Lexium 32M – Profibus/Profinet Example TIA / S7-1200/1500

S7-1200

S7-1500

Profibus/
Profinet

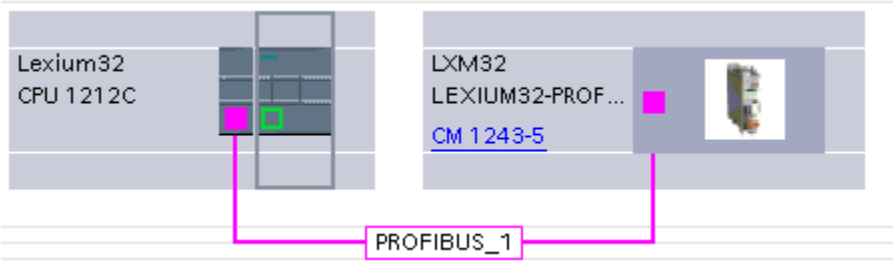
LXM32M

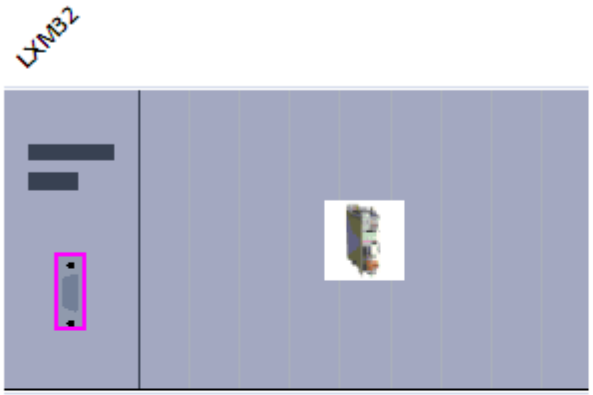
V1.009

LXM32M – S7-1200/1500

Hardware – Configuration (Profibus)

GSD file for Lexium32M: “SE120B9D.GSD”





LXM32M uses 26 Bytes Input data and 26 bytes Output data.

Drive Profile Lexium 1

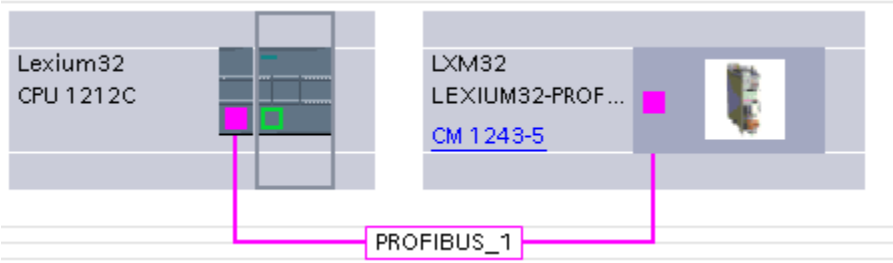
Device overview

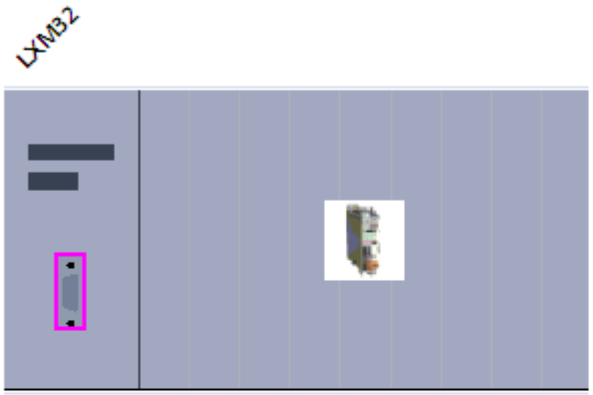
...	Module	Rack	Slot	I address	Q address	Type
	LXM32	0	0			LEXIUM32-PROFIBUS-DPV1 FW V01.10
	Drive Profile Lexium 1_1	0	Processdata-Interface	1...26	1...26	Drive Profile Lexium 1
	Empty module_1	0	Optional IO Module			Empty module

LXM32M – S7-1200/1500

Hardware – Configuration (Profinet)

GSD file for Lexium32M: “SE120B9D.GSD”





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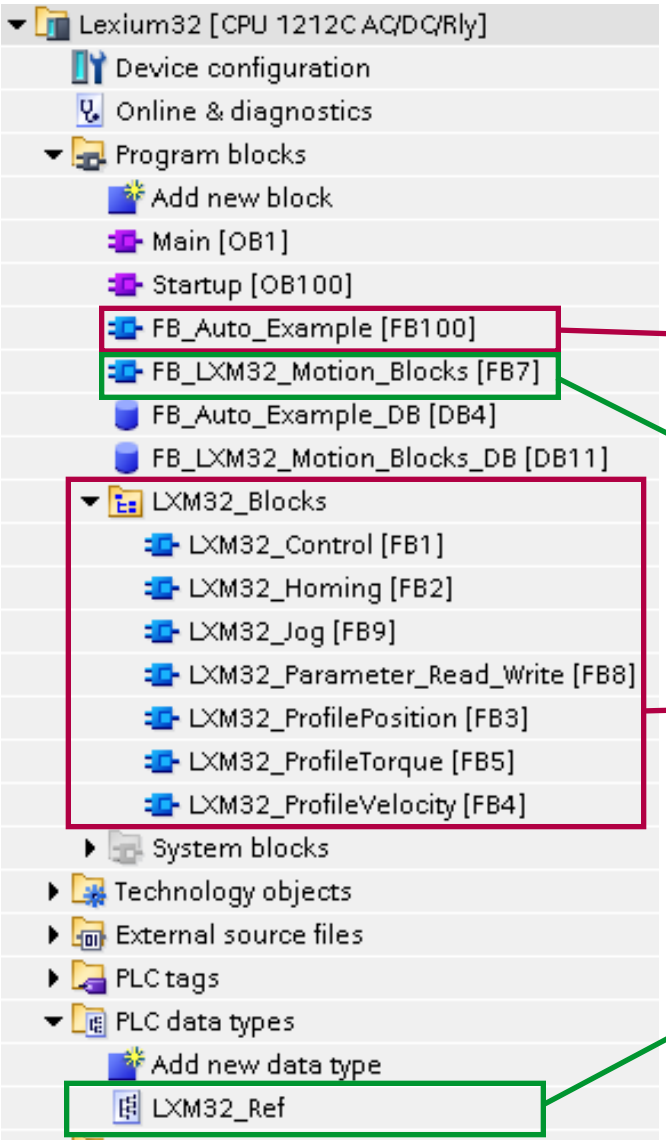
LXM32M – S7-1200/1500

Overview



Example sequence

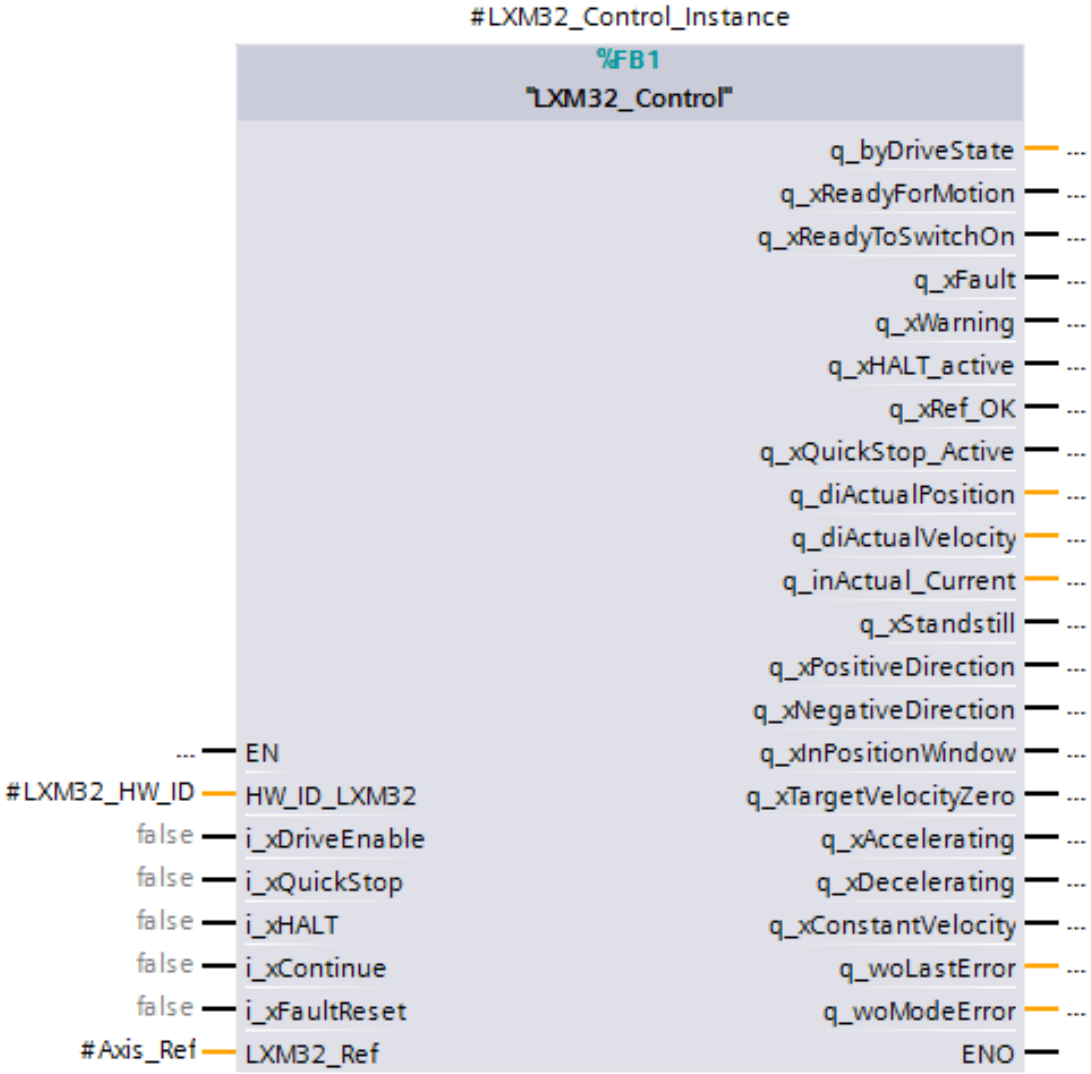
Example for calling the LXM32 motion function blocks

Function blocks to control the LXM32 drive

All function blocks need a common Axis reference data structure (LXM32_Ref) for each axis.
This structure could be created in a global data block or in the static variables of a FB.

LXM32M – S7-1200/1500

Function block - LXM32_Control



LXM32M – S7-1200/1500

LXM32_Control Interface

LXM32_Control

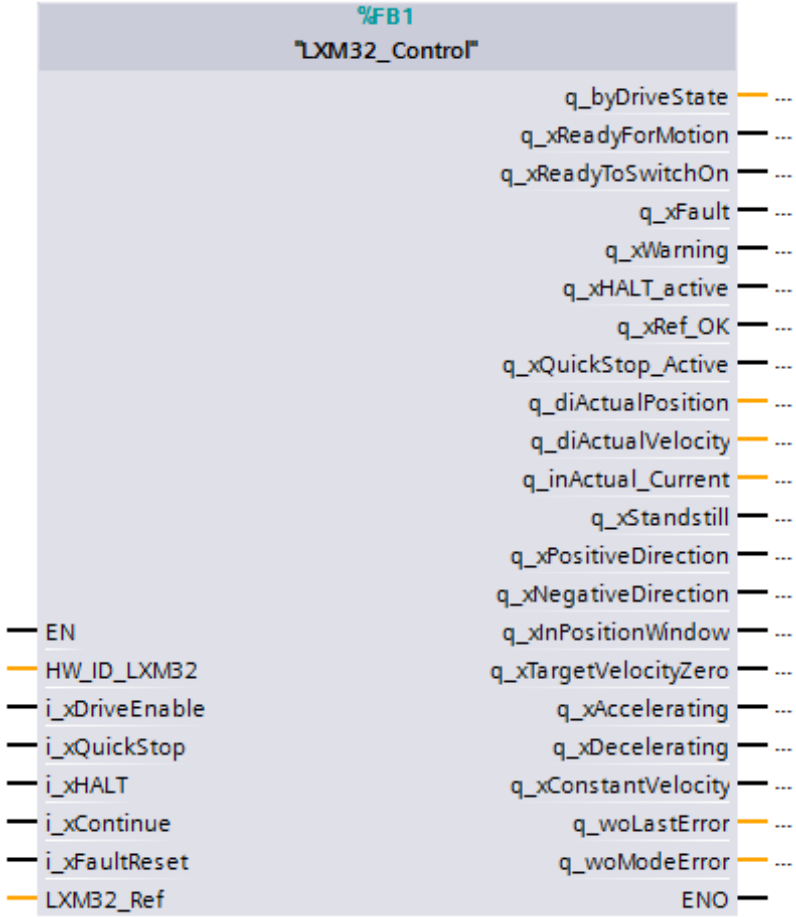
	Name	Datentyp	Defaultwert	Remanenz	Erreichbar a..	Sichtbar i...	Einstellwert	Kommentar
1	Input							
2	HW_ID_LXM32	HW_IO	16#0	Nicht rema...	☑	☑		HWID from PLC configuration
3	i_xDriveEnable	Bool	false	Nicht rema...	☑	☑		Enable motor current
4	i_xQuickStop	Bool	false	Nicht rema...	☑	☑		QuickStop
5	i_xHALT	Bool	false	Nicht rema...	☑	☑		HALT
6	i_xContinue	Bool	false	Nicht rema...	☑	☑		Continue after HALT
7	i_xFaultReset	Bool	false	Nicht rema...	☑	☑		Clear Error
8	Output							
9	q_byDriveState	Byte	16#0	Nicht rema...	☑	☑		Drive state
10	q_xReadyForMotion	Bool	false	Nicht rema...	☑	☑		Drive is in state 6 - Ready to start any movement
11	q_xReadyToSwitchOn	Bool	false	Nicht re...	☑	☑		Drive is in state 4 - Ready to switch ON (ENABLE)
12	q_xFault	Bool	false	Nicht rema...	☑	☑		fault is active
13	q_xWarning	Bool	false	Nicht rema...	☑	☑		warning is active
14	q_xHALT_active	Bool	false	Nicht rema...	☑	☑		HALT is active
15	q_xRef_OK	Bool	false	Nicht rema...	☑	☑		reference OK
16	q_xQuickStop_Active	Bool	false	Nicht rema...	☑	☑		Quick Stop is active
17	q_diActualPosition	DInt	0	Nicht rema...	☑	☑		Actual position value
18	q_diActualVelocity	DInt	0	Nicht rema...	☑	☑		Actual velocity value
19	q_inActual_Current	Int	0	Nicht rema...	☑	☑		Actual motor current
20	q_xStandstill	Bool	false	Nicht rema...	☑	☑		STANDSTILL
21	q_xPositiveDirection	Bool	false	Nicht rema...	☑	☑		positive direction
22	q_xNegativeDirection	Bool	false	Nicht rema...	☑	☑		negative direction
23	q_xInPositionWindow	Bool	false	Nicht rema...	☑	☑		In position window
24	q_xTargetVelocityZero	Bool	false	Nicht rema...	☑	☑		target velocity is zero
25	q_xAccelerating	Bool	false	Nicht rema...	☑	☑		accelerating phase
26	q_xDecelerating	Bool	false	Nicht rema...	☑	☑		decelerating phase
27	q_xConstantVelocity	Bool	false	Nicht rema...	☑	☑		constant velocity
28	q_woLastError	Word	16#0	Nicht rema...	☑	☑		Last Error ID (7178)
29	q_woModeError	Word	16#0	Nicht rema...	☑	☑		Mode Error ID (6962)
30	InOut							
31	LXM32_Ref	"LXM32_Ref"						Axis reference structure

LXM32M – S7-1200/1500

Function block - LXM32_Control

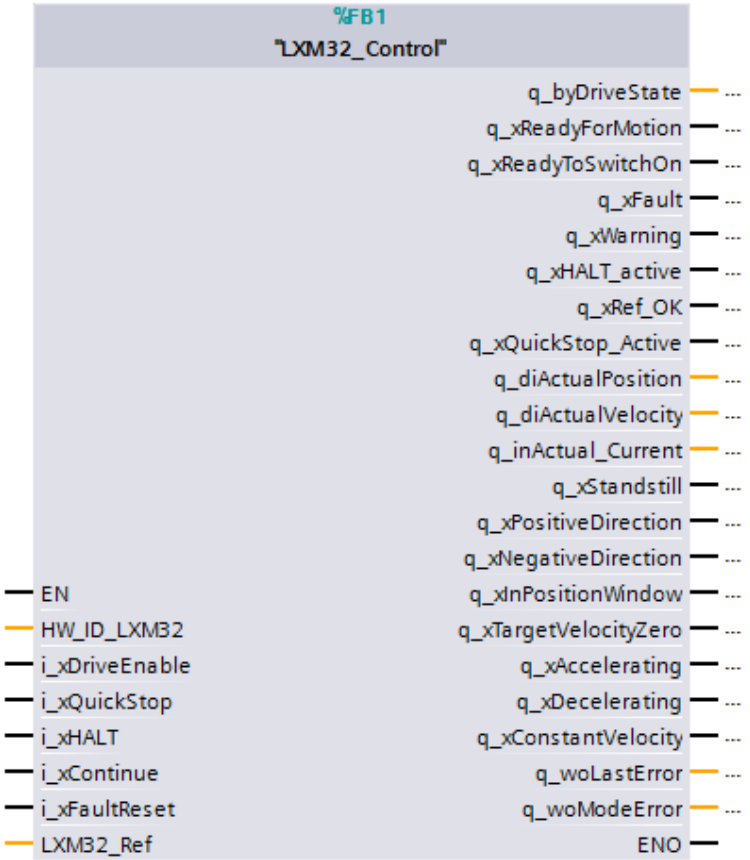
<u>Inputs:</u>

i_DriveEnable:	Enables the power stage
i_xQuickStop:	Stop movement with quick stop
i_xHALT:	HALT activate
i_xContinue:	Continues movement after HALT
i_xFaultReset:	Error reset



LXM32M – S7-1200/1500

Function block - LXM32_Control

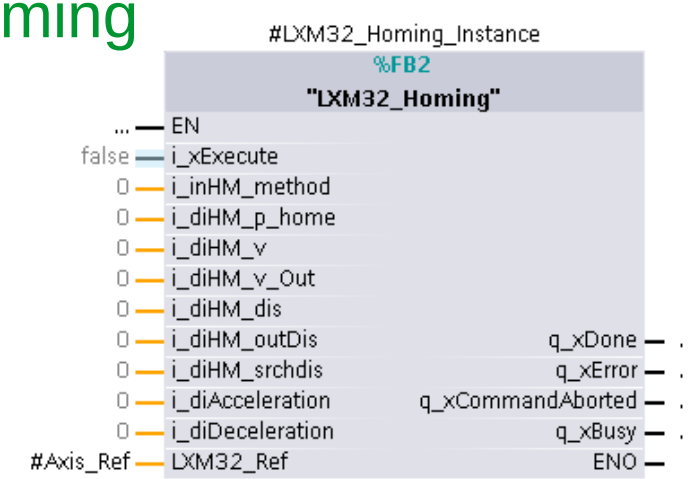


Outputs:

q_byDriveState:	Operating state of the drive
q_xReadyForMotion:	Drive is enabled (state 6)
q_xReadyToSwitchOn:	Drive is ready to switch on (state 4)
q_xFault:	Drive Fault is active
q_xWarning:	Warning is active
q_xRef_OK:	Drive is referenced
q_xQuickStop_Active:	Quick Stop is active
q_diActualPosition:	Actual motor position
q_diActualVelocity:	Actual motor speed
q_inActual_Current:	Actual motor current
q_xStandstill:	Statusbit STANDSTILL
q_xPositiveDirection:	Statusbit motor moves positive
q_xNegativeDirection:	Statusbit motor moves negative
q_xInPositionWindow:	Statusbit “In Position Window”
q_xTargetVelocityZero:	Target velocity is zero
q_xAccelerating:	drive is accelerating
q_xDecelerating:	drive is decelerating
q_xConstantVelocity:	drive moves with constant velocity
q_woLastError:	drive error ID – See product manual (Object 7178)
q_woModeError:	drive mode error ID – See product manual (Object 6962)

LXM32M – S7-1200/1500

Function block - LXM32_Homing



Interface

	Name	Data type	Default value	Retain	Visible in ...	Comment
	Input					
	i_xExecute	Bool	false	Non-retentive	☑	rising edge starts the operation
	i_inHM_method	Int	0	Non-retentive	☑	Homing method (6936)
	i_diHM_p_home	DInt	0	Non-retentive	☑	Position at reference point (10262)
	i_diHM_v	DInt	0	Non-retentive	☑	Target velocity for searching the switch (10248)
	i_diHM_v_Out	DInt	0	Non-retentive	☑	Target velocity for moving away from switch (10250)
	i_diHM_dis	DInt	0	Non-retentive	☑	Distance from switching point (10254)
	i_diHM_outDis	DInt	0	Non-retentive	☑	Maximum distance for search for switching point (10252)
	i_diHM_srchdis	DInt	0	Non-retentive	☑	Maximum search distance after overtravel of switch (10266)
	i_diAcceleration	DInt	0	Non-retentive	☑	Acceleration value
	i_diDeceleration	DInt	0	Non-retentive	☑	Deceleration value
	Output					
	q_xDone	Bool	false	Non-retentive	☑	reference movement finished without error
	q_xError	Bool	false	Non-retentive	☑	finished with error
	q_xCommandAborted	Bool	false	Non-retentive	☑	function aborted
	q_xBusy	Bool	false	Non-retentive	☑	function is active
	InOut					
	LXM32_Ref	"LXM32_Ref"		Non-retentive	☑	Axis reference structure

LXM32M – S7-1200/1500

Function block - LXM32_Homing

Rising edge on “i_xExecute” starts the reference movement.
The homing is finished without an error when the output “q_xDone” is TRUE.
Homing could be aborted by a QuickStop (LXM32_Control).
In this case the output “q_xError” will be set to TRUE.

Homing types: (Product manual parameter HMmethod (6936))

HMmethod	Homing method (263) 1: LIMN with index pulse 2: LIMP with index pulse 7: REF+ with index pulse, inv., outside 8: REF+ with index pulse, inv., inside 9: REF+ with index pulse, not inv., inside 10: REF+ with index pulse, not inv., outside 11: REF- with index pulse, inv., outside 12: REF- with index pulse, inv., inside 13: REF- with index pulse, not inv., inside 14: REF- with index pulse, not inv., outside 17: LIMN 18: LIMP 23: REF+, inv., outside 24: REF+, inv., inside 25: REF+, not inv., inside 26: REF+, not inv., outside 27: REF-, inv., outside 28: REF-, inv., inside 29: REF-, not inv., inside 30: REF-, not inv., outside 33: Index pulse neg. direction 34: Index pulse pos. direction 35: Position setting	- 1 18 35	INT8 INT16 INT16 INT16 R/W - -	CANopen 6098:0_h Modbus 6936 Profibus 6936 CIP 127.1.12

A detailed description of the homing parameters is available in the drive manual of LXM32.

LXM32M – S7-1200/1500

Function block - LXM32_Homing

HMdis	Distance from switching point The distance from the switching point is defined as the reference point. The parameter is only effective during a reference movement without index pulse. Changed settings become active the next time the motor moves.	usr_p 1 200 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3028:7h Modbus 10254 Profibus 10254 CIP 140.1.7
HMp_home	Position at reference point After a successful reference movement, this position is automatically set at the reference point. Changed settings become active the next time the motor moves.	usr_p -2147483648 0 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3028:Bh Modbus 10262 Profibus 10262 CIP 140.1.11

LXM32M – S7-1200/1500

Function block - LXM32_Homing

HMoutdis	Maximum distance for search for switching point 0: Monitoring of distance inactive >0: Maximum distance After detection of the switch, the drive starts to search for the defined switching point. If the defined switching point is not found within the distance defined here, the reference movement is canceled with an error. Changed settings become active the next time the motor moves.	usr_p 0 0 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3028:6h Modbus 10252 Profibus 10252 CIP 140.1.6
HMsrchdis	Maximum search distance after overtravel of switch 0: Search distance monitoring disabled >0: Search distance The switch must be activated again within this search distance, otherwise the reference movement is canceled. Changed settings become active the next time the motor moves.	usr_p 0 0 2147483647	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3028:Dh Modbus 10266 Profibus 10266 CIP 140.1.13

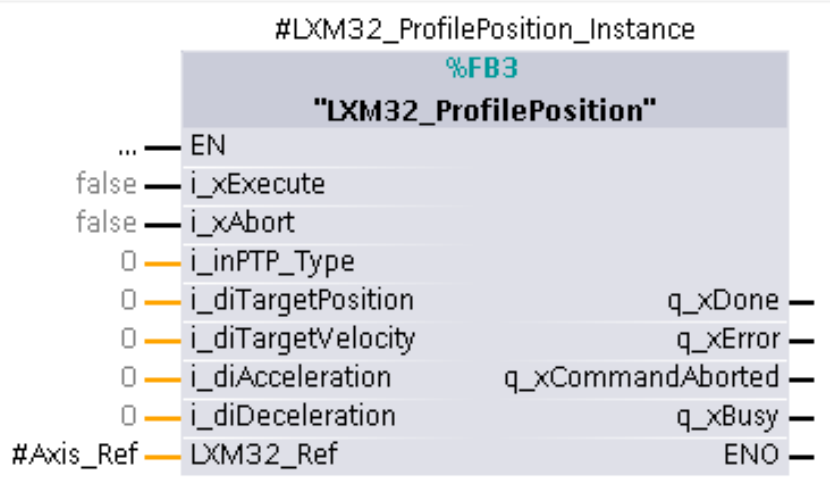
LXM32M – S7-1200/1500

Function block - LXM32_Homing

HMv oP → hon- hOn	Target velocity for searching the switch The adjustable value is internally limited to the current parameter setting in RAMP_v_max. Changed settings become active the next time the motor moves.	usr_v 1 60 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 6099:1h Modbus 10248 Profibus 10248 CIP 140.1.4
HMv_out	Target velocity for moving away from switch The adjustable value is internally limited to the current parameter setting in RAMP_v_max. Changed settings become active the next time the motor moves.	usr_v 1 6 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 6099:2h Modbus 10250 Profibus 10250 CIP 140.1.5

LXM32M – S7-1200/1500

LXM32_ProfilePosition



Interface

	Name	Data type	Default value	Retain	Visible in HMI	Comment
	Input					
	i_xExecute	Bool	false	Non-retentive	☑	rising edge starts a new movement
	i_xAbort	Bool	false	Non-retentive	☑	abort active movement
	i_inPTP_Type	Int	0	Non-retentive	☑	1=absolute / 2=additive / 3=relative
	i_diTargetPosition	DInt	0	Non-retentive	☑	Target position value
	i_diTargetVelocity	DInt	0	Non-retentive	☑	Target velocity value
	i_diAcceleration	DInt	0	Non-retentive	☑	Acceleration value
	i_diDeceleration	DInt	0	Non-retentive	☑	Deceleration value
	Output					
	q_xDone	Bool	false	Non-retentive	☑	Target position reached
	q_xError	Bool	false	Non-retentive	☑	finished with error
	q_xCommandAborted	Bool	false	Non-retentive	☑	function aborted
	q_xBusy	Bool	false	Non-retentive	☑	function is active
	InOut					
	LXM32_Ref	"LXM32_Ref"		Non-retentive	☑	Axis reference structure

LXM32M – S7-1200/1500

LXM32_ProfilePosition

Rising edge on “i_xExecute” starts the movement.

Rising edge on “i_xAbort” stops the movement.

“i_inPTP_Type”:
1 = Absolute movement
2 = Additive movement
3 = Relative movement

New target position can be started with a new rising edge on “i_xExecute” during an active movement.

Absolute movement:
Changing target velocity value during an active movement takes effect immediately.

LXM32M – S7-1200/1500

LXM32_ProfileVelocity

Interface

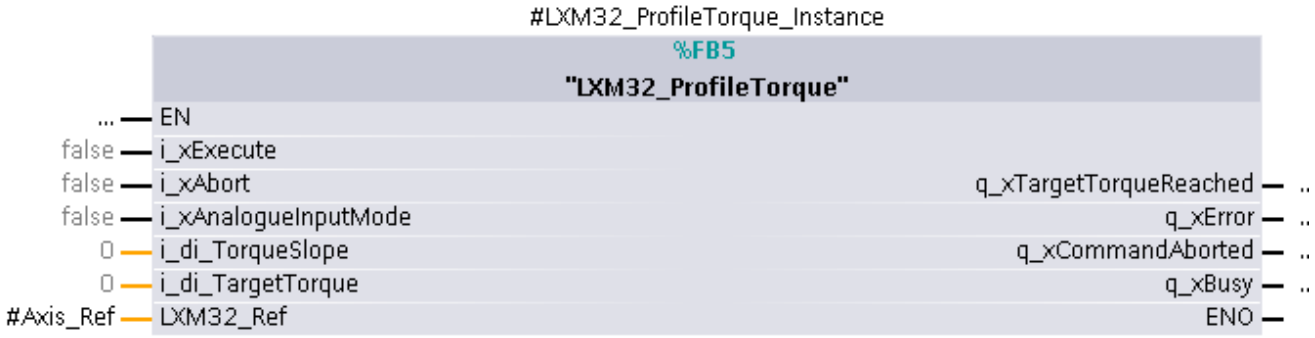
	Name	Data type	Default value	Retain	Visible in HMI	Comment
	Input					
	i_xExecute	Bool	false	Non-retentive	☑	Start movement
	i_xAbort	Bool	false	Non-retentive	☑	Abort current movement
	i_xAnalogueInputMode	Bool	false	Non-retentive	☑	TRUE =speed reference is +/- 10V analogue signal
	i_diTargetVelocity	DInt	0	Non-retentive	☑	Target speed
	i_diAcceleration	DInt	0	Non-retentive	☑	Acceleration
	i_diDeceleration	DInt	0	Non-retentive	☑	Deceleration
	Output					
	q_xTargetVelocityReached	Bool	false	Non-retentive	☑	Target velocity reached
	q_xError	Bool	false	Non-retentive	☑	FB finished with error
	q_xCommandAborted	Bool	false	Non-retentive	☑	FB aborted
	q_xBusy	Bool	false	Non-retentive	☑	function block is busy
	InOut					
	LXM32_Ref	"LXM32_Ref"		Non-retentive	☑	Axis reference structure

i_xAnalogueInputMode: TRUE = target velocity is set by analogue input of IO module.

Changing target velocity value during an active movement take effect immediately.

LXM32M – S7-1200/1500

LXM32_ProfileTorque



Interface

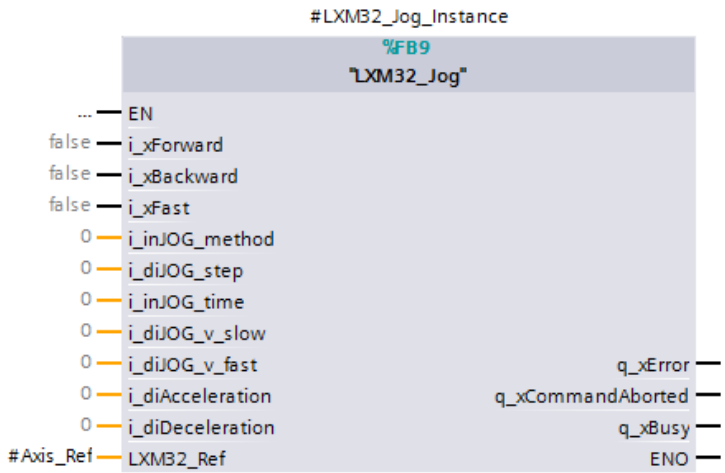
	Name	Data type	Default value	Retain	Visible in HMI	Comment
	Input					
	i_xExecute	Bool	false	Non-retentive	☑	Start movement
	i_xAbort	Bool	false	Non-retentive	☑	Abort current movement
	i_xAnalogueInputMode	Bool	false	Non-retentive	☑	TRUE =torque reference is +/- 10V analogue signal
	i_di_TorqueSlope	DInt	0	Non-retentive	☑	Torque slope (1620)
	i_di_TargetTorque	DInt	0	Non-retentive	☑	Target torque (6944)
	Output					
	q_xTargetTorqueReached	Bool	false	Non-retentive	☑	Target torque is reached
	q_xError	Bool	false	Non-retentive	☑	finished with error
	q_xCommandAborted	Bool	false	Non-retentive	☑	function aborted
	q_xBusy	Bool	false	Non-retentive	☑	function is active
	InOut					
	LXM32_Ref	"LXM32_Ref"		Non-retentive	☑	Axis reference structure

i_xAnalogueInputMode: TRUE = target torque is set by analogue input of IO module.

Changing target torque value during an active movement take effect immediately.

LXM32M – S7-1200/1500

LXM32_Jog

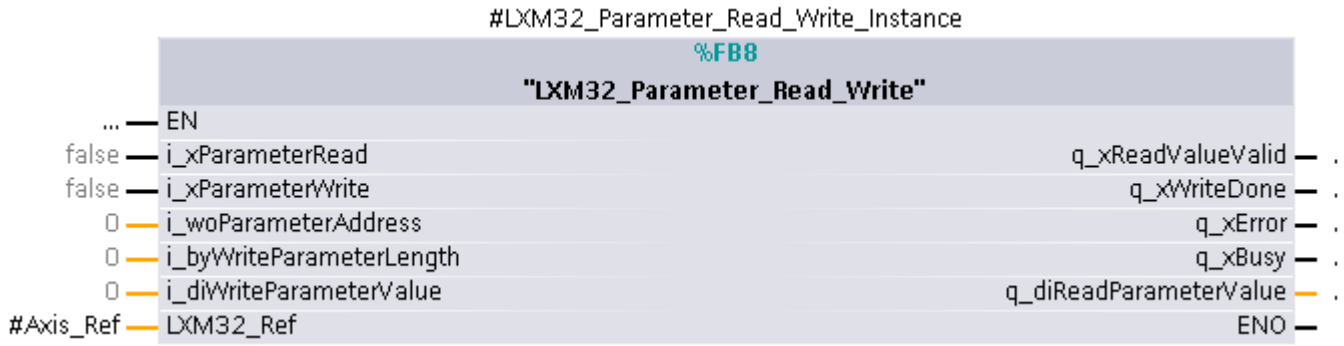


LXM32_Jog

	Name	Data t...	Def...	Retain	Accessible f...	Visible...	Setp...	Comment
1	Input							
2	i_xForward	Bool	false	Non-retain	☑	☑		Jog forward
3	i_xBackward	Bool	false	Non-retain	☑	☑		Jog backward
4	i_xFast	Bool	false	Non-retain	☑	☑		Jog fast
5	i_inJOG_method	Int	0	Non-retain	☑	☑		Jog method (10502) 0=continuous 1= Step movement
6	i_diJOG_step	DInt	0	Non-retain	☑	☑		Jog_Step (10510) Distance for Step movement
7	i_inJOG_time	Int	0	Non-retain	☑	☑		Jog time (10512) Wait time for Step movement
8	i_diJOG_v_slow	DInt	0	Non-retain	☑	☑		Jog slow velocity (10504)
9	i_diJOG_v_fast	DInt	0	Non-retain	☑	☑		Jog fast velocity (10506)
10	i_diAcceleration	DInt	0	Non-retain	☑	☑		Acceleration
11	i_diDeceleration	DInt	0	Non-retain	☑	☑		Deceleration
12	Output							
13	q_xError	Bool	false	Non-retain	☑	☑		finished with error
14	q_xCommandAborted	Bool	false	Non-retain	☑	☑		function aborted
15	q_xBusy	Bool	false	Non-retain	☑	☑		function is busy
16	InOut							
17	LXM32_Ref	"LXM...						Axis reference structure

LXM32M – S7-1200/1500

LXM32_Parameter_Read_Write



Interface

	Name	Data type	Default value	Retain	Visible in HMI	Comment
	Input					
	i_xParameterRead	Bool	false	Non-retentive	☑	TRUE = Reading value continuously
	i_xParameterWrite	Bool	false	Non-retentive	☑	rising edge = Writing once
	i_woParameterAddress	Word	0	Non-retentive	☑	Parameter address (see product manual)
	i_byWriteParameterLength	Byte	0	Non-retentive	☑	parameter length in bytes (2 or 4 bytes)
	i_diWriteParameterValue	DInt	0	Non-retentive	☑	parameter write value
	Output					
	q_xReadValueValid	Bool	false	Non-retentive	☑	reading value is valid
	q_xWriteDone	Bool	false	Non-retentive	☑	writing finished without error
	q_xError	Bool	false	Non-retentive	☑	finished with error
	q_xBusy	Bool	false	Non-retentive	☑	function is active
	q_diReadParameterValue	DInt	0	Non-retentive	☑	reading value
	InOut					
	LXM32_Ref	"LXM32_Ref"		Non-retentive	☑	Axis reference structure

LXM32M – S7-1200/1500

LXM32_ElectronicGear

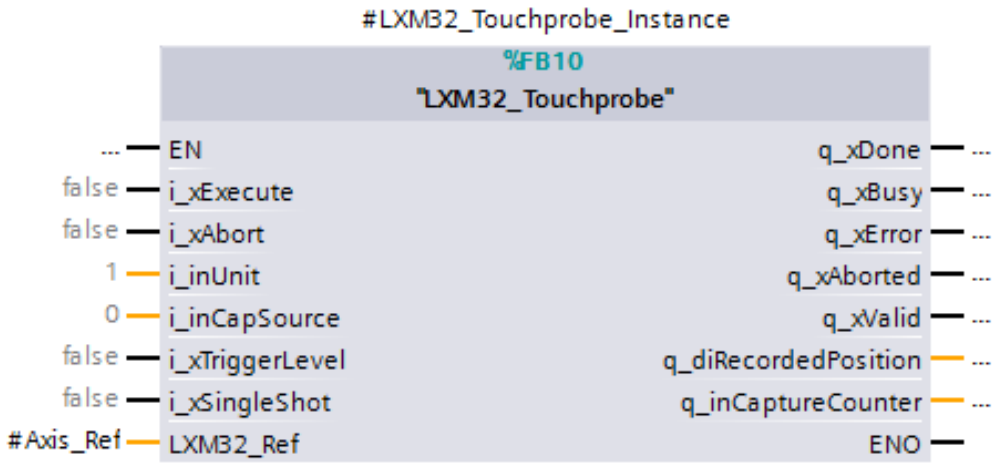
Interface

Name	Data type	Default value	Retain	Visible in ...	Comment
Input					
i_xExecute	Bool	false	Non-ret...	☑	Start movement
i_xAbort	Bool	false	Non-retenti...	☑	Abort current movement
i_inGearReference	Int	0	Non-retenti...	☑	(1..3) 1= PosSync immediate / 2=PosSync compensated / 3=VelocitySync
i_diGearNumerator	DInt	131072	Non-retenti...	☑	Gear Numerator (9736) (-2147483648...2147483647)
i_diGearDenomerator	DInt	4096	Non-retenti...	☑	GearDenomerator (9734) (1..2147483647)
i_diAcceleration	DInt	1000	Non-retenti...	☑	Acceleration only active in Velocity Sync with ProfileOn
i_diDeceleration	DInt	1000	Non-retenti...	☑	Deceleration only active in Velocity Sync with ProfileOn
Output					
q_xInGear	Bool	false	Non-retenti...	☑	Synchronization is active
q_xError	Bool	false	Non-retenti...	☑	FB finished with error
q_xCommandAborted	Bool	false	Non-retenti...	☑	FB aborted
q_xBusy	Bool	false	Non-retenti...	☑	function block is busy
InOut					
LXM32_Ref	"LXM32_Ref"		Non-retenti...	☑	Axis reference structure

Note: Additional Parameter values for Gear mode have to be configured by commissioning tool or by using LXM32_Parameter_Read_Write function block.

LXM32M – S7-1200/1500

LXM32_Touchprobe



LXM32_Touchprobe

	Name	Datentyp	Defau...	Remanenz	Erreichbar a..	Sichtbar i...	Einstellwert	Kommentar
1	Input							
2	i_xExecute	Bool	false	Nicht re...	☑	☑	☐	Rising edge starts the touchprobe function
3	i_xAbort	Bool	false	Nicht reman...	☑	☑	☐	Abort active touchprobe FB
4	i_inUnit	Int	1	Nicht reman...	☑	☑	☐	Unit number CAP1, CAP2 or CAP3
5	i_inCapSource	Int	0	Nicht reman...	☑	☑	☐	0=Encoder1 / 1=Encoder2
6	i_xTriggerLevel	Bool	false	Nicht reman...	☑	☑	☐	FALSE: Trigger on falling adge / TRUE: Trigger on rising edge
7	i_xSingleShot	Bool	false	Nicht reman...	☑	☑	☐	FALSE: trigger continuously / TRUE Trigger only once
8	Output							
9	q_xDone	Bool	false	Nicht reman...	☑	☑	☐	Position capture OK (only SingleShot)
10	q_xBusy	Bool	false	Nicht reman...	☑	☑	☐	Function block busy
11	q_xError	Bool	false	Nicht reman...	☑	☑	☐	Function block error - Capture stopped
12	q_xAborted	Bool	false	Nicht reman...	☑	☑	☐	Function block aborted - Capture stopped
13	q_xValid	Bool	false	Nicht reman...	☑	☑	☐	TRUE=new Capture event (only TRUE for 1 PLC cycle)
14	q_diRecordedPosition	DInt	0	Nicht reman...	☑	☑	☐	Captured position at the time of the "capture signal"
15	q_inCaptureCounter	Int	0	Nicht reman...	☑	☑	☐	Capture input event counter
16	InOut							
17	LXM32_Ref	"LXM32_Ref"			☐	☐	☐	Axis reference structure

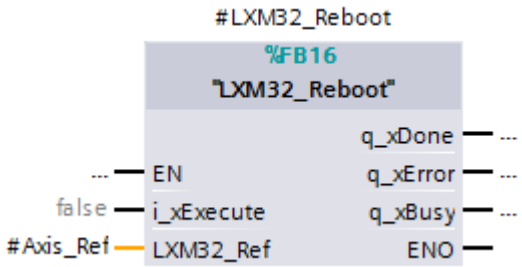
LXM32M – S7-1200/1500

LXM32_Reboot

This function can be used to restart the LXM32 device.

Note !!!

The communication will be lost until the LXM32 has booted up again



LXM32_Reboot

	Name	Datentyp	Defaultwert	Remanenz	Erreichbar a..	Sichtbar i...	Einstellwert	Kommentar
1	Input							
2	i_xExecute	Bool	false	Nicht remanent	☑	☑		TRUE = Reading value continuously
3	Output							
4	q_xDone	Bool	false	Nicht remanent	☑	☑		writing finished without error
5	q_xError	Bool	false	Nicht remanent	☑	☑		finished with error
6	q_xBusy	Bool	false	Nicht remanent	☑	☑		function is active
7	InOut							
8	LXM32_Ref	"LXM32_Ref"						Axis reference structure

LXM32M – S7-1200/1500

LXM32_RMAC

Relative Movement After Capture

LXM32 Configuration

Only define the one digital input with “Start Signal Of RMAC” and connect the capture sensor to this digital input.

- LXM32M
  - Simply start
  - Axis configuration
  - Operation configuration
  - Motor control
  - I/O functions
    - Digital inputs
    - Digital outputs
    - PTI
    - PTO

In: All Search

Name	Value	
IOfunct_DI0	Start Signal Of RMAC	Function Input DI0
IOfunct_DI1	Reference Switch (REF)	Function Input DI1
IOfunct_DI2	Positive Limit Switch (LIMP)	Function Input DI2
IOfunct_DI3	Negative Limit Switch (LIMN)	Function Input DI3
IOfunct_DI4	Freely Available	Function Input DI4
IOfunct_DI5	Freely Available	Function Input DI5

Do not define the IO function “Activate RMAC” !
The activation is done by the PLC when using the FB “LXM32_RMAC”

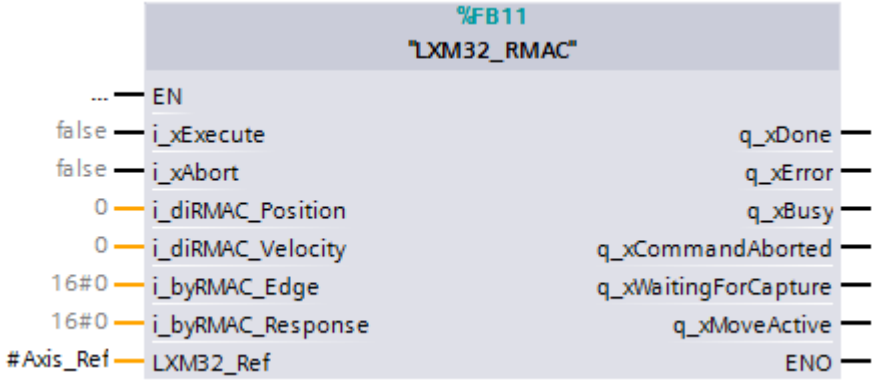
LXM32M – S7-1200/1500

LXM32_RMAC

Relative Movement After Capture

i_xExecute
Rising edge activates RMAC function
Activation can be done in STANDSTILL
or during a movement.

i_xAbort
1st case: Deactivates RMAC function
2nd case: Stops an active RMAC movement
if capture already occurred



q_xDONE –
RMAC Movement is finished without error

q_xWaitingForCapture –
RMAC is activated and waiting for Capture signal

q_xMoveActive –
Capture signal occurred and RMAC movement is active. The Original operating mode is aborted. E.g. ProfilePosition.q_xAborted = TRUE

LXM32M – S7-1200/1500

LXM32_RMAC

Relative Movement After Capture

Parameters (see also LXM32 Product manual)

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
RMAC_Position	Target position of relative movement after capture Minimum/maximum values depend on: - Scaling factor Changed settings become active the next time the motor moves. Available with firmware version ≥V01.10.	usr_p - 0 -	INT32 INT32 INT32 INT32 R/W per. -	CANopen 3023:D_h Modbus 8986 Profibus 8986 CIP 135.1.13
RMAC_Velocity	Velocity of relative movement after capture Value 0: Use of current motor velocity Value >0: Value is the target velocity The adjustable value is internally limited to the setting in RAMP_v_max. Changed settings become active the next time the motor moves. Available with firmware version ≥V01.10.	usr_v 0 0 2147483647	UINT32 UINT32 UINT32 UINT32 R/W per. -	CANopen 3023:E_h Modbus 8988 Profibus 8988 CIP 135.1.14

LXM32M – S7-1200/1500

LXM32_RMAC

Relative Movement After Capture

Parameters (see also LXM32 Product manual)

Parameter name HMI menu HMI name	Description	Unit Minimum value Factory setting Maximum value	Data type R/W Persistent Expert	Parameter address via fieldbus
RMAC_Edge	Edge of capture signal for relative movement after capture **0 / Falling edge**: Falling edge **1 / Rising edge**: Rising edge Available with firmware version ≥V01.10.	- 0 0 1	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3023:10_h Modbus 8992 Profibus 8992 CIP 135.1.16
RMAC_Response	Response if target postion is overtraveld **0 / Error Class 1**: Error class 1 **1 / No Movement To Target Position**: No movement to target position **2 / Movement To Target Position**: Movement to target position Changed settings become active immediately. Available with firmware version ≥V01.10.	- 0 0 2	UINT16 UINT16 UINT16 UINT16 R/W per. -	CANopen 3023:F_h Modbus 8990 Profibus 8990 CIP 135.1.15

LXM32M – Profibus – S7-1200/1500

Questions and Answers

Thanks!

Make the most of your energy