access | |
| 10h | Read ROM Value of Parameter by UPID |
| 11h | Read RAM Value of Parameter by UPID |
| 12h | Write ROM Value of Parameter by UPID |
| 13h | Write RAM Value of Parameter by UPID |
| 14h | Write RAM and ROM Value of Parameter by UPID |
| 15h | Get minimal Value of Parameter by UPID |
| 16h | Get maximal Value of Parameter by UPID |
| 17h | Get default Value of Parameter by UPID |
| Parameter (UPID) List | |
| 20h | Start Getting UPID List |
| 21h | Get next UPID List item |
| 22h | Start Getting Modified UPID List |
| 23h | Get next Modified UPID List item |
| Stop / Start / Default | |
| 30h | Restart Controller |
| 31h | Set ROM to default (OS) |
| 32h | Set ROM to default (MC SW) |
| 33h | Set ROM to default (Interface) |
| 34h | Set ROM to default (Application) |
| 35h | Stop MC and Application Software (for Flash access) |
| 36h | Start MC and Application Software |
| Curve Service | |
| 41h | Curve Service: Delete all Curves (RAM) |
| 50h | Curve Service: Add Curve |
| 51h | Curve Service: Add Curve Info Block |
| 52h | Curve Service: Add Curve Data |
| 53h | Curve Service: Modify Curve |
| 54h | Curve Service: Modify Curve Info Block |
| 55h | Curve Service: Modify Curve Data |
| 60h | Curve Service: Get Curve |
| 61h | Curve Service: Get Curve Info Block |
| 62h | Curve Service: Get Curve Data |
| Error Log | |

| | |
|----------------------|--|
| 70h | Get Error Log Entry Counter |
| 71h | Get Error Log Entry Error Code |
| 72h | Get Error Log Entry Time low |
| 73h | Get Error Log Entry Time high |
| 74h | Get Error Code Text Stringlet |
| Command Table | |
| 80h | Command Table: Save to Flash |
| 81h | Command Table: Delete all Entries (RAM) |
| 82h | Command Table: Delete Entry (Entry Number) |
| 83h | Command Table: Write Entry |
| 84h | Command Table: Write Entry Data |
| 85h | Command Table: Get Entry (Entry Number) |
| 86h | Command Table: Get Entry Data |
| 87h | Command Table: Get Entry List (Entry 0..31) |
| 88h | Command Table: Get Entry List (Entry 32..63) |
| 89h | Command Table: Get Entry List (Entry 64..95) |
| 8Ah | Command Table: Get Entry List (Entry 96..127) |
| 8Bh | Command Table: Get Entry List (Entry 128..159) |
| 8Ch | Command Table: Get Entry List (Entry 160..191) |
| 8Dh | Command Table: Get Entry List (Entry 192..223) |
| 8Eh | Command Table: Get Entry List (Entry 224..255) |

| Parameter Status | Description |
|------------------|--|
| 00h | OK, done |
| 02h | Command Running / Busy |
| 04h | OK, but there has more data to be sent |
| 05h | Busy |
| | |
| C0h | UPID Error |
| C1h | Parameter Type Error |
| C2h | Range Error |
| C3h | Address Usage Error |
| C5h | Error: "Get next UPID List item" was executed without prior execution of "Start getting UPID List" |
| C6h | End of UPID List reached (no next UPID List item found) |
| | |
| D0h | Odd Address |
| D1h | Size Error (Curve Service) |
| D4h | Curve already defined / Curve not present (Curve Service) |
| | |
| | |



Further documentation on how to configure a controller by fieldbus and handle curves can be found on the additional manual "Parameterization of LinMot E1100 Servo Controllers over Fieldbus Interfaces".



With STEP7 from Siemens the module "Universal Module" must never be configured.

6. State Machine

Please refer to "Usermanual Motion Control Software"

7. PROFIBUS Diagnosis

The LinMot controller supports 12 byte of diagnostic data. The diagnosis telegram is according the following table:

| Byte | Description |
|--------|--|
| 0..5 | Data according PROFIBUS-DP standard |
| 6..7 | Extended Diagnosis Header and stuffing |
| 8..9 | Warn Word (see chapter 9 for description) |
| 10..11 | Error Code (see chapter 8 for description) |

8. Error Codes

Please refer to "Usermanual Motion Control Software" for the Error Codes of the MC Software. The PROFIBUS Interface has the following additional Error Codes:

| Error Code Hexadecimal | Error Description |
|---------------------------|---------------------------------------|
| \$C1 | Fatal Error: Controller not supported |
| \$C2 | Config Error: Invalid MACID |
| \$C3 | DP Err: Connection lost |

9. Warn Word

Please refer to "Usermanual Motion Control Software"

10. Example for Siemens Simatic S7

The following example shows the homing procedure and execution of a motion command together with S7 and Simatic from Siemens:

Bus configuration (HW Konfig):

| Steckplatz | DP-Kennung | Bestellnummer / Bezeichnung | E-Adresse | A-Adresse |
|------------|------------|---------------------------------|-----------|-----------|
| 1 | 193 | Control/Status [1 Word DI/DO] | 10...11 | 10...11 |
| 2 | 129 | MC Cmd Interface [10 Word DO] | | 20...39 |
| 3 | 65 | Get StateVar [1 Word DI] | 20...21 | |
| 4 | 65 | Get Actual Position [2 Word DI] | 22...25 | |
| 5 | 65 | Get Current [1 Word DI] | 26...27 | |
| 6 | | | | |
| 7 | | | | |
| 8 | | | | |
| 9 | | | | |
| 10 | | | | |
| 11 | | | | |
| 12 | | | | |
| 13 | | | | |
| 14 | | | | |

Homing (Control Word = 0x083Fh):

| | Operand | Symbol | Anze | Statuswert | Steuerwert |
|---|---------|--------|------|------------|------------|
| 1 | EW 10 | | HEX | W#16#4C37 | |
| 2 | AW 10 | | HEX | W#16#083F | W#16#083F |

Enter Operational State (Control Word = 0x003Fh):

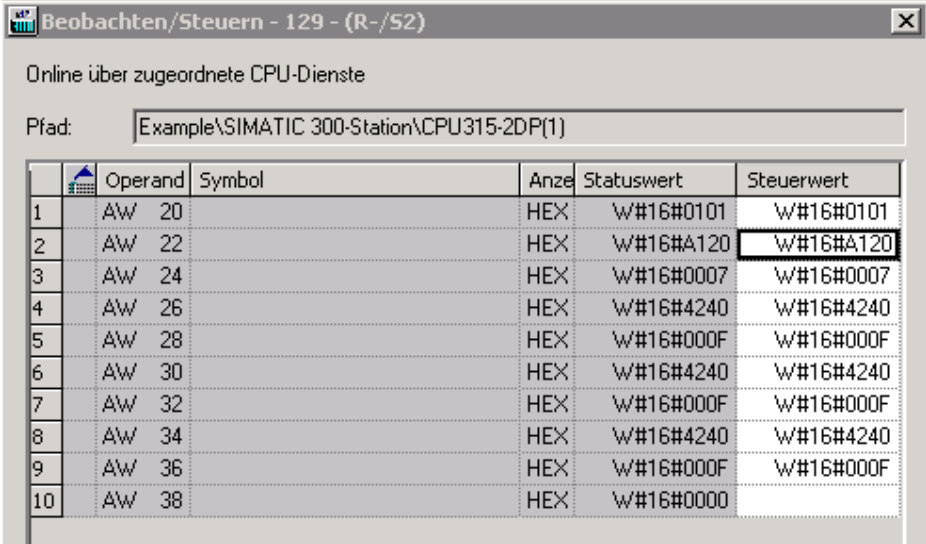
| | Operand | Symbol | Anze | Statuswert | Steuerwert |
|---|---------|--------|------|------------|------------|
| 1 | EW 10 | | HEX | W#16#4C37 | |
| 2 | AW 10 | | HEX | W#16#003F | W#16#003F |

PROFIBUS Interface

Execute Motion Command: VAl goto Position (010xh)

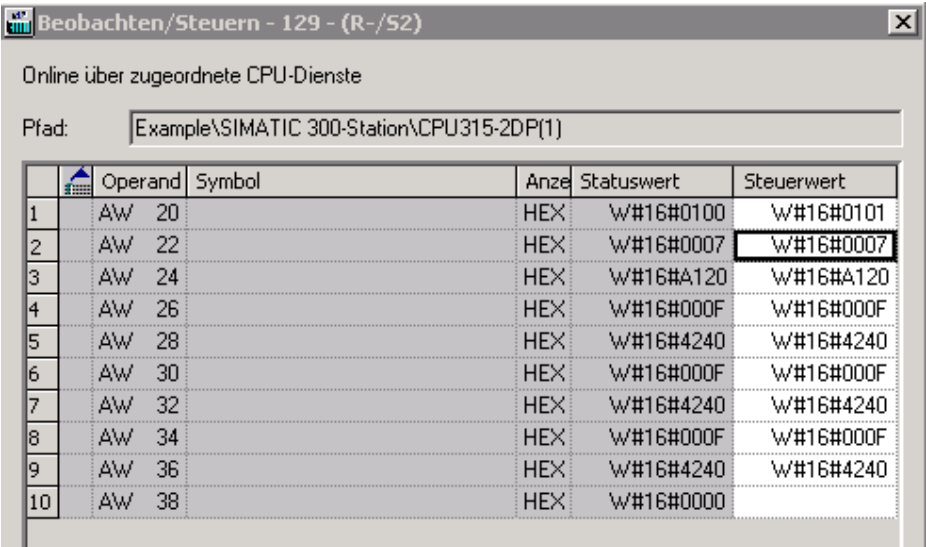
| | | |
|-------------------|---------|-----------|
| Target Position: | 50mm | 0007A120h |
| Maximal Velocity: | 1m/s | 000F4240h |
| Acceleration: | 10m/s^2 | 000F4240h |
| Deceleration: | 10m/s^2 | 000F4240h |

In the case of \Parameters\PROFIBUS Interface\Byte/Word Order\MC CMD Intf Par Order\not reversed (default setting):



| Online über zugeordnete CPU-Dienste | | | | | |
|---|---------|--------|------|------------|------------|
| Pfad: Example\SIMATIC 300-Station\CPU315-2DP(1) | | | | | |
| | Operand | Symbol | Anze | Statuswert | Steuerwert |
| 1 | Aw 20 | | HEX | W#16#0101 | W#16#0101 |
| 2 | Aw 22 | | HEX | W#16#A120 | W#16#A120 |
| 3 | Aw 24 | | HEX | W#16#0007 | W#16#0007 |
| 4 | Aw 26 | | HEX | W#16#4240 | W#16#4240 |
| 5 | Aw 28 | | HEX | W#16#000F | W#16#000F |
| 6 | Aw 30 | | HEX | W#16#4240 | W#16#4240 |
| 7 | Aw 32 | | HEX | W#16#000F | W#16#000F |
| 8 | Aw 34 | | HEX | W#16#4240 | W#16#4240 |
| 9 | Aw 36 | | HEX | W#16#000F | W#16#000F |
| 10 | Aw 38 | | HEX | W#16#0000 | |

In the case of \Parameters\PROFIBUS Interface\Byte/Word Order\MC CMD Intf Par Order\not reversed:



| Online über zugeordnete CPU-Dienste | | | | | |
|---|---------|--------|------|------------|------------|
| Pfad: Example\SIMATIC 300-Station\CPU315-2DP(1) | | | | | |
| | Operand | Symbol | Anze | Statuswert | Steuerwert |
| 1 | Aw 20 | | HEX | W#16#0100 | W#16#0101 |
| 2 | Aw 22 | | HEX | W#16#0007 | W#16#0007 |
| 3 | Aw 24 | | HEX | W#16#A120 | W#16#A120 |
| 4 | Aw 26 | | HEX | W#16#000F | W#16#000F |
| 5 | Aw 28 | | HEX | W#16#4240 | W#16#4240 |
| 6 | Aw 30 | | HEX | W#16#000F | W#16#000F |
| 7 | Aw 32 | | HEX | W#16#4240 | W#16#4240 |
| 8 | Aw 34 | | HEX | W#16#000F | W#16#000F |
| 9 | Aw 36 | | HEX | W#16#4240 | W#16#4240 |
| 10 | Aw 38 | | HEX | W#16#0000 | |

As it appears with LinMot-Talk1100 after "Read Command" in the Control Panel:

Motion Command Interface

Enable Manual Override: ☐

-10 mm

-1 mm

+1 mm

+10 mm

Command Category: Most Commonly Used ▼

Command Type: VAI Go To Pos (010xh) ▼

Count Nibble (Toggle Bits): 1h ▼ ☐ Auto Increment Count Nibble

| Name | Offs. | Description | Scaled Value | Int. Value (Dec) | Int. Value (Hex) |
|--------|-------|----------------------|---------------------|------------------|------------------|
| Header | 0 | 010xh: VAI Go To Pos | 257 | 257 | 0101h |
| 1. Par | 2 | Target Position | 50 mm | 500000 | 0007A120h |
| 2. Par | 6 | Maximal Velocity | 1 m/s | 1000000 | 000F4240h |
| 3. Par | 10 | Acceleration | 10 m/s ² | 1000000 | 000F4240h |
| 4. Par | 14 | Deceleration | 10 m/s ² | 1000000 | 000F4240h |

Read Command

Send Command

11. Troubleshooting

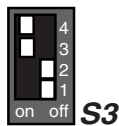
If the PROFIBUS connection is not working, proceed as followed:

- Is the correct firmware installed on the controller? When installing the firmware the PROFIBUS interface must be selected. The actual firmware and configuration software can always be downloaded from <http://www.linmot.com>
- Is the node address correct (attention, the rotary switches are hexadecimal)? The correct setting can be verified with LinMot Talk 1100 in the variables section under \PROFIBUS\Node Address
- The interface switch S3.4 must be ON

S3

ON – OFF

Interface
CAN Term
RS485 Term
RS485/232



- When using a S7 PLC from Siemens, the “universal module” should never be configured.
- Check if the correct GSD file is used (LINM092D.GSD, which is provided together with LinMot Talk 1100 in the subdirectory. \firmware\PROFIBUS\GSD). Attention the Controller Series E430-DP and E4030-DP have a different and incompatible GSD file.
- Check bus cabling and termination.