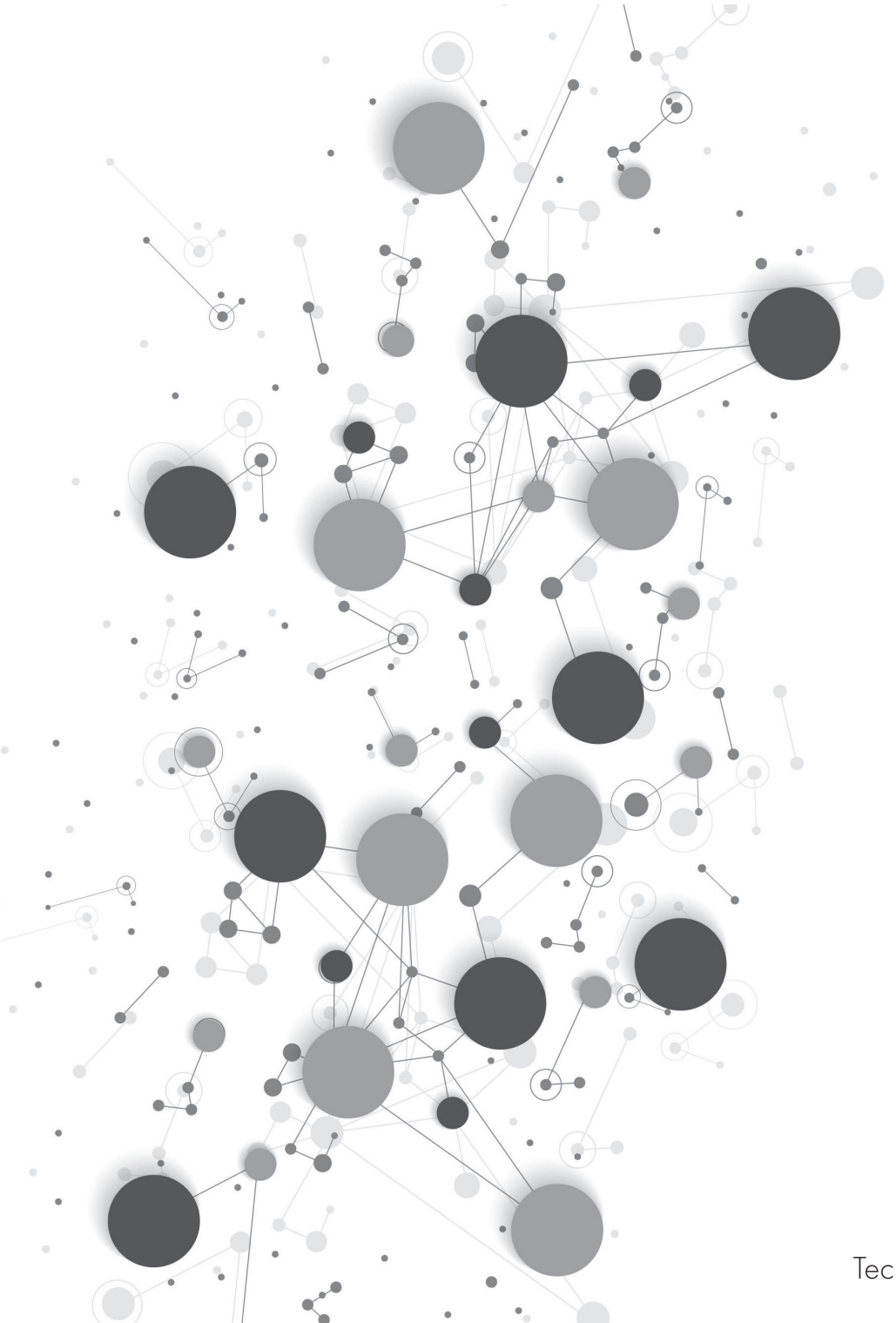
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User Guide

# FIELDBUS User Guide




About This Document 1

Fieldbus Connectivity 2

Parameter Configuration for Fieldbus Operation 3

Modbus RTU 4

CAN 5

Ethernet Connection 6

Internal Webserver 7

Ethernet/IP Communication 8

Modbus TCP 9

Fieldbus Gateways 10

Control & Status Registers 11

Technical Data (External Interface) 12

**1. About This Document ..... 4**
1.1. Compatibility ..... 4
1.2. Intended Audience ..... 4
1.3. Additional Documentation ..... 4
**2. Fieldbus Connectivity ..... 5**
2.1. Overview ..... 5
**3. Parameter Configuration for Fieldbus Operation ..... 6**
3.1. Overview ..... 6
**4. Modbus RTU ..... 8**
4.1. Overview ..... 8
4.2. Hardware Connection ..... 8
4.3. Modbus RTU Configuration Parameter ..... 10
4.4. Modbus RTU Status & Control Holding Registers ..... 10
4.5. Parameter Access ..... 10
4.6. Modbus RTU Indirect Parameter Access ..... 10
**5. CAN ..... 23**
5.1. Overview ..... 11
5.2. CAN Communication Configuration Parameter ..... 11
5.3. CAN COB-ID ..... 11
5.4. PDO Default Mapping ..... 12
5.5. PDO Transmission Type ..... 12
5.6. CAN Specific Object Table ..... 12
5.7. Parameter Access ..... 13
5.8. Additional Status Indices ..... 13
**6. Ethernet Connection ..... 14**
6.1. Available Interface Options ..... 14
6.2. External Interface ..... 14
6.3. Internal Interface for IP66 Drives ..... 16
6.4. Optional Interface for Compact 2 Basic Drives ..... 17
6.5. Drive Parameter Settings ..... 17
**7. Internal Webserver ..... 18**
7.1. Overview ..... 18
7.2. Default Login ..... 18
7.3. Web Server Contents ..... 18
7.4. Changing the IP Address ..... 20
7.5. Creating an Additional User Account for Limited Access ..... 21
**8. Ethernet/IP Communication ..... 22**
8.1. Overview ..... 22
8.2. Operation ..... 22
8.3. Usage Requirement ..... 22
8.4. Operation ..... 23
8.5. Process Data Exchange (cyclic communication) ..... 23
8.6. Configuring the Scanner ..... 23
8.7. Advanced connection methods ..... 40
8.8. Parameter data transfer ..... 41
8.9. Trouble Shooting ..... 43
**9. Modbus TCP ..... 45**
9.1. Overview ..... 45
9.2. Usage Requirement ..... 45
9.3. Operation ..... 45
9.4. Trouble Shooting ..... 45
**10. Fieldbus Gateways ..... 47**
10.1. Gateway Concept ..... 47
10.2. Gateway Included Components ..... 47
10.3. Gateway Installation ..... 47
10.4. Subnetwork Connection ..... 48
10.5. Gateway Memory Mapping ..... 49
10.6. Controlling the Optidrive(s) ..... 50
10.7. Profibus DP Gateway Features – OD-PROFB-IN ..... 51
10.8. DeviceNet Gateway Features – OD-DEVNT-IN ..... 52
10.9. Diagnostics and Troubleshooting ..... 53
**11. Control & Status Registers ..... 54**
11.1. Control Registers ..... 54
11.2. Standard Status Registers ..... 55
11.3. Extended Status Registers ..... 56
11.4. Additional Modbus RTU Registers / CAN Index Data – Control & Monitoring ..... 57
**12. Technical Data (External Interface) ..... 61**
12.1. Environmental ..... 61

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**This document is the "original instructions" document. All non-English versions are translations of the "original instructions".**

The contents of this document are believed to be correct at the time of printing. In the interest of a commitment to a policy of continuous improvement, the manufacturer reserves the right to change the specification of the product or its performance or the contents of the User Guide without notice.

**Fieldbus Guide Issue 02 (10/21)**

Invertek Drives Ltd adopts a policy of continuous improvement and whilst every effort has been made to provide accurate and up to date information, the information contained in this User Guide should be used for guidance purposes only and does not form the part of any contract.

# 1. About This Document

## 1.1. Compatibility

**This Document is for use with the following firmware versions:**

**Optidrive E3: Version 3.11**

**Optidrive Compact 2 Basic: Version 2.07**

This document provides information regarding parameters and programming for all Invertek Drives' Optidrive E3 product families including the Optidrive E3 based Compact 2 Basic units.

For information regarding installation and technical data, refer to the relevant Installation Guide document.

Invertek Drives Ltd adopts a policy of continuous improvement and whilst every effort has been made to provide accurate and up to date information, the information contained in this User Guide should be used for guidance purposes only and does not form the part of any contract.

The information in this user guide relates to the functionality of the firmware version as stated above. Prior versions of firmware may not fully support all functions as described. If necessary, firmware updates may be carried out using Optitools Studio PC software.

## 1.2. Intended Audience

This document provides an overview of the parameters and functions of the Optidrive product ranges and provides the necessary technical information to allow competent users to understand the functions of the parameters.

## 1.3. Additional Documentation

This document forms part of a package of documents intended to provide information about the Optidrive product range. Related documents are shown in the table below.

| Product Range | Optidrive E3 ODE-3-... | | | | | Optidrive Compact 2-Basic OPC-2-...E |
|---|---|---|---|---|---|---|
| Enclosure | IP20 | IP66 | | | | All |
| Version | All | A | B | C | D | All |
| Quick Start Guide | EN<br>DE<br>SP<br>FR<br>PT<br>IT<br>PO | EN<br>DE<br>SP<br>FR<br>PT<br>IT<br>PO | | | | EN<br>DE |
| Declaration of Conformity | EN | | | | | EN |
| Installation Guide | EN<br>DE<br>SP<br>FR<br>PT<br>IT<br>PO | | | | | EN<br>DE |
| Parameter List | EN<br>DE<br>SP<br>FR<br>PT<br>IT<br>PO | | | | | |
| Fieldbus Guide | EN<br>DE<br>SP<br>FR<br>PT<br>IT<br>PO | | | | | |

# 2. Fieldbus Connectivity

## 2.1. Overview

The following fieldbus networks are supported:

| Fieldbus Network | Requires Option | | | Supported Communication Type | Refer to Section |
|---|---|---|---|---|---|
| | For Compact 2 | For Optidrive E3 IP20 | For Optidrive E3 IP66 | | |
| Modbus RTU | Built In | | | R/W Holding Registers | *4. Modbus RTU* |
| CAN | Built In | | | 2 x PDO & SDO | *5. CAN* |
| Ethernet/IP | - | - | "-EIP" | Cyclic & Acyclic | *6. Ethernet Connection* and *8. Ethernet/IP Communication* |
| Modbus TCP | - | - | "-MTP" | R/W Holding Registers | *6. Ethernet Connection* |
| Profibus DP | OD-PROFB-IN | | | Cyclic Control Only | *10. Fieldbus Gateways* |
| DeviceNet | OD-DEVNET-IN | | | Cyclic Control Only | *10. Fieldbus Gateways* |

# 3. Parameter Configuration for Fieldbus Operation

## 3.1. Overview

The following parameters are used to configure any fieldbus connection. Refer to the Programming Guide for further information. Parameters are explained more fully in the Programming Guide.

### *3.1.1. Parameter P-12: Control Source*

The fieldbus interfaces may be used to monitor information from the drive regardless of where the control commands originate.

If it is required to control the drive through the fieldbus interface, the following parameter should be adjusted as shown.

| **Reference: P-12** | **Function: Control Source Selection** |
|---|---|

| Setting | Function | Description |
|---|---|---|
| **3** | **Fieldbus Mode** | Control via Modbus RTU or Ethernet using the internal Accel / Decel ramp parameters. Recommended setting for all fieldbus except CAN. |
| **4** | **Fieldbus Mode** | Control via Modbus RTU or Ethernet with Accel / Decel ramps determined by the fieldbus. |
| **7** | **CAN open Control** | Control via CAN (RS485) using the internal Accel / Decel ramp parameters. Recommended setting. |
| **8** | **CAN open Control** | Control via CAN (RS485) interface with Accel / Decel ramps updated via CAN. |

**NOTE** When P-12 = 3, 4, 7, or 8 an enable signal must still be provided at the control terminals, digital input 1.

### *3.1.2. P-36 Communication Configuration*

| **Reference: P-36** | **Function: Serial Interface Configuration** |
|---|---|
| **Index 1** | **Function: Address / Node ID** |

**For Modbus RTU: Defines the Node Address**
**For CAN: Defines the Node ID**
**For Ethernet: Setting 1 MUST be used**

| **Index 2** | **Function: Baud Rate** |
|---|---|

| Setting | Baud Rate | Fieldbus |
|---|---|---|
| **0** | 9.6 | Modbus RTU. |
| **1** | 19.2 | For Ethernet communication, 115,2kbps must be selected. |
| **2** | 38.4 | |
| **3** | 57.6 | |
| **4** | 115.2 | |
| **5** | 125 | CAN |
| **6** | 250 | |
| **7** | 500 | |
| **8** | 1000 | |

| Index 3 | Function: Modbus RTU Communication Loss Detection |
|---|---|

Communication loss protection for Modbus RTU is selected here. For CAN, refer to the Fieldbus Guide for information.

| Setting | Display | Timeout | Action |
|---|---|---|---|
| **0** | 0 | Disabled | |
| **1** | t 30 | 30ms | Trip (Coast Stop) |
| **2** | t 100 | 100ms | |
| **3** | t 1000 | 1s | |
| **4** | t 3000 | 3s | |
| **5** | r 30 | 30ms | Ramp to Stop |
| **6** | r 100 | 100ms | |
| **7** | r 1000 | 1s | |
| **8** | r 3000 | 3s | |
| **9** | t 10000 | 10s | Trip (Coast Stop) |
| **10** | t 30000 | 30s | |
| **11** | t 60000 | 60s | |
| **12** | r 10000 | 10s | Ramp to Stop |
| **13** | r 30000 | 30s | |
| **14** | r 60000 | 60s | |

Parameter P-36 is a compound parameter with multiple indices. The indices are displayed sequentially when accessing the parameter through a keypad or separately in Optitools Studio. The data from all indices is stored within the drive memory as a single WORD. When accessing this value through a fieldbus network, the data format is as follows:

| Reference: P-63 | Function: Modbus RTU Mode Selection | | | |
|---|---|---|---|---|
| E3 IP20, IP66NS | Minimum: | Maximum: 1 | Default: 0 | Scaling: 1 = 1 |
| E3 IP66S | | | | |
| Compact 2 Basic | | | | |
| **Fieldbus Information:** | CAN Index: 20A3h | Modbus Register: 191 | Format: UINT | Units: N/A |

**Description:**

| Setting | Function | Description |
|---|---|---|
| **0** | **Standard** | All Modbus RTU telegrams are valid regardless of the destination address. In this case, communication loss detection is only activated when no valid Modbus RTU data is present on the network for the time period selected in P-36 regardless of the intended destination address. This is intended for larger Modbus RTU networks with several noes where there may be some time delay between Modbus transactions specifically intended for the drive however transactions intended for other network devices will be present. |
| **1** | **Advanced** | Only Modbus RTU telegrams intended for the specific node address are valid. Communication loss protection will activate if no Modbus RTU message intended for the specific drive node address is received within the time limit set in P-36. This mode is intended for use in small networks and **must** be used with any other Fieldbus network type e.g. Modbus TCP, Ethernet/IP. |

# 4. Modbus RTU

## 4.1. Overview

Modbus RTU communication is supported using Function Codes 03 Read Holding Registers and 06 Write Single Holding Register.

All internal registers are Holding registers. There are no other register types present within the drive.

Registers 1 to 4 only support Function Code 16 Write multiple Holding Registers.

Modbus RTU communication is enabled by default for Read access.

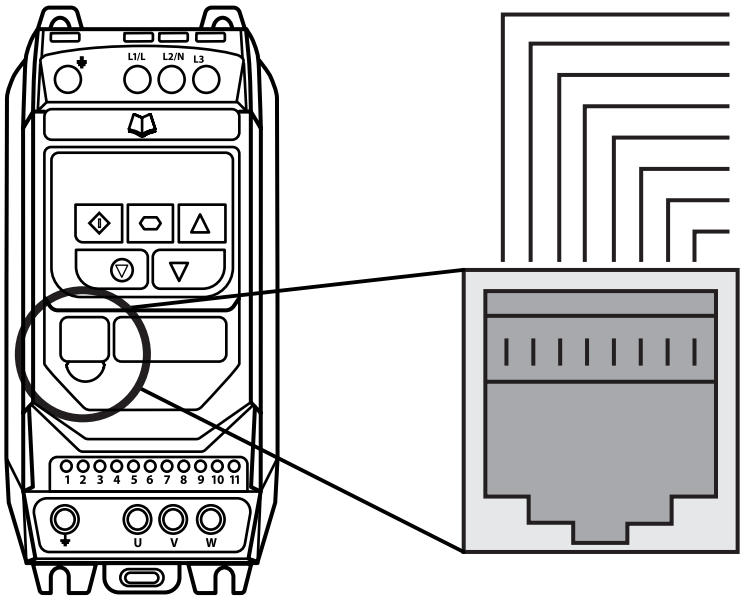
To control the drive through Modbus RTU, parameter P-12 should be set to 3 or 4. Refer to the programming guide for further information on the parameter settings.

When an external Modbus RTU device is used to control the drive, Digital Input 1 acts to provide a local enable / disable signal. The drive will not operate unless digital input 1 is ON. Additional functions may be assigned to other input terminals. Refer to the Installation guide for details of the digital Input function assignments that are possible.

## 4.2. Hardware Connection

### *4.2.1. Optidrive E3 IP20*

Optidrive E3 IP20 models have a built in RJ45 connector which provides the interface for Modbus RTU connection.



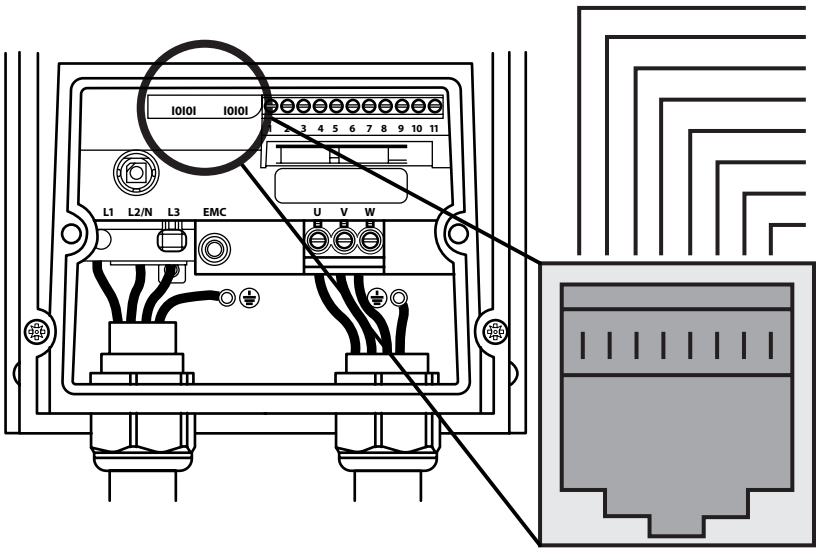

| | |
|---|---|
| **1** | CAN- |
| **2** | CAN+ |
| **3** | 0 Volts |
| **4** | Optibus / Remote Keypad / PC Connection |
| **5** | Optibus / Remote Keypad / PC Connection + |
| **6** | +24 Volt |
| **7** | -RS485 (Modbus RTU) |
| **8** | +RS485 (Modbus RTU) |

**Warning:**

This is not an Ethernet connection. Do not connect directly to an Ethernet port.

### *4.2.2. Optidrive E3 IP66*

Optidrive E3 IP66 models have two RJ45 connectors fitted under the terminal cover as shown below. The connectors are parallel allowing simple connection between multiple drives.




| | |
|---|---|
| **1** | CAN- |
| **2** | CAN+ |
| **3** | 0 Volts |
| **4** | Optibus / Remote Keypad / PC Connection |
| **5** | Optibus / Remote Keypad / PC Connection + |
| **6** | +24 Volt |
| **7** | -RS485 (Modbus RTU) |
| **8** | +RS485 (Modbus RTU) |

**Warning:**

This is not an Ethernet connection. Do not connect directly to an Ethernet port.

### *4.2.3. Optidrive Compact 2 Basic*

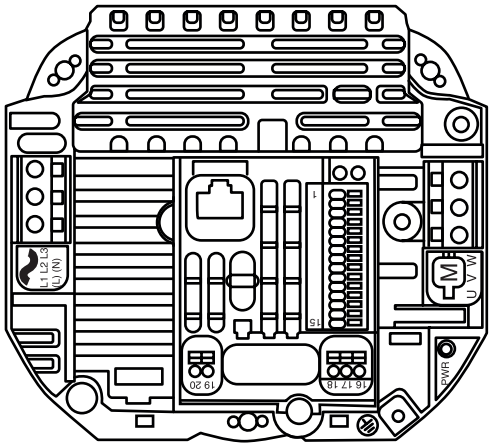
**Suitable Motor Types**

Optidrive Compact 2 Basic drives also include the RJ45 connector with the same layout as Optidrive E3 units shown above. Additionally, the Modbus RTU interface is also present on terminals as follows:

Terminal 7: 0V

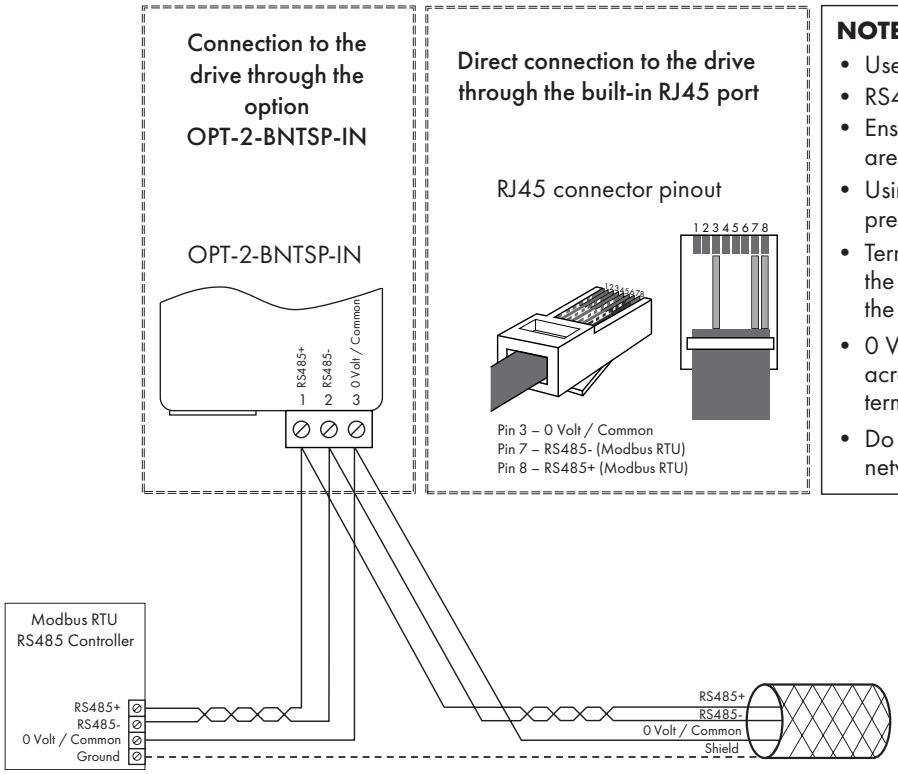
Terminal 10: Modbus RTU +

Terminal 11: Modbus RTU -




### *4.2.4. General*

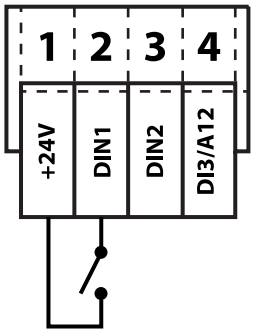
All Invertek drive's support the RS485 **3-wire** connection method for Modbus RTU according to the network specification. The three wires are essential to transfer data and maintain common potential between all nodes. For drives that have an RJ45 connector an optional interface connector providing terminals to connect to a Modbus RTU network is available, part number OPT-2-BNTSP-IN.




**NOTES**

- Use 3 or 4 Conductor Twisted Pair Cable
- RS485+ and RS485- must be twisted pair
- Ensure the network taps for the drive are kept as short as possible
- Using Option OPT-2-BNTSP-IN is preferred
- Terminate the network cable shield at the controller only. Do not terminate at the drive!
- 0 Volt common must be connected across all devices and to reference 0 Volt terminal at the controller
- Do not connect the 0V Common of the network to power ground

### *4.2.5. Control Terminal Connection*



## 4.3. Modbus RTU Configuration Parameter

Refer to section *3. Parameter Configuration for Fieldbus Operation on page 6.*

## 4.4. Modbus RTU Status & Control Holding Registers

Modbus RTU status holding registers are shown in section *11. Control & Status Registers on page 54.*

Holding Register 1 – 4 are used for drive control.

Additional Holding registers provide status information which may be read from the drive.

Modbus Master devices differ between different manufacturers and so it may be necessary to review the documentation for the specific Master device being used to understand the correct addressing method to access Holding Registers, e.g.

- Some devices use zero based addressing
  - In this case the first Holding Register address is Holding Register 0
  - Subtract 1 from the Holding Register number shown in the documentation.
- Some devices recognise Holding Registers with a 40000 prefix
  - In this case the first Holding Register may be 40000 or 40001
  - Add the appropriate prefix and if necessary, subtract the offset.

## 4.5. Parameter Access

All User Adjustable parameters are accessible by Modbus RTU using the corresponding Holding Register. The register number associated to each parameter is shown in the Programming Guide document along with any specific information about how the value is scaled or stored.

Parameter values may be read from the drive or written to, depending on the operating mode of the drive – some parameters cannot be changed whilst the drive is enabled.

## 4.6. Modbus RTU Indirect Parameter Access

In addition to Direct Access, Indirect Read / Write access to all user adjustable parameters is supported using a simple method as detailed below. This is achieved using the following two Modbus registers.

### *4.6.1. Register 44: Drive Parameter Index*

This index value will be used by register 45 to carry out parameter read and write function.

If the value is set to a parameter number that does not exist in the drive, an exception response will be received.

### *4.6.2. Register 45: Drive Parameter Value*

When reading this register, the value represents the value of the parameter specified by register 44.

When writing to this register, the value will be written to the drive parameter number specified by register 44.

If the value written to a parameter is outside of the parameter range, an exception response will be received.

### *4.6.3. Parameter Read Method*

To read a parameter, firstly write the parameter number to register 44, then read the value from register 45, e.g. to Read the Value of P-01.

- Write 1 to Register 44.
- Read the Value of Register 45.

### *4.6.4. Parameter Write Method*

Writing parameter values can be achieved by the same method, however, register 45 is used to write the parameter value after the parameter number has been selected using Register 44, e.g. to Write a Value of 60.0Hz to parameter P-01.

- Write 1 to Register 44.
- Register 45 will return the present value of P-01, which can be Read if required.
- Referring to the Programming Guide, apply any scaling necessary
  - In this case, 60.0Hz = 3600.
- Write the scaled value to Register 45. P-01 now changes to 60.0Hz, or an exception code may be returned.

# 5. CAN

## 5.1. Overview

The CAN communication profile is implemented according to the specification DS301 version 4.02 of CAN in automation (www.can-cia.de). Specific device profiles such as DS402 are not supported.

CAN communication is enabled by default however to use any control functions parameter P-12 must be set to 7 or 8. Refer to the Programming Guide for further Information.

## 5.2. CAN Communication Configuration Parameter

The CAN communication baud rate can be set by using parameter P-36. Available baud rates are: 125kbps, 250kbps, 500kbps, 1Mbps. (with default settings as 500kbps).

The Node ID is set up through drive address parameter P-36 as well with the default value of 1.

## 5.3. CAN COB-ID

The following default COB-ID and functions are supported:

| Type | COB-ID | Function |
|---|---|---|
| NMT | 000h | Network management. |
| Sync | 080h | Synchronous message.<br>COB-ID can be configured to other value. |
| Emergency | 080h + Node address | Emergency message. |
| PDO1 (TX) | 180h + Node address | Process data object.<br>PDO1 is pre-mapped and enabled by default.<br>COB-ID can be configured to other value.<br>PDO2 is pre-mapped and disabled by default.<br>Transmission mode, COB-ID and mapping can be configured. |
| PDO1 (RX) | 200h + Node address | |
| PDO2 (TX) | 280h + Node address | |
| PDO2 (RX) | 300h + Node address | |
| SDO (TX) | 580h + Node address | SDO channel can be used for drive parameter access. |
| SDO (RX) | 600h + Node address | |
| Error Control | 700h + Node address | Guarding and Heartbeat function are supported.<br>COB-ID can be configured to other value. |

**NOTE**

- The SDO channel only supports expedited transmission.
- A maximum of 2 Process Data Objects (PDO) are supported.
  - All PDOs are pre-mapped; however, PDO2 is disabled by default
  - The table below gives the default PDO mapping information.
- Customer configuration (mapping) will **NOT** be saved during power down. This means that the CAN configuration will restore to its default condition each time the drive is powered up.

## 5.4. PDO Default Mapping

| | Objects No. | Mapped Object | Length | Mapped Function | Transmission Type | For information on the values |
|---|---|---|---|---|---|---|
| RX PDO1 | 1 | 2000h | Unsigned 16 | Control word | 254 Valid immediately | Refer to section *11.1. Control Registers on page 54* |
| | 2 | 2001h | Integer 16 | Frequency setpoint | | |
| | 3 | 2003h | Unsigned 16 | User ramp reference | | |
| | 4 | 0006h | Unsigned 16 | Dummy | | |
| TX PDO1 | 1 | 200Ah | Unsigned 16 | Drive status register | 254 Send after receiving RX PDO 1 | Refer to section *11.1.1. Drive Control Word PDO0 on page 54* |
| | 2 | 200Bh | Integer 16 | Motor speed Hz | | |
| | 3 | 200Dh | Unsigned 16 | Motor current | | |
| | 4 | 2010h | Integer 16 | Drive temperature | | |
| RX PDO2 | 1 | 0006h | Unsigned 16 | Dummy | 254 | |
| | 2 | 0006h | Unsigned 16 | Dummy | | |
| | 3 | 0006h | Unsigned 16 | Dummy | | |
| | 4 | 0006h | Unsigned 16 | Dummy | | |
| TX PDO2 | 1 | 2011h | Unsigned 16 | DC bus voltage | 254 | |
| | 2 | 2012h | Unsigned 16 | Digital input status | | |
| | 3 | 2013h | Integer 16 | Analog input 1 (%) | | |
| | 4 | 2014h | Integer 16 | Analog input 2 (%) | | |

## 5.5. PDO Transmission Type

Various transmission modes can be selected for each PDO. For RX PDO, the following modes are supported:

| Transmission Type | Mode | Description |
|---|---|---|
| 0 – 240 | Synchronous | The received data will be transferred to the drive active control register when the next sync message is received. |
| 254, 255 | Asynchronous | The received data will be transferred to the drive active control register immediately without delay. |

For TX PDO, the following modes are supported:

| Transmission Type | Mode | Description |
|---|---|---|
| 0 | Acyclic synchronous | TX PDO will only be sent out if the PDO data has changed and PDO will be transmitted on reception of SYNC object. |
| 1-240 | Cyclic synchronous | TX PDO will be transmitted synchronously and cyclically. The transmission type indicates the number of SYNC object that are. |
| 254 | Asynchronous | TX PDO will only be transferred once corresponding RX PDO has been received. |
| 255 | Asynchronous | TX PDO will only be transferred anytime if PDO data value has changed. |

## 5.6. CAN Specific Object Table

| Index | Sub Index | Function | Access | Type | PDO Map | Default Value |
|---|---|---|---|---|---|---|
| 1000h | 0 | Device Type | RO | U32 | N | 0 |
| 1001h | 0 | Error Register | RO | U8 | N | 0 |
| 1002h | 0 | Manufacturer Status Register | RO | U16 | N | 0 |
| 1005h | 0 | COB-ID Sync | RW | U32 | N | 00000080h |
| 1008h | 0 | Manufacturer Device Name | RO | String | N | ODE3 |
| 1009h | 0 | Manufacturer Hardware Version | RO | String | N | x.xx |
| 100Ah | 0 | Manufacturer Software Version | RO | String | N | x.xx |
| 100Ch | 0 | Guard Time (1ms) | RW | U16 | N | 0 |
| 100Dh | 0 | Lifetime Factor | RW | U8 | N | 0 |
| 1014h | 0 | COB-ID EMCY | RW | U32 | N | 00000080h+Node ID |
| 1015h | 0 | Inhibit Time Emergency (100µs) | RW | U16 | N | 0 |

| Index | Sub Index | Function | Access | Type | PDO Map | Default Value |
|---|---|---|---|---|---|---|
| 1016h | 0 | Consumer Heartbeat Time No. of entries | RO | U8 | N | 1 |
| | 1 | Consumer Heartbeat Master Node & Time | RW | U32 | N | 0 |
| 1017h | 0 | Producer Heartbeat Time (1ms) | RW | U16 | N | 0 |
| 1018h | 0 | Identity Object No. Of entries | RO | U8 | N | 4 |
| | 1 | Vendor ID | RO | U32 | N | 0x0000031A |
| | 2 | Product Code | RO | U32 | N | Drive Dependent |
| | 3 | Revision Number | RO | U32 | N | x.xx |
| | 4 | Serial Number | RO | U32 | N | Drive Dependent |
| 1200h | 0 | SDO Parameter No. Of entries | RO | U8 | N | 2 |
| | 1 | COB-ID Client -> Server (RX) | RO | U32 | N | 00000600h+Node ID |
| | 2 | COB-ID Server -> Client (TX) | RO | U32 | N | 00000580h+Node ID |
| 1400h | 0 | RX PDO1 comms param. no. of entries | RO | U8 | N | 2 |
| | 1 | RX PDO1 COB-ID | RW | U32 | N | 40000200h+Node ID |
| | 2 | RX PDO transmission type | RW | U32 | N | 254 |
| 1401h | 0 | RX PDO2 comms param. no. of entries | RO | U8 | N | 2 |
| | 1 | RX PDO2 COB-ID | RW | U32 | N | C0000300h+Node ID |
| | 2 | RX PDO2 transmission type | RW | U8 | N | 0 |
| 1600h | 0 | RX PDO1 1 mapping / no. of entries | RW | U8 | N | 4 |
| | 1 | RX PDO1 1st mapped object | RW | U32 | N | 20000010h |
| | 2 | RX PDO1 2nd mapped object | RW | U32 | N | 20010010h |
| | 3 | RX PDO1 3rd mapped object | RW | U32 | N | 20030010h |
| | 4 | RX PDO1 4th mapped object | RW | U32 | N | 00060010h |
| 1601h | 0 | RX PDO2 1 mapping / no. of entries | RW | U8 | N | 4 |
| | 1 | RX PDO2 1st mapped object | RW | U32 | N | 00060010h |
| | 2 | RX PDO2 2nd mapped object | RW | U32 | N | 00060010h |
| | 3 | RX PDO2 3rd mapped object | RW | U32 | N | 00060010h |
| | 4 | RX PDO2 4th mapped object | RW | U32 | N | 00060010h |
| 1800h | 0 | TX PDO1 comms parameter number of entries | RO | U8 | N | 3 |
| | 1 | TX PDO1 COB-ID | RW | U32 | N | 40000180h+Node ID |
| | 2 | TX PDO1 transmission type | RW | U8 | N | 254 |
| | 3 | TX PDO1 Inhibit time (100µs) | RW | U16 | N | 0 |
| 1801h | 0 | TX PDO2 comms param no. of entries | RO | U8 | N | 3 |
| | 1 | TX PDO2 COB-ID | RW | U32 | N | C0000280h+Node ID |
| | 2 | TX PDO2 transmission type | RW | U8 | N | 0 |
| | 3 | TX PDO2 Inhibit time (100µs) | RW | U16 | N | 0 |
| 1A00h | 0 | TX PDO1 mapping / no. of entries | RW | U8 | N | 4 |
| | 1 | TX PDO1 1st mapped object | RW | U32 | N | 200A0010h |
| | 2 | TX PDO1 2nd mapped object | RW | U32 | N | 200B0010h |
| | 3 | TX PDO1 3rd mapped object | RW | U32 | N | 200D0010h |
| | 4 | TX PDO1 4th mapped object | RW | U32 | N | 20100010h |
| 1A01h | 0 | TX PDO2 mapping / no. of entries | RW | U8 | N | 4 |
| | 1 | TX PDO2 1st mapped object | RW | U32 | N | 20110010h |
| | 2 | TX PDO2 2nd mapped object | RW | U32 | N | 20120010h |
| | 3 | TX PDO2 3rd mapped object | RW | U32 | N | 20130010h |
| | 4 | TX PDO2 4th mapped object | RW | U32 | N | 20140010h |

## 5.7. Parameter Access

All user adjustable parameters are accessible through the CAN communication interface. The Programming Guide document provides the Index for each parameter along with any scaling or information how the data for each parameter is stored.

## 5.8. Additional Status Indices

Further additional status Indices are present in the drive. These are described in section *11. Control & Status Registers on page 54.*

# 6. Ethernet Connection

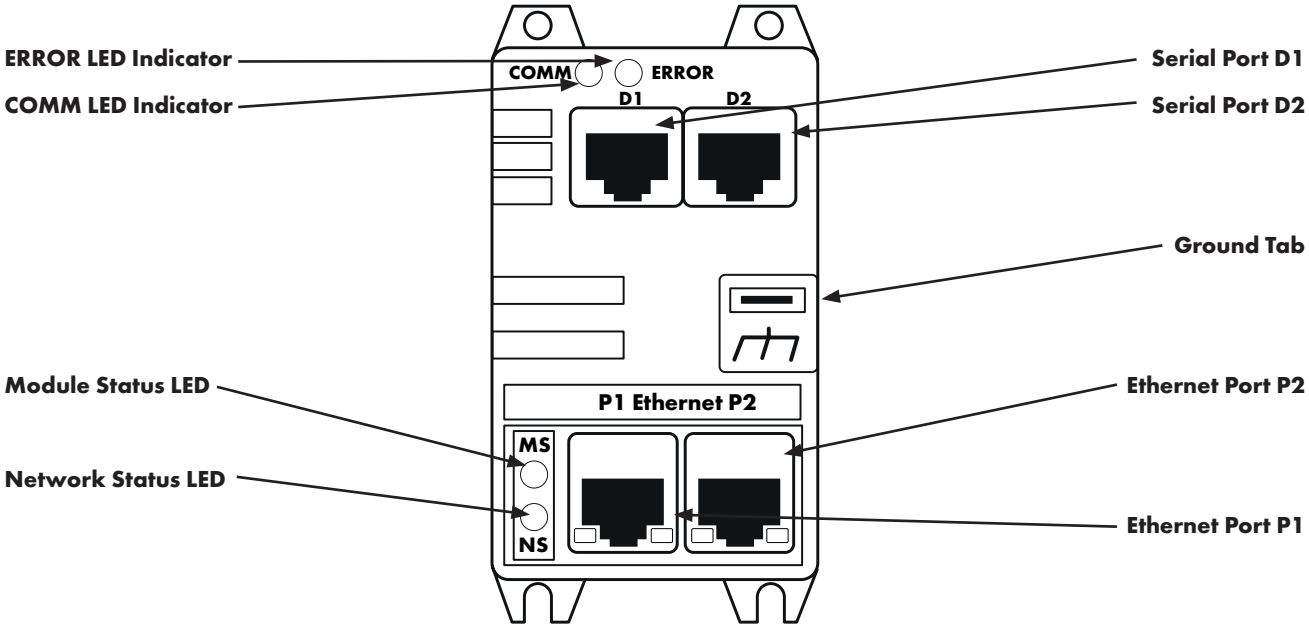
## 6.1. Available Interface Options

Ethernet interfaces are optionally available for Optidrive E3 and Optidrive Compact 2 products which support either Ethernet/IP protocol or Modbus TCP protocol. Part numbers for these interfaces are shown in the table below. The correct interface should be selected according to the drive type.

| Drive Family | Interface Type | Ethernet/IP Interface Model Code | Modbus TCP Interface Model Code |
|---|---|---|---|
| Optidrive E3 IP20 | External Option | OPT-2-ETHEG-IN | OPT-3-MTPEG-IN |
| Optidrive E3 IP66 | Internal Option | Drive Model Code + "-EIP" | Drive Model Code + "-MTP" |
| Optidrive Compact 2 | Plug in Option | OPT-2-ETHIG-IN | OPT-2-MTPEG-IN |

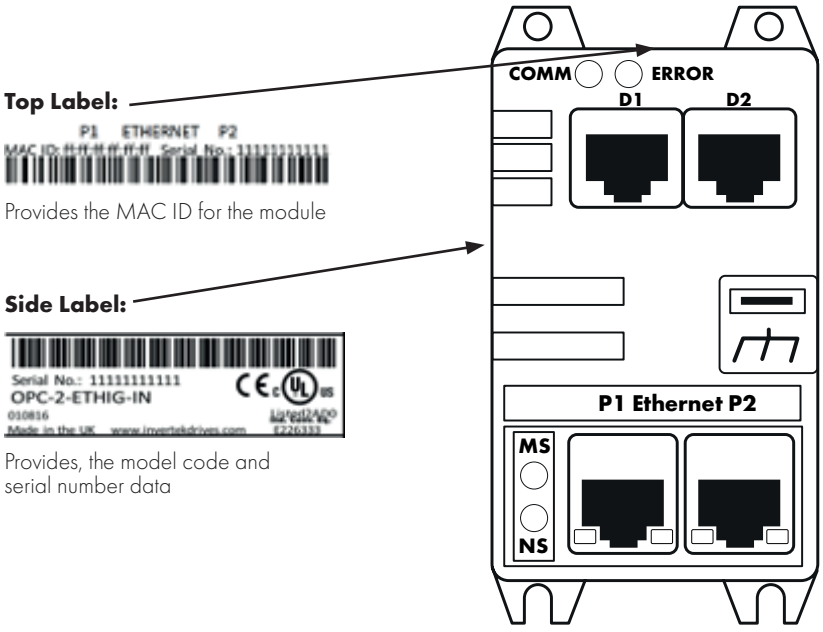
## 6.2. External Interface

### *6.2.1. Layout*



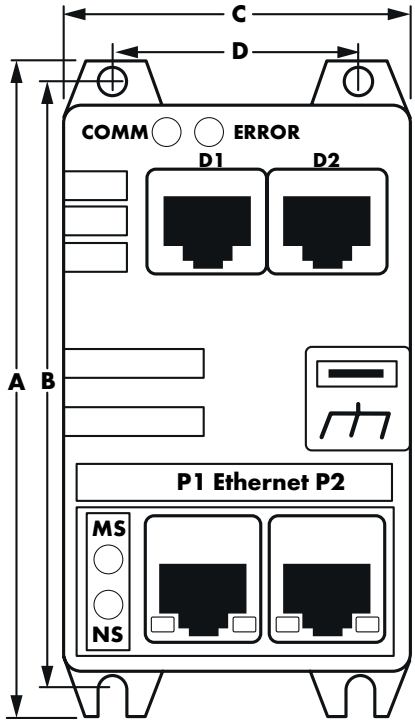

### *6.2.2. Labelling*

There are two labels:



### *6.2.3. Mechanical Installation*

- The Ethernet IP interface is intended for mounting inside a control cabinet adjacent to the drive.
- The unit should be mounted in a vertical position only, on a flat, flame resistant, vibration free mounting.
- The unit must be installed in a pollution degree 1 or 2 environment only.
- Use the module as a template to mark the locations for drilling the mounting screws.
- Drill and tap the holes as required.
- Secure the unit to the backplate using suitable screws, 1Nm.




| A | | B | | C | | D | | Weight | |
|---|---|---|---|---|---|---|---|---|---|
| mm | in | mm | in | mm | in | mm | in | g | oz |
| 89 | 3.50 | 76 | 2.99 | 47 | 1.85 | 31 | 1.22 | 65 | 2.29 |

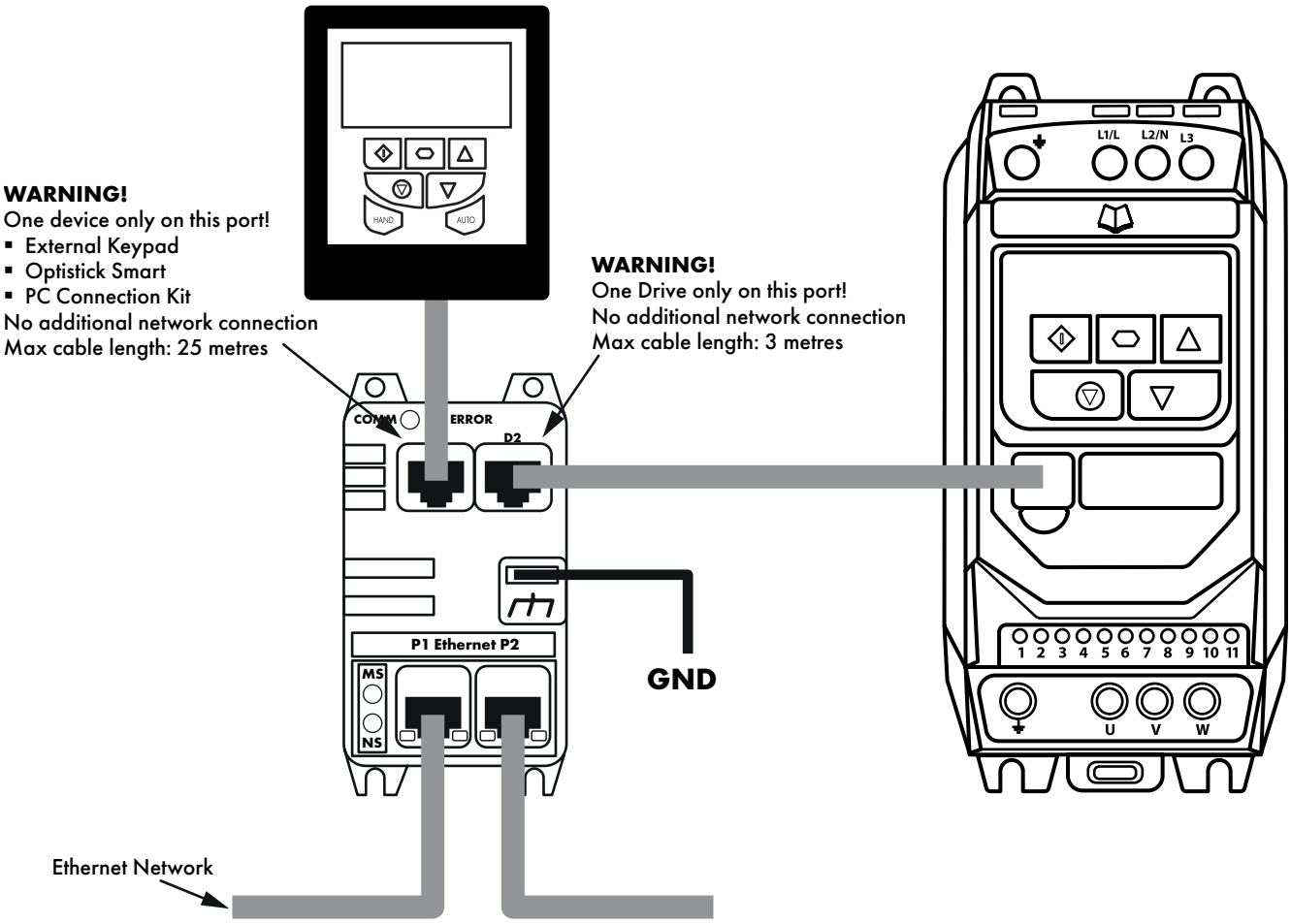
| Mounting Bolts | |
|---|---|
| Metric | UNF |
| M4 | #8 |

### *6.2.4. Electrical Installation*

**WARNING!** Do not connect Ethernet devices to ports D1 or D2. They may be damaged!

Power supply to the module is provided from the connected drive via the RJ45 connection.

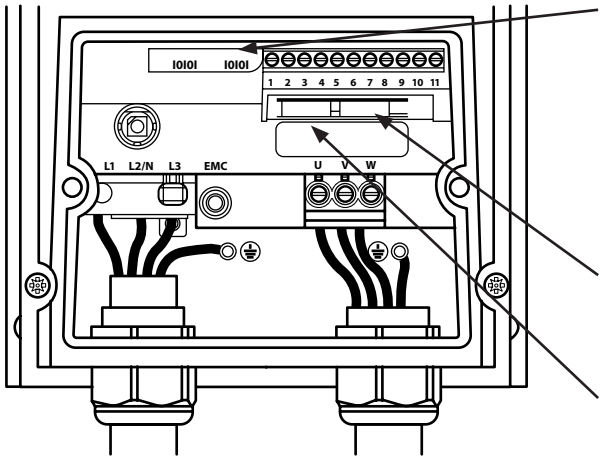
**WARNING!** Do not use cross over cables! Cables must be pin to pin connected!




Ground tab – Observe the recommended grounding procedure for the fieldbus network and if necessary, connect this tab to ground where required.

## 6.3. Internal Interface for IP66 Drives

### *6.3.1. Layout – Internal Interface*




**IOIOI: Dual serial ports.**

**WARNING! Do not connect Ethernet devices here!**

**These ports are for external serial connection of remote keypad and PC connection only!**

Port P1: Primary Ethernet port

Port P2: Secondary Ethernet Port

### *6.3.2. Labelling – Internal Interface*

The MAC address of the device is shown below the ports.

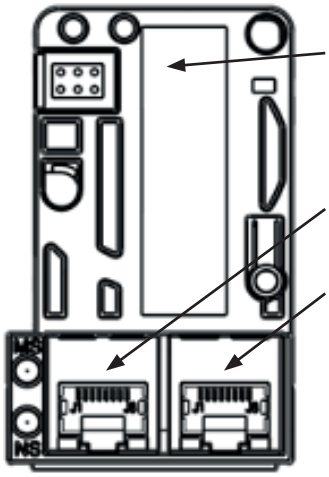
## 6.4. Optional Interface for Compact 2 Basic Drives

### *6.4.1. Installation*

The Ethernet/IP interface is mounted underneath the control pod.

- Remove the control pod as described in the Compact 2 installation guide.
- Locate the Ethernet/IP interface in the slot below the control pod.
- Refit the control pod.

### *6.4.2. Layout*




**WARNING! Do not connect Ethernet cables to the RJ45 port on the control Pod!**

## 6.5. Drive Parameter Settings

### *6.5.1. Overview*

The following parameter settings are required in the drive. For further description of the drive parameters, refer to the drive user guide.

| Drive Type | Optidrive E3 (ODE-3-...) | Setting |
|---|---|---|
| Parameter | | |
| Drive Address | P-36 Index 1 | 1 |
| Modbus RTU Baud Rate | P-36 Index 2 | 115.2kbps |
| Modbus RTU Data Format | N/A | N-1 |
| Communication Loss Reaction | P-36 Index 3 | As required |
| Command Source Selection | P-12 | Select for Fieldbus Control if control of the drive operation is required |

# 7. Internal Webserver

## 7.1. Overview

A web server interface is present in all Ethernet based fieldbus interfaces and can be accessed using the IP address or host name.

- Default IP address: 192.168.1.253.
- Hostname: OPCxxxxxxxxxx, where xxxxxxxxxx = 'PR ID' value shown on the top product label as described in section *6.2.2. Labelling on page 14* or *6.3.2. Labelling – Internal Interface on page 16*.

The IP address and Host Name may be reconfigured by the user via the Web Server or Ethernet/IP Class 0xF4.

## 7.2. Default Login

To access to the web server:

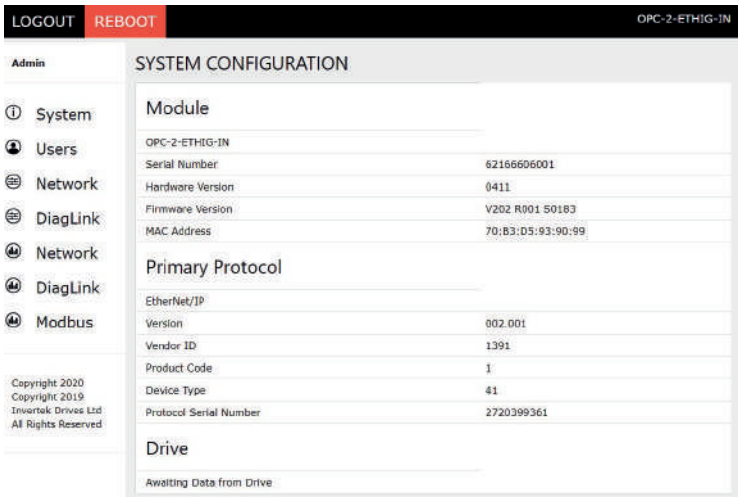
- Open a web browser on your connected PC.
- Enter the module IP address in the address bar.
- Default admin login details:
  - Username: **Admin**
- Password: **Serial Number** of the module (see product label as described in section *6.2.2. Labelling on page 14* or *6.3.2. Labelling – Internal Interface on page 16*.)

## 7.3. Web Server Contents

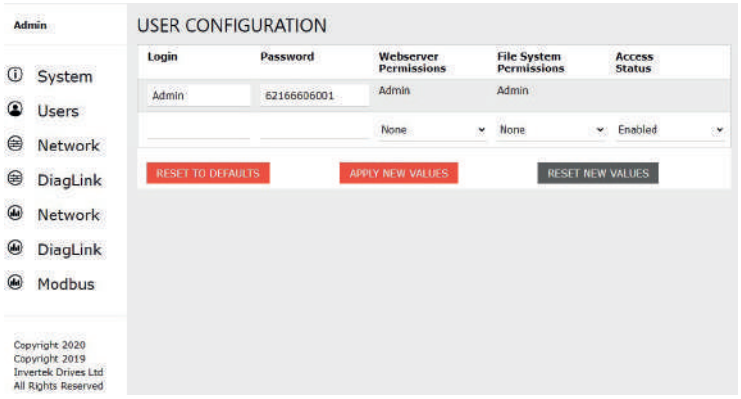
The web server contains 7 pages as described below.

### *7.3.1. System*

Information about the Module and Primary Protocol is displayed. This information is Read Only.



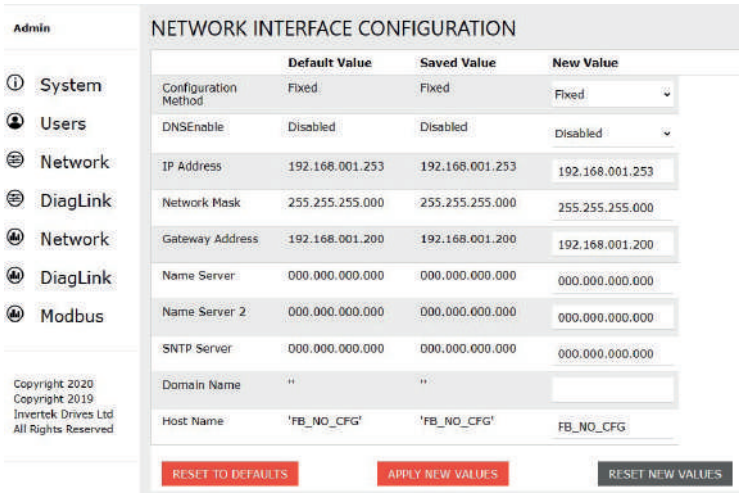

### *7.3.2. Users*




Information about user's accounts is displayed.

### *7.3.3. Network (IP Address and Network Settings)*

Information about network adapter configuration is displayed.



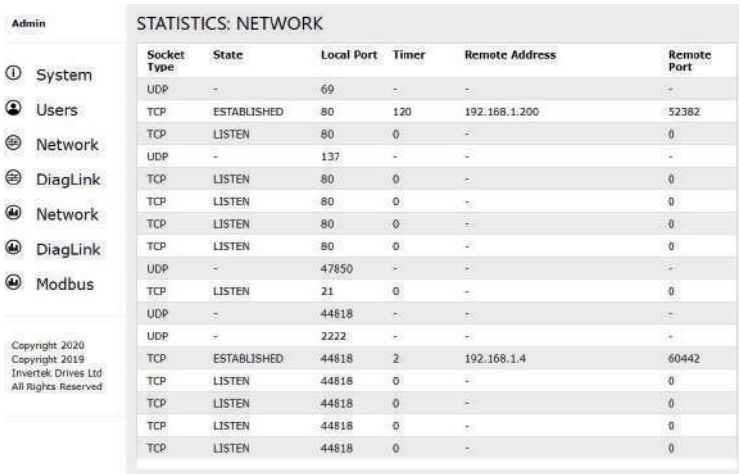

### *7.3.4. DiagLink (Ethernet Configuration Message)*

Information about the serial communication settings to the drive are displayed.



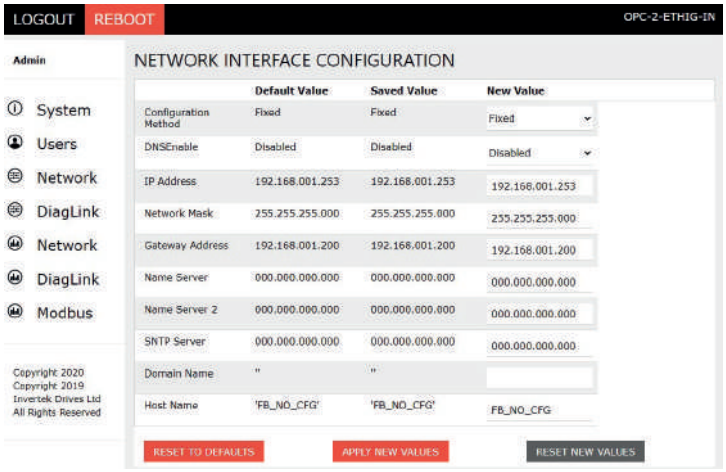

### *7.3.5. Network (Ethernet Network Statistics)*

Statistic information about the ethernet connections is displayed.



## 7.4. Changing the IP Address

Go to **Network** settings screen:

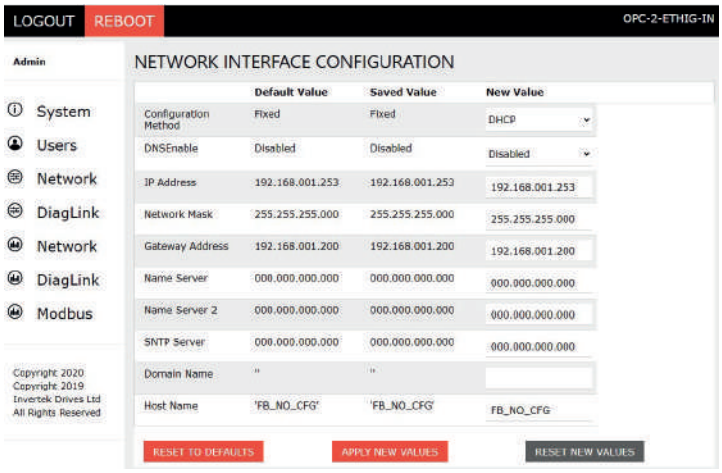



The IP address can be assigned to the module manually by the User (Fixed or Static IP Address) or automatically by the DHCP Server. The default configuration method is Fixed IP address.

### *7.4.1. Automatically (DHCP) Assigned IP Address*

To automatically (DHCP) assign an IP address to the module please select **DHCP** mode in the **Configuration Method** and confirm changes by clicking **APPLY NEW VALUES**.

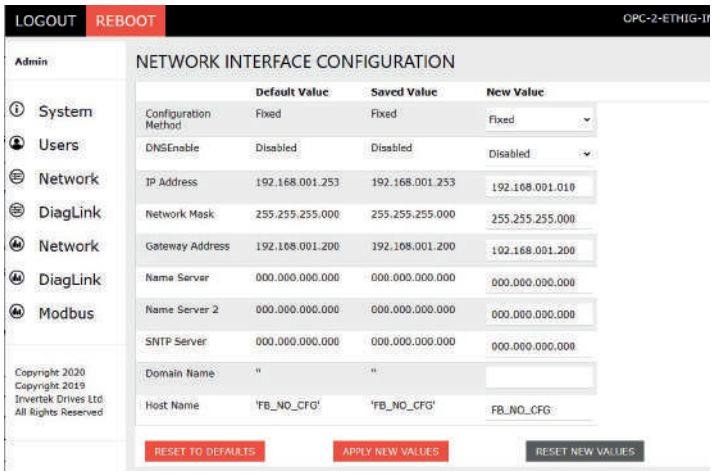
**NOTE** A power cycle is necessary after changing the network settings. Please click REBOOT button at the top left corner or power cycle the module!



### *7.4.2. Manually Assigned IP Address*

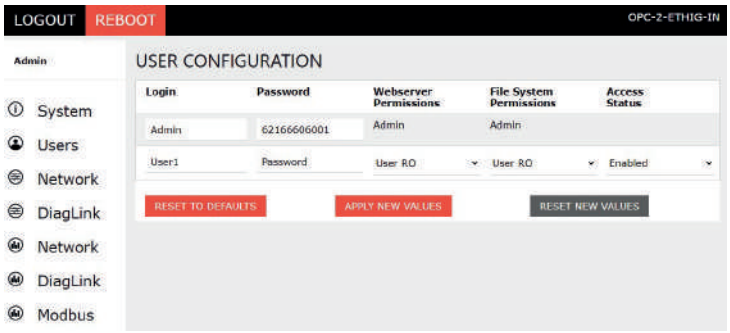
To manually set up the module IP address, please select **Fixed** mode in the **Configuration Method**, type new values in required fields in column New Value as shown below and confirm changes by clicking **APPLY NEW VALUES**.

**NOTE** A power cycle is necessary after changing the network settings. Please click REBOOT button at the top left corner or power cycle the module!

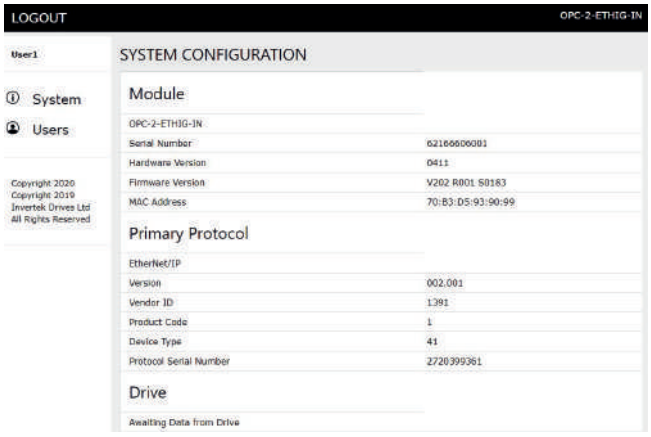



## *7.5. Creating an Additional User Account for Limited Access*

It is possible to change admin password and create second User with its own login, password, permissions, and limited access if required. To create new user, you need to add new login details (login and password) and defined the access levels (permissions) for this user.




User with permissions like above, will have a limited access to the module data and settings as shown below.



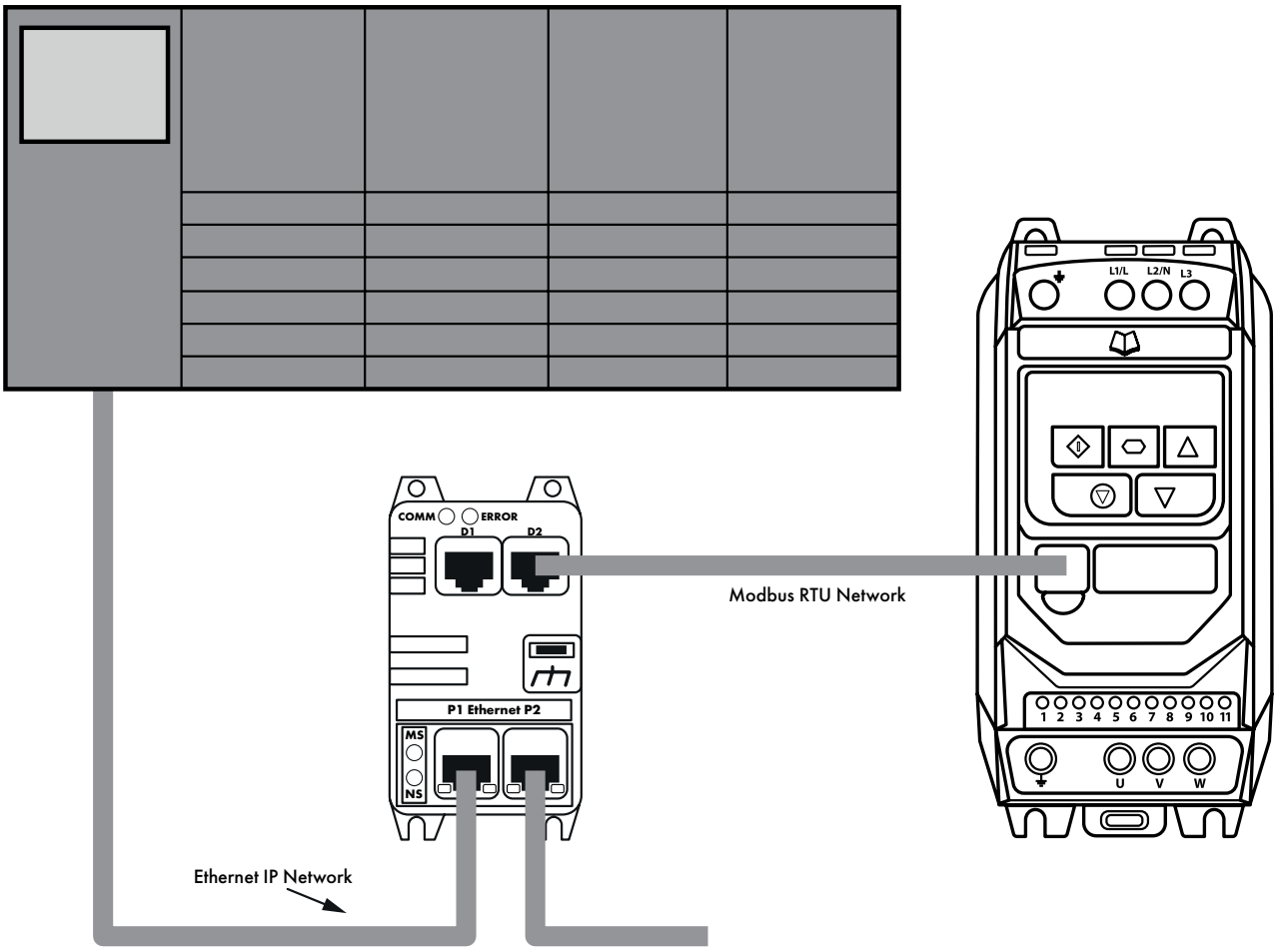

**NOTE** Default user account is still valid in addition to the second user account!

# 8. Ethernet/IP Communication

## 8.1. Overview

The Ethernet/IP interface is a CIP Modbus Translator Device (CIP Type 29) providing access to a virtual Modbus device (CIP Type 28h) defined according to CIP Volume 7 specification.

## 8.2. Operation




Messages are not sent to the Ethernet Interface, rather they are sent to the drive through the interface. The interface provides a translation from the Ethernet/IP network to the Modbus sub network and therefore to the drive. In order for this to operate successfully, the PLC needs to send the message along with the necessary routing information. This procedure is detailed in the following sections.

## 8.3. Usage Requirement

- To fully use the functionality of the Ethernet/IP Modbus translator requires a compatible Network Master device that supports use with a Modbus Translator Device (CIP Type 29) defined according to CIP Specification.
  - o Alternatively, the device may be support as a Generic CIP Bridge Device which supports cyclic communication only.
  - o Consult your PLC / Control Device vendor to determine compatibility.
- When using the device to control the drive it is necessary to ensure that the amount of data and frequency of data exchange does not exceed the amount of data which can be successfully exchanged on the Modbus sub-network within the permitted time.
  - o Recommended minimum RPI is 100ms.
  - o When Acyclic telegrams are exchanged, Cyclic telegrams should be paused.
- Whilst the Optitools Studio PC software supports communication through the Ethernet network for device commissioning, it is not recommended to use this continuously during operation of the drive as the additional communication load may exceed the limit resulting in loss of Cyclic communication.
  - o In this case, connect the PC software to the drive serial port using the USB / RS485 adaptor.
    - Use port D1 or D2 of the external Ethernet adaptor.
    - Use port D1 or D2 of the Compact 2 Ethernet adaptor.
    - Use one of the available ports labelled "IOIOI".
  - o Do not connect via Ethernet if data logging is required.

## 8.4. Operation

Cyclic control and monitoring of the drive is achieved by a Class 1 connection to the mapped Modbus PDI and PDO parameters. This can be achieved using one of the following methods.

### *8.4.1. Configuration*

The interface supports the following Ethernet/IP classes:

- 0x01 Identity
- 0x02 Message Router
- 0x06 Connection manager
- 0x45 Modbus Serial
- 0xF4 Port
- 0xF5 TCP/IP
- 0xF6 Ethernet Link

### *8.4.2. IP Address*

The default IP address is 192.168.1.253, Subnet Mask 255.255.255.0

IP configuration can be changed using:

- The TCP/IP Class 0xF5. Values will not be applied until an Identity Class 0x01 reset is executed
- Via the internal webserver interface. Please refer to section *7.4. Changing the IP Address on page 20* for more information..

## 8.5. Process Data Exchange (cyclic communication)

For simple connection and control it is recommended to use the 4-word input, 4-word output process data exchange to allow control and monitoring of the drive.

In this case the 4 Control Words transferred to the drive correspond to Modbus Register addresses 1 – 4. Refer to section *11.1. Control Registers on page 54* for further information.

The 4 Status Words returned from the drive correspond to Modbus Registers 6 – 9. Refer to section *11.2. Standard Status Registers on page 55* for further information.

An optional Extended Status Information is also possible and defined within the EDS file which supports 16 Words of Status information. Refer to section *11.3. Extended Status Registers on page 56* for further information.

## 8.6. Configuring the Scanner

This section explains how to configure a communication exchange between the drive with Ethernet/IP interface (built-in or external one) and compatible controller with Ethernet/IP.

### *8.6.1. EDS File*

EDS files are available from the Invertek website, www.invertekdrives.com/variable-frequency-drives/options/communication-interfaces.

Multiple EDS files are included to support a variety of Master network devices, e.g., Rockwell Automation, Codesys. The EDS files contain the necessary path information to establish a connection as described below in further detail and may be used directly with compatible master systems.

#### 8.6.1.1. OPT-2-ETHEG-IN and Compact 2 Ethernet/IP

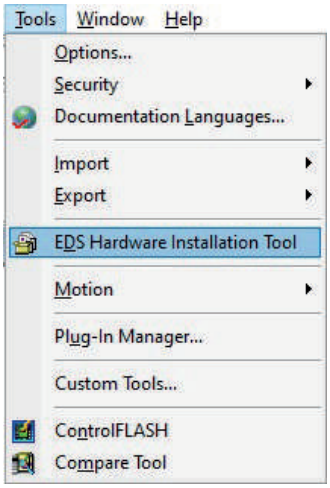
OPC-2-ETIG-IN V2.xx EDS file is dedicated for use with standalone Ethernet/IP Interface (OPT-2-ETHEG-IN) and the Compact 2 Ethernet/IP interface.

#### 8.6.1.2. ODE-3 IP66 Outdoor with built-in Ethernet/IP interface

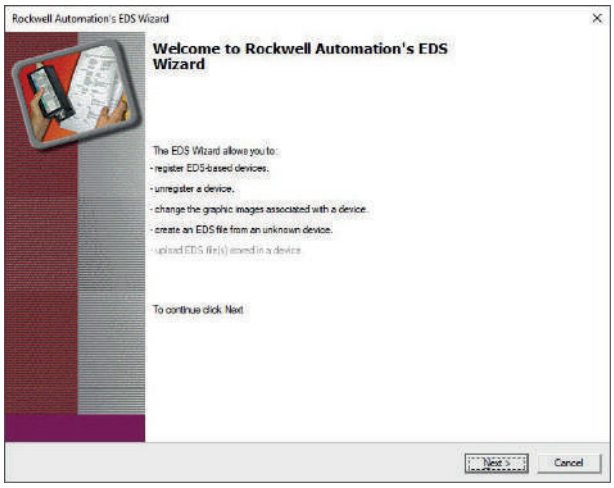
OPT-3-ETIG-IN V2.xx EDS file is dedicated for use with Optidrive E3 IP66 Outdoor with built-in Ethernet/IP interface.

### *8.6.2. Installing EDS files using Allen Bradley (Rockwell) Studio 5000 Logix Design*

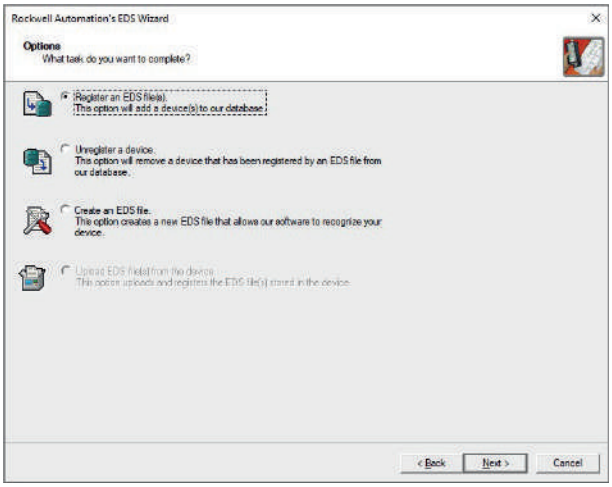
**Step 1.**
Open the EDS Hardware Installation Tool from Tools Tab



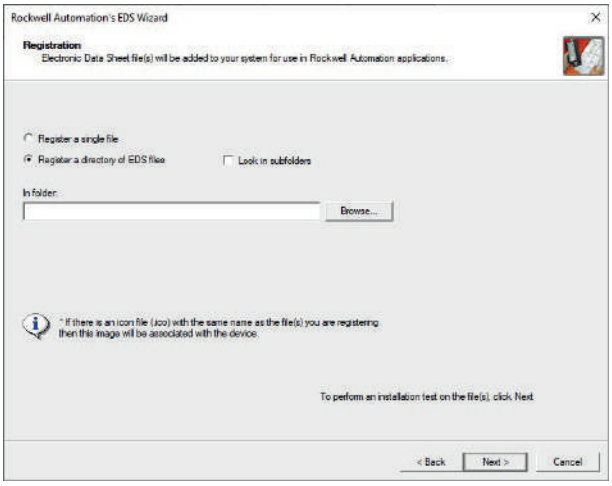

**Step 2.**
Starting the EDS Wizard



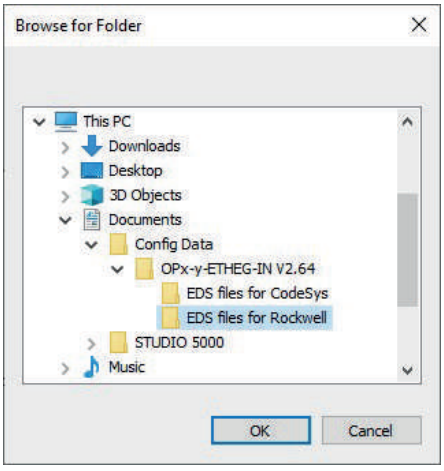

**Step 3.**
Select 'Register EDS file(s)' option



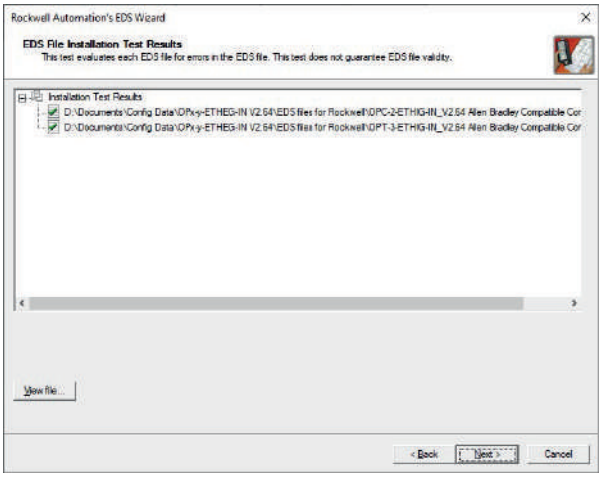

**Step 4.**
Select 'Register a directory of EDS files'



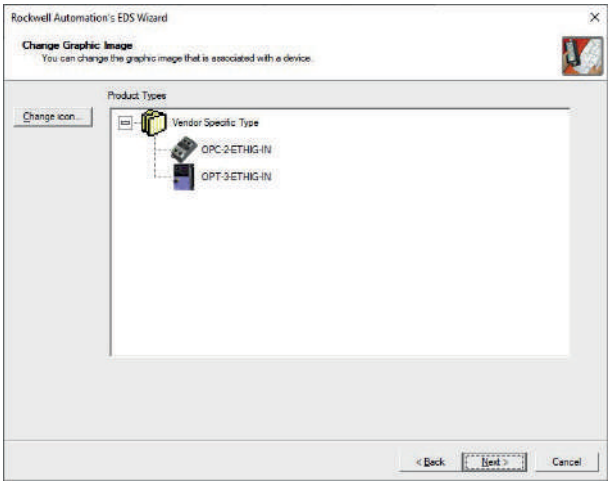

**Step 5.**
Select folder 'EDS files for Rockwell'



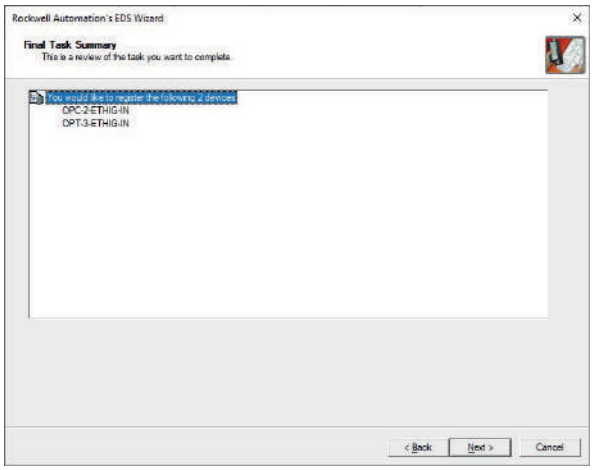

**Step 6.**
Confirm EDS File Installation Test Result



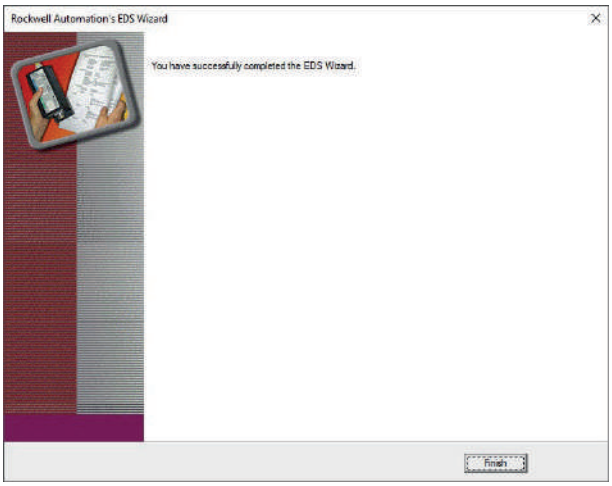
**Step 7.**
Confirm the Graphic Images




**Step 8.**
Confirm the Final Task Summary




**Step 9.**
Finish the EDS Wizard

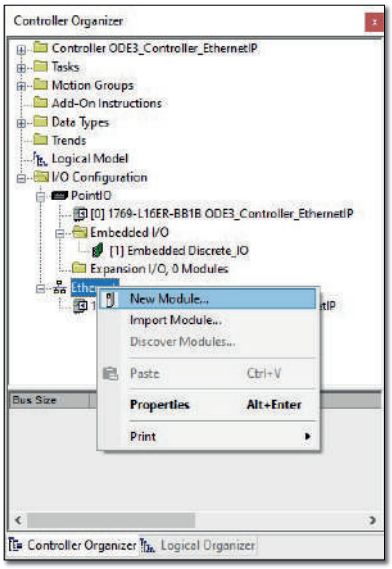


### 8.6.3. *Setting up the communication between the Rockwell Master and the Drive with Ethernet/IP Interface*

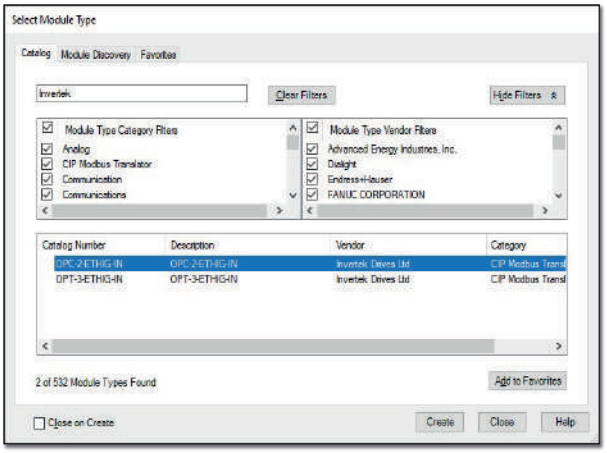
#### 8.6.3.1. Invertek's Standard Telegram (4 Words In / 4 Words Out)

#### 8.6.3.1.1. For use with OPT-2-ETHEG-IN (ODE-3 IP20 & IP66 Outdoor without Ethernet/IP interface) & OPT-2-ETHIG-IN plug in option for Compact 2

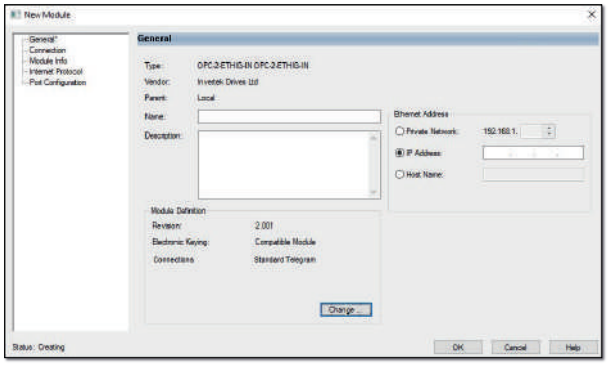
**Step 1.**
Add the New Module to the Ethernet/IP network
*Click the right button on the Ethernet (under the I/O Configuration) and add the New Module*



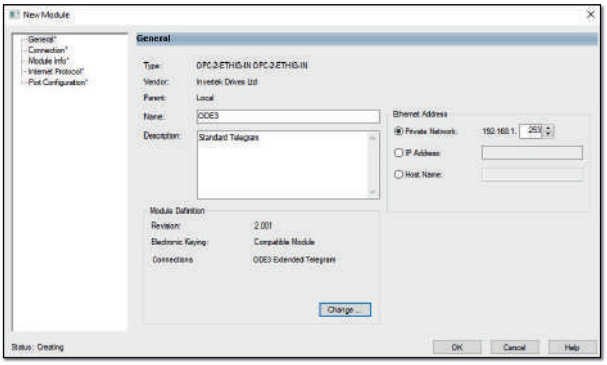

**Step 2.**
Search for Invertek devices in the Catalog View
*Select the OPC-2-ETHIG-IN device from the list*



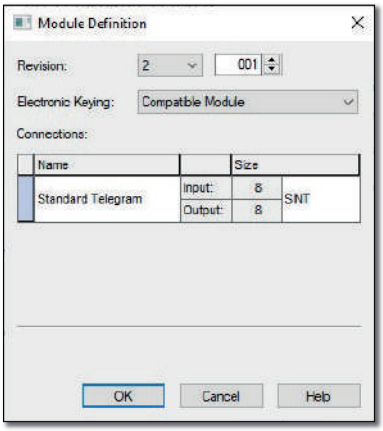

**Step 3.**
Assign the device Name and the IP Address to the Drive
*(Default IP Address of the module is 192.168.1.253)*



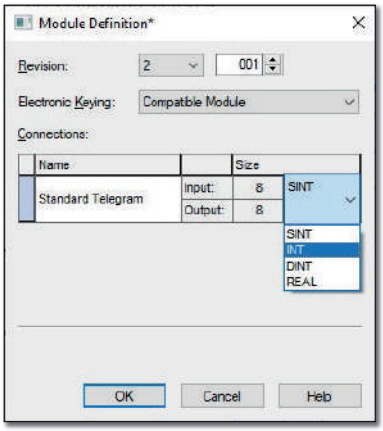

**Step 4.**
Click the *'Change...'* button in the Module Definition



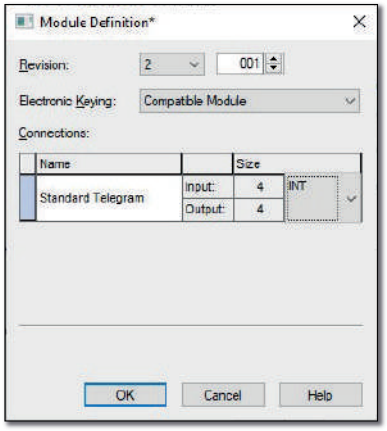

**Step 5.**
Change the data type
*Click the left button on the SINT field under the Size Tab*



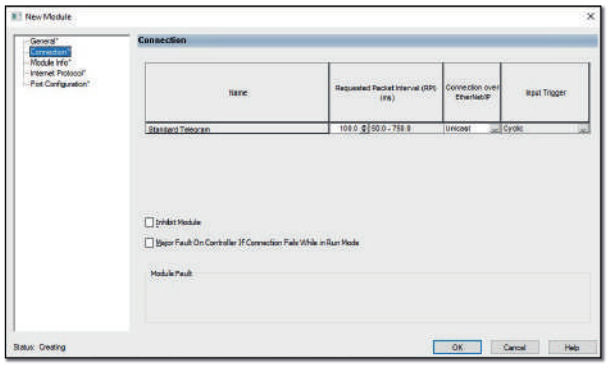

**Step 6.**
Select INT data type from the drop list



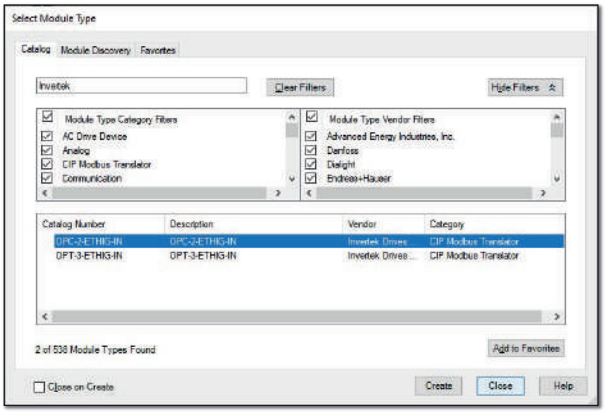
**Step 7.**
Confirm INT as the selected data type



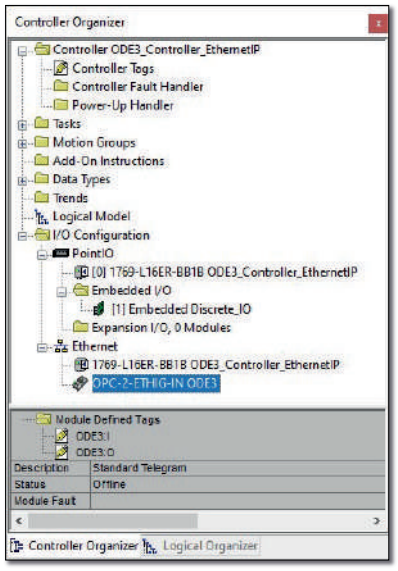

**Step 8.**
(Optional) Adjust the RPI time in the Connection tab
Click OK button to save your settings



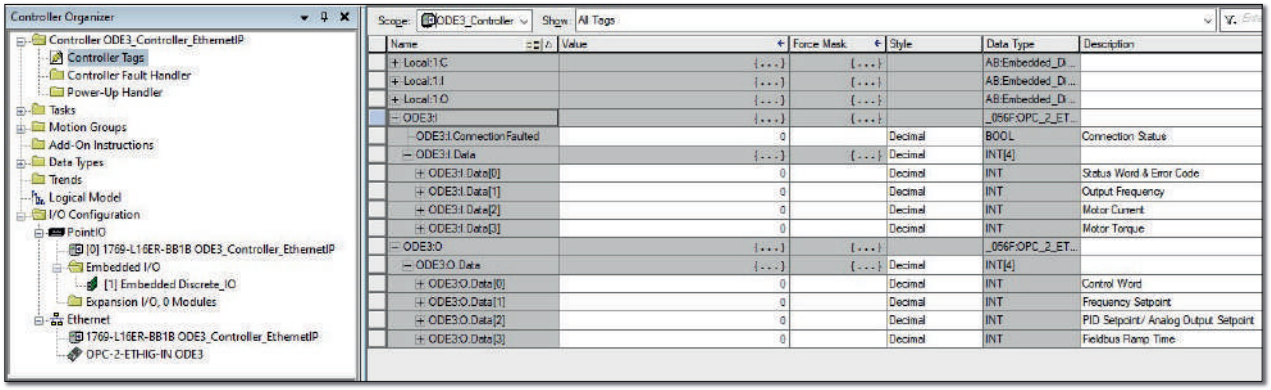

**Step 9.**
Close the Select Module Type Window




**Step 10.**
OPC-2-ETHIG-IN device will be added to the project

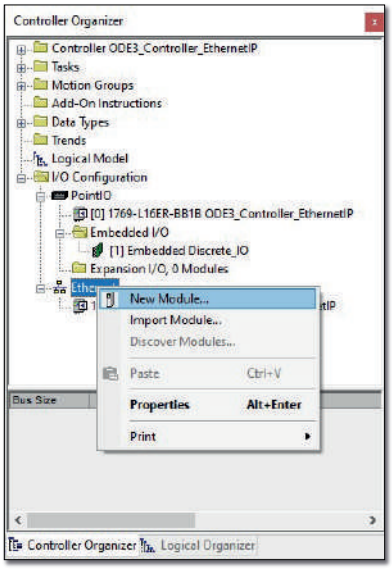



**Step 11.**
Drive tags created in the Controller Tags Window

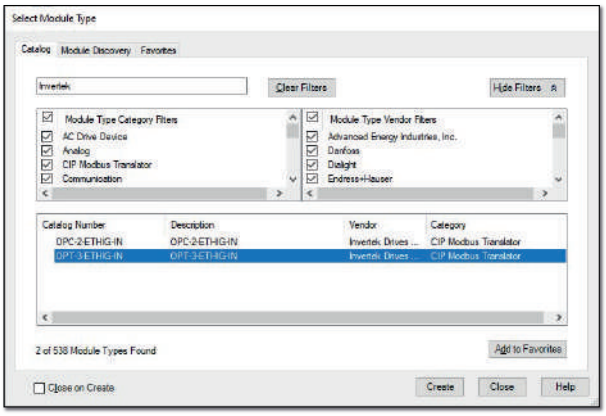


### 8.6.3.1.2. For use with ODE-3 IP66 Outdoor drives with built-in Ethernet/IP interface (Drive model code +"EiP").

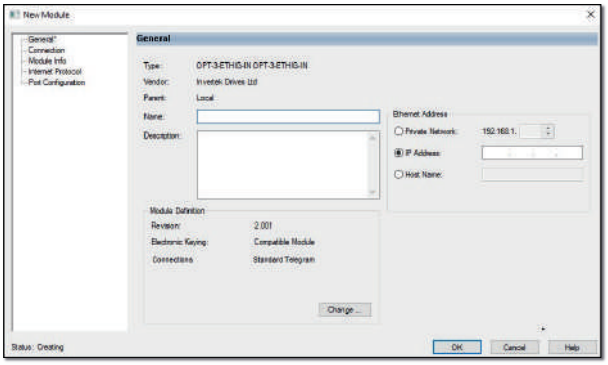
**Step 1.**
Add the New Module to the Ethernet/IP network
*Click the right button on the Ethernet (under the I/O Configuration) and add the New Module*



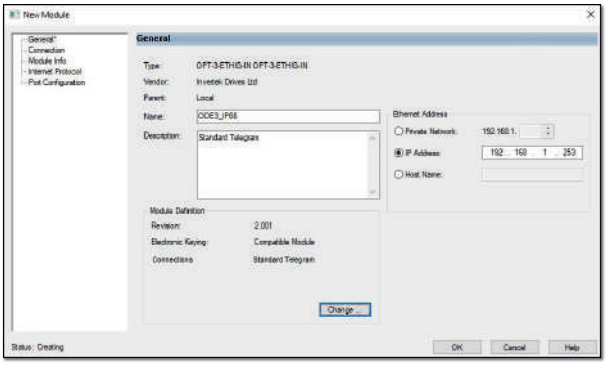

**Step 2.**
Search for Invertek devices in the Catalog View
*Select the OPT-3-ETHIG-IN device from the list*



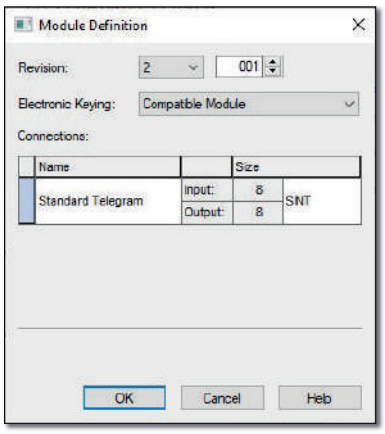

**Step 3.**
Assign the device Name and the IP Address to the Drive
*(Default IP Address of the module is 192.168.1.253)*



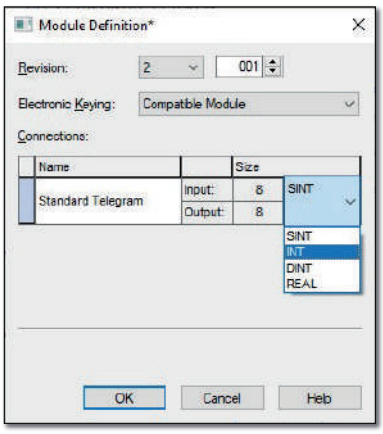

**Step 4.**
Click the *'Change...'* button in the Module Definition.



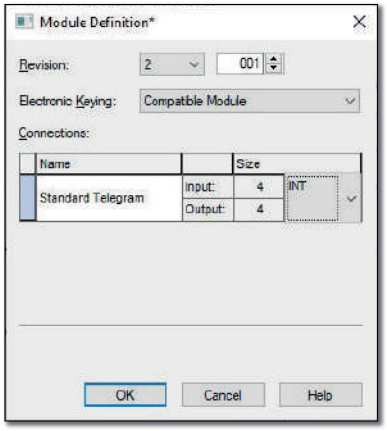

**Step 5.**
Change the data type
*Click the left button on the SINT field under the Size Tab*



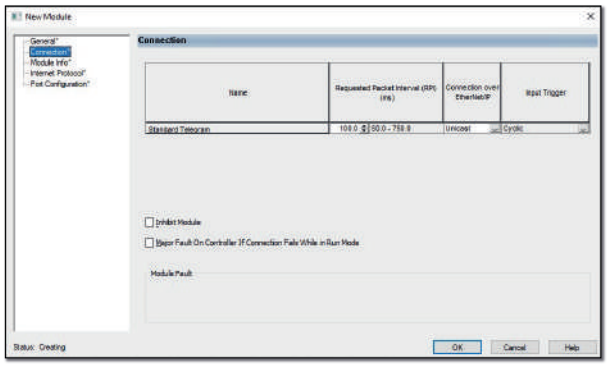

**Step 6.**
Select INT data type from the drop list



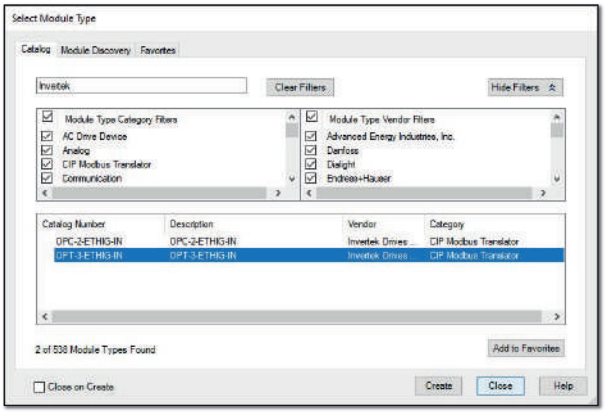
**Step 7.**
Confirm INT as the selected data type



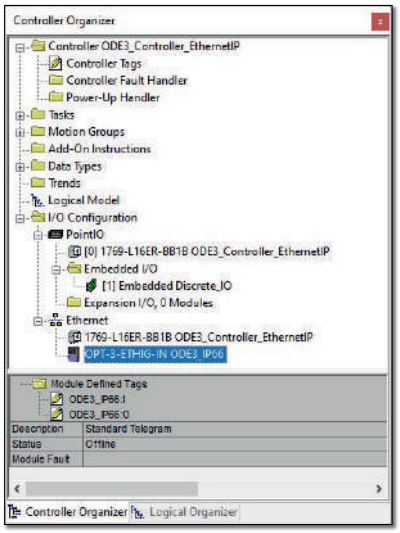

**Step 8.**
(Optional) Adjust the RPI time in the Connection tab
Click OK button to save your settings



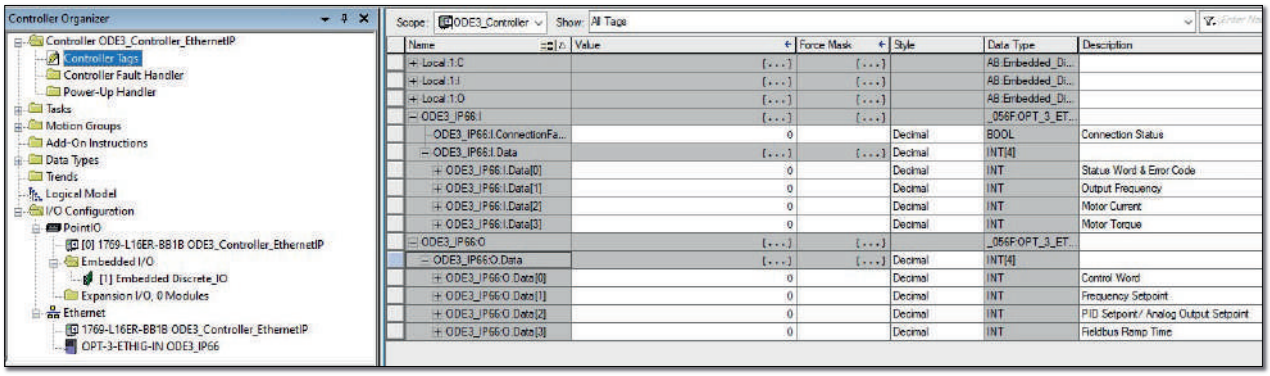

**Step 9.**
Close the Select Module Type Window




**Step 10.**
OPT-3-ETHIG-IN device will be added to the project



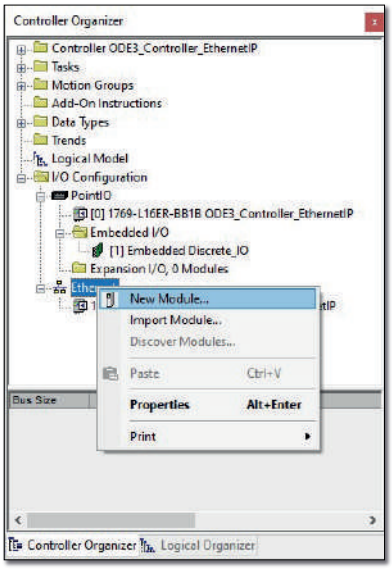

**Step 11.**
Drive tags created in the Controller Tags Window



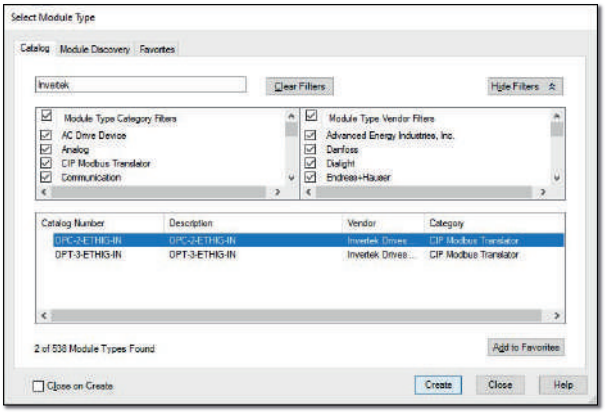
### 8.6.3.2. ODE-3 Extended Status Information (4 Words In / 16 Words Out)

#### 8.6.3.2.1. For use with OPT-2-ETHEG-IN (ODE-3 IP20 & IP66 Outdoor without Ethernet/IP interface) & OPT-2-ETHIG-IN plug in option for Compact 2.

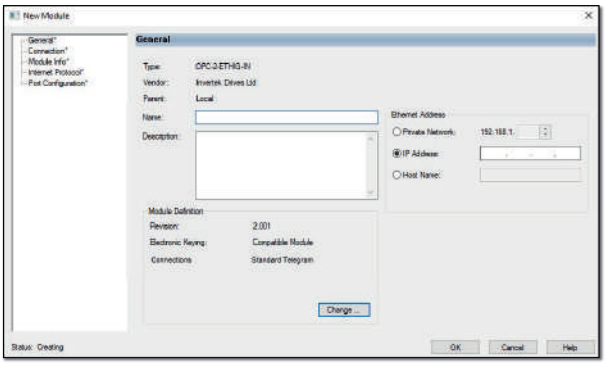
**Step 1.**
Add the New Module to the Ethernet/IP network
*Click the right button on the Ethernet (under the I/O Configuration) and add the New Module*



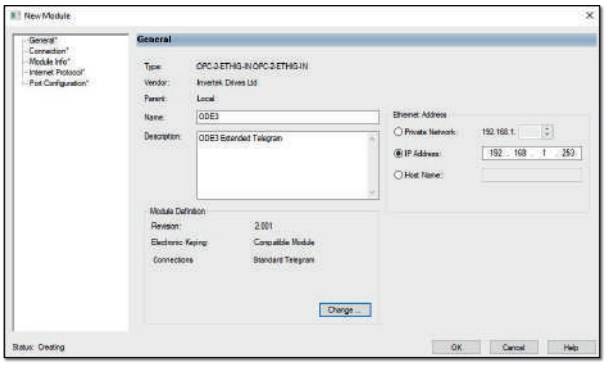

**Step 2.**
Search for Invertek devices in the Catalog View
*Select the OPC-2-ETHIG-IN device from the list*



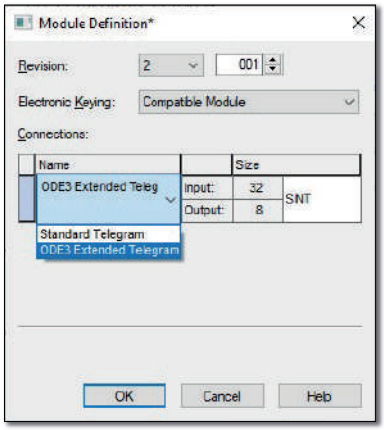

**Step 3.**
Assign the device Name and the IP Address to the Drive
*(Default IP Address of the module is 192.168.1.253)*



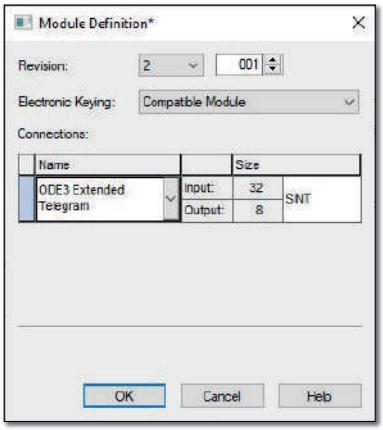

**Step 4.**
Click the *'Change...'* button in the Module Definition




**Step 5.**
Chang the Connection type
*Click the left button under the Name tab on the Standard Telegram field*

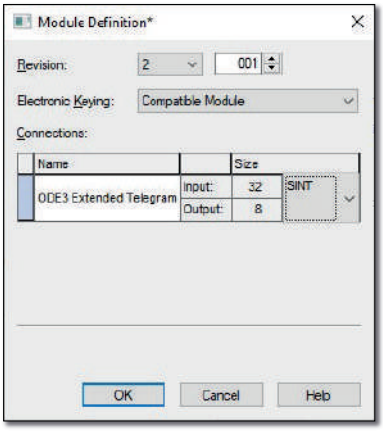



**Step 6.**
Select ODE3 Extended Telegram form the drop list as the Connection

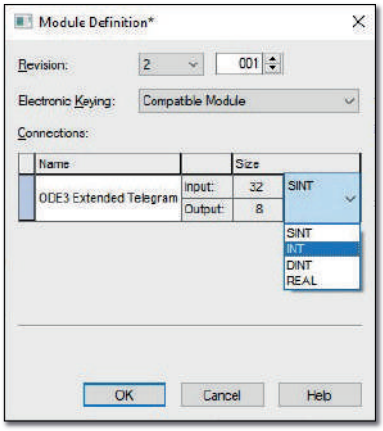


**Step 7.**
Change the data type

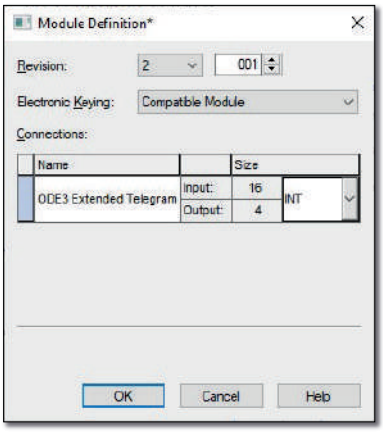
*Click the left button on the SINT field under the Size Tab*




**Step 8.**
Select INT data type from the drop list

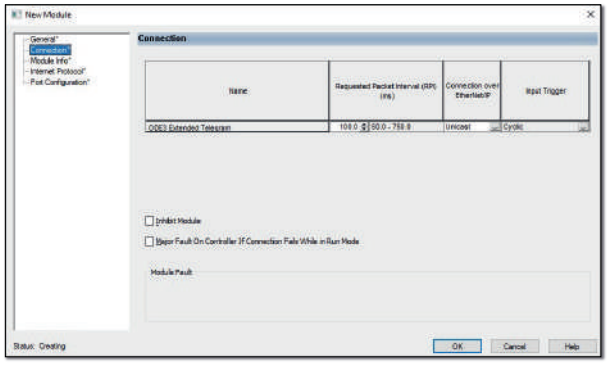



**Step 9.**
Confirm INT as the selected data type

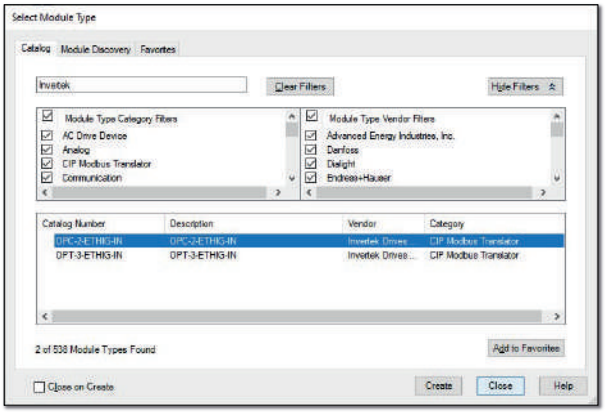



**Step 10.**
(Optional) Adjust the RPI time in the Connection tab.

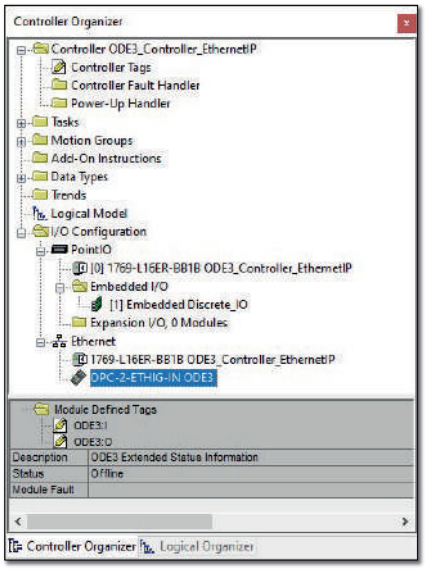
*Click OK button to save your settings.*



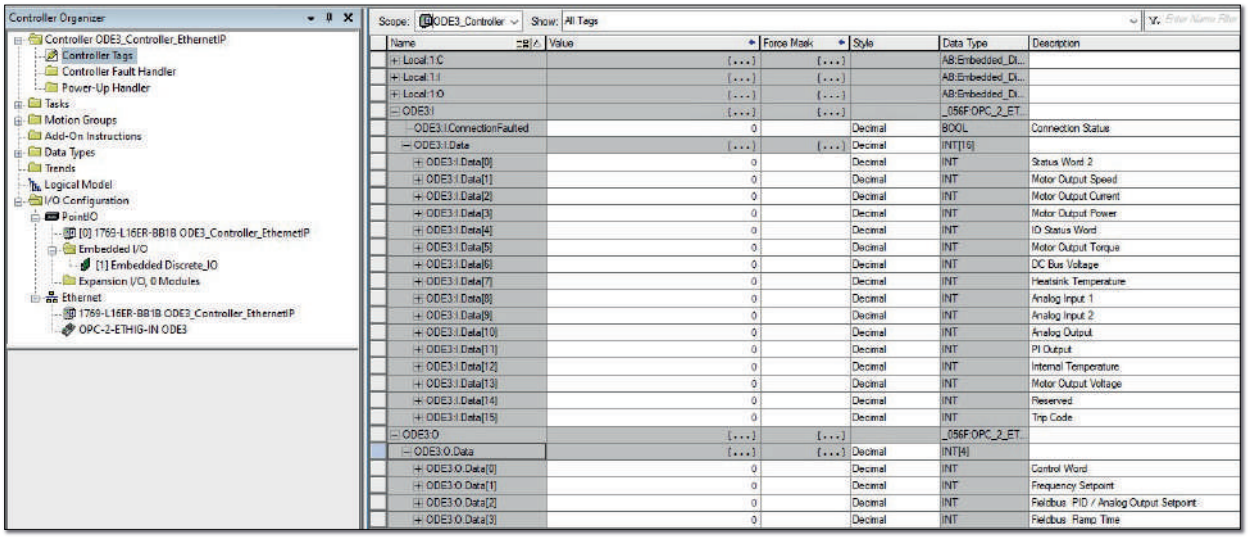

**Step 11.**
Close the Select Module Type Window




**Step 12.**
OPC-2-ETHIG-IN device will be added to the project

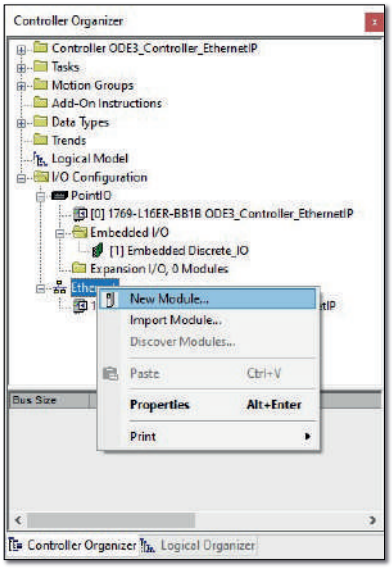


**Step 13.**
Drive tags created in the Controller Tags Window

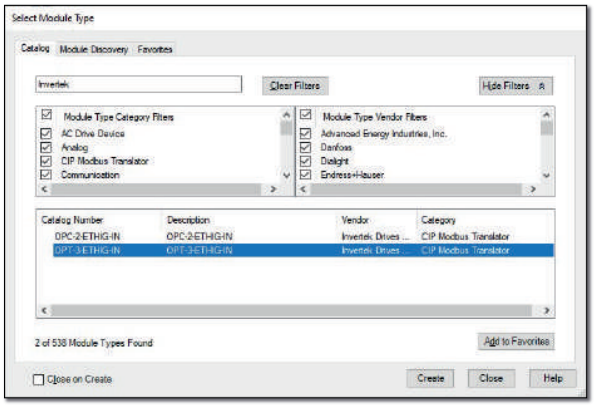



### 8.6.3.2.2. For use with ODE-3 IP66 Outdoor drives with built-in Ethernet/IP interface (Drive model code +"EiP")

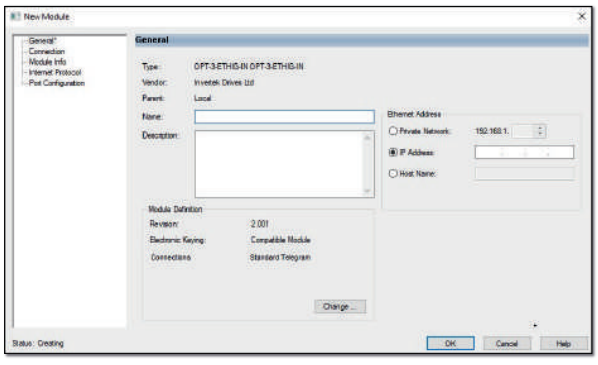
**Step 1.**
Add the New Module to the Ethernet/IP network
*Click the right button on the Ethernet (under the I/O Configuration) and add the New Module*



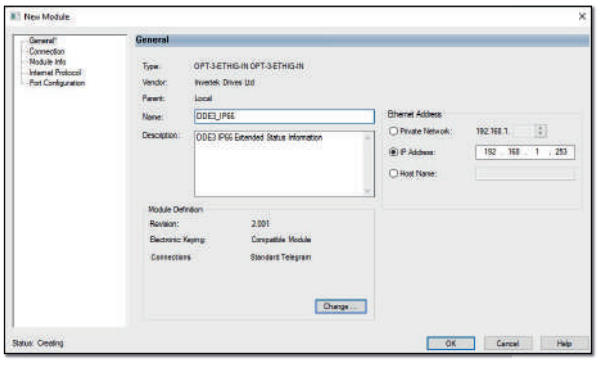

**Step 2.**
Search for Invertek devices in the Catalog View
*Select the OPT-3-ETHIG-IN device from the list*




**Step 3.**
Assign the device Name and the IP Address to the Drive
*(Default IP Address of the module is 192.168.1.253)*

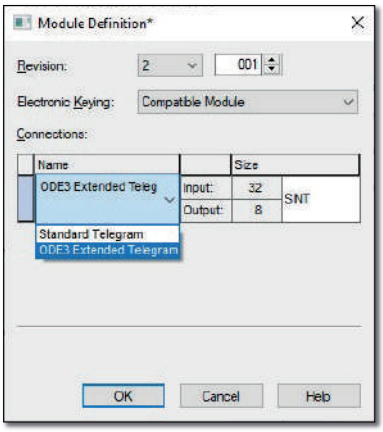



**Step 4.**
Click the *'Change...'* button in the Module Definition

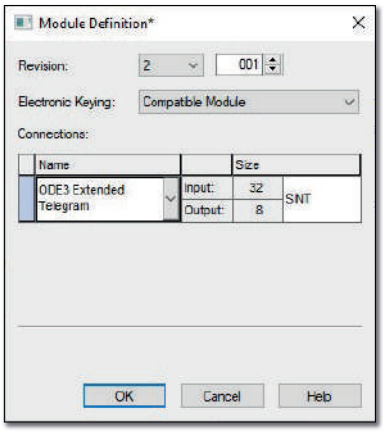


**Step 5.**
Change the Connection type

*Click the left button under the Name tab on the Standard Telegram field*

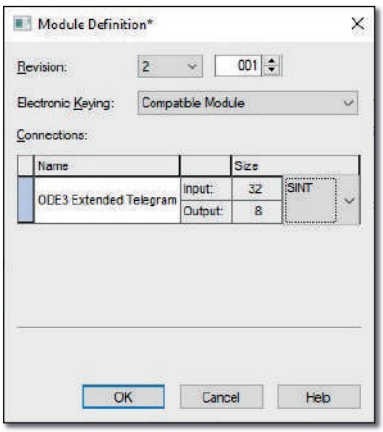



**Step 6.**
Select ODE3 Extended Telegram form the drop list as the Connection

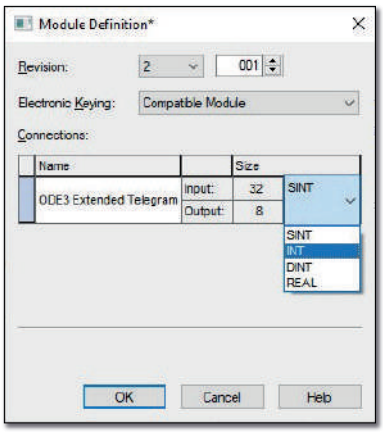



**Step 7.**
Change the data type

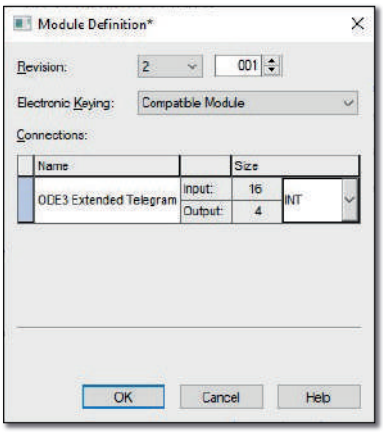
*Click the left button on the SINT field under the Size Tab*




**Step 8.**
Select INT data type from the drop list

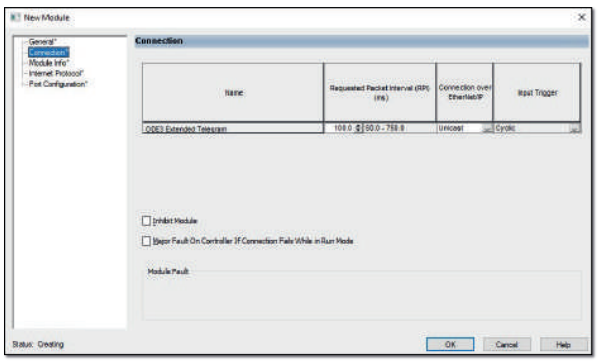



**Step 9.**
Confirm INT as the selected data type

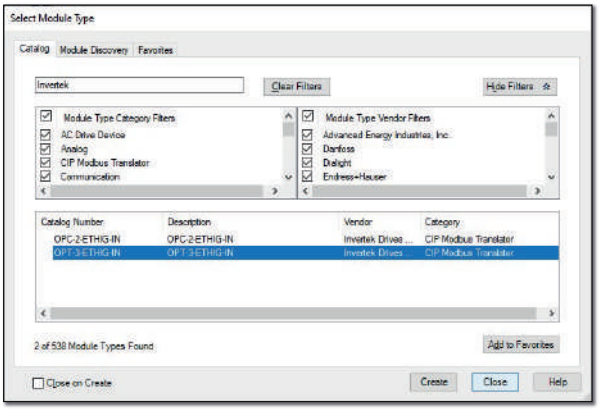



**Step 10.**
(Optional) Adjust the RPI time in the Connection tab

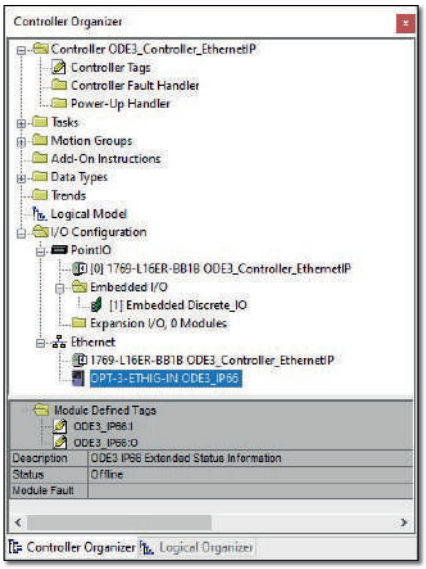
*Click OK button to save your settings*



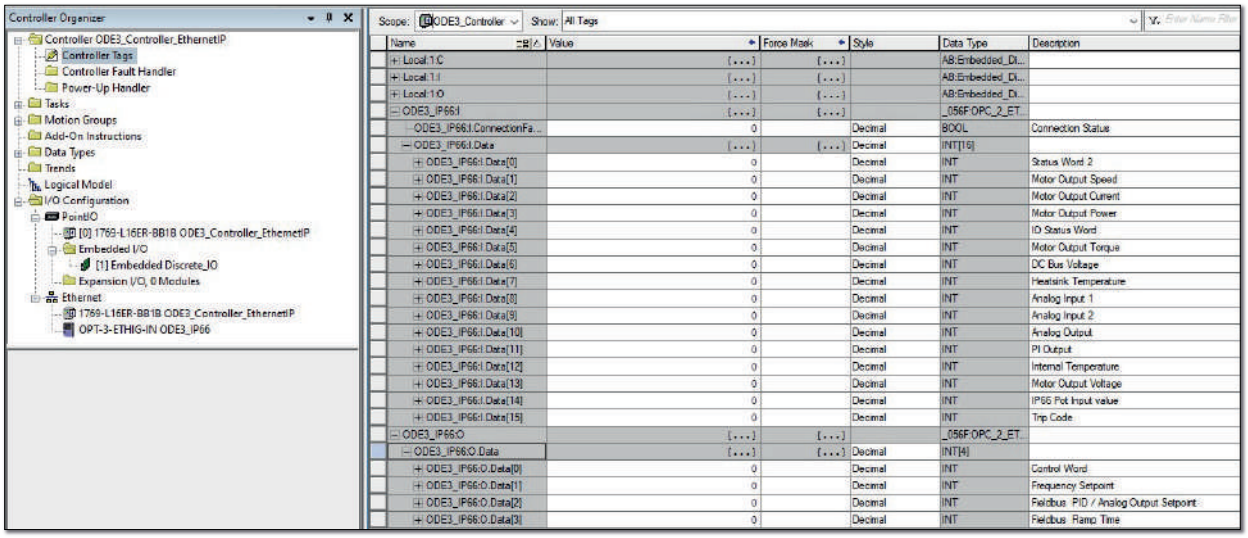
**Step 11.**
Close the Select Module Type Window




**Step 12.**
OPT-3-ETHIG-IN device will be added to the project




**Step 13.**
Drive tags created in the Controller Tags Window



### 8.6.4. *Generic device configuration*

**NOTE** This method of connection and operation without using the EDS file is only possible when working with PLC's which support message routing through a Modbus Translator device. Consult your PLC supplier for confirmation.

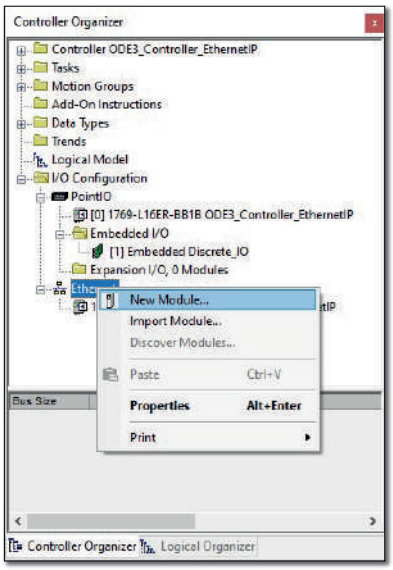
#### 8.6.4.1. Configuration example based on Allen Bradley Studio 5000 Logix Design

##### 8.6.4.1.1. Configuration example for Standard Telegram (4 Words in, 4 Words Out)

**Step 1.**

Add the New Module to the Ethernet/IP network

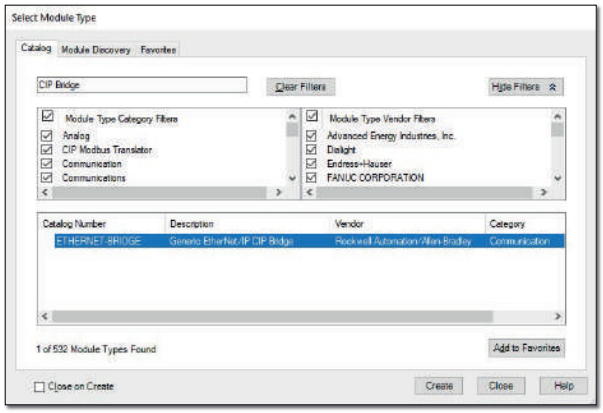
*Click the right button on the Ethernet (under the I/O Configuration) and add the New Module*




**Step 2.**

Search for Invertek devices in the Catalog View

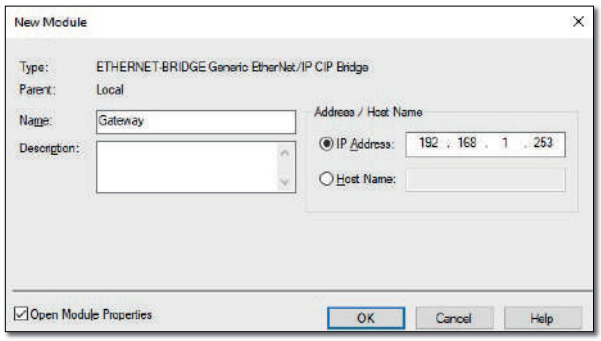
*Please type 'CIP Bridge' in the search box and select ETHERNET-BRIDGE*




**Step 3.**

Assign the device Name and the IP Address to the Drive

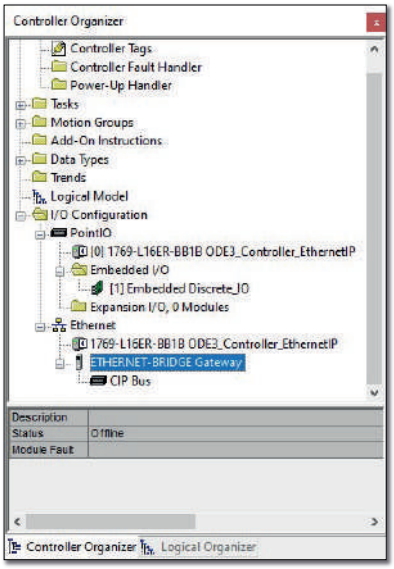
*(Default IP Address of the module is 192.168.1.253)*




**Step 4.**

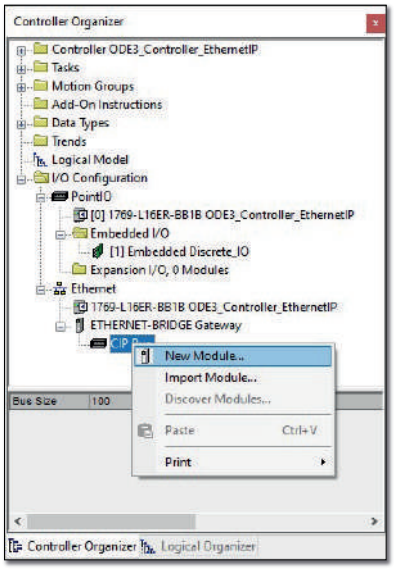
Ethernet-Bridge device will be added to your project

*The Modbus Translator will be added to your Ethernet/IP network represented as an "ETHERNET-BRIDGE"*

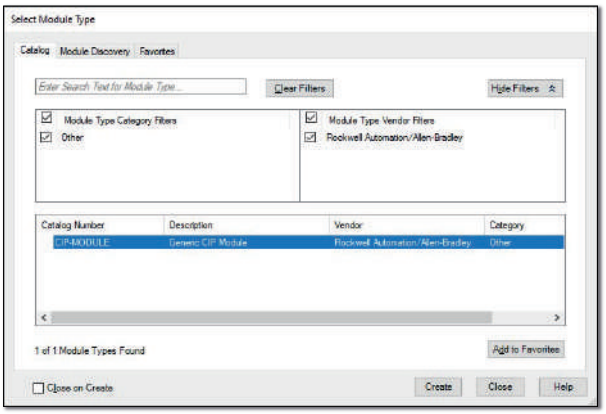


**Step 5.**
Add the 'New Module' under the 'CIP Bus'

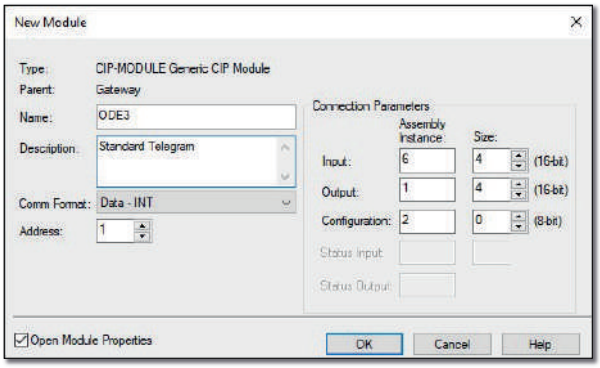
*Click the right button on the CIP Bus (under the ETHERNET-BRDIGE) and add the New Module*



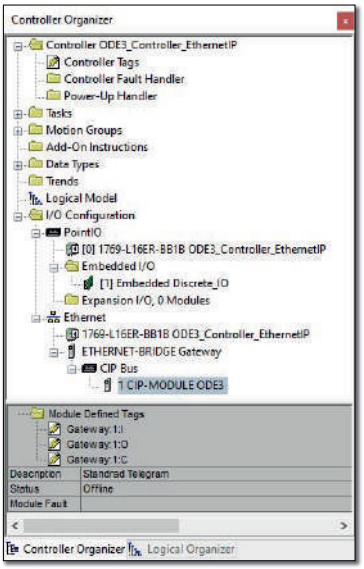

**Step 6.**
Select the 'CIP-Module' from the list



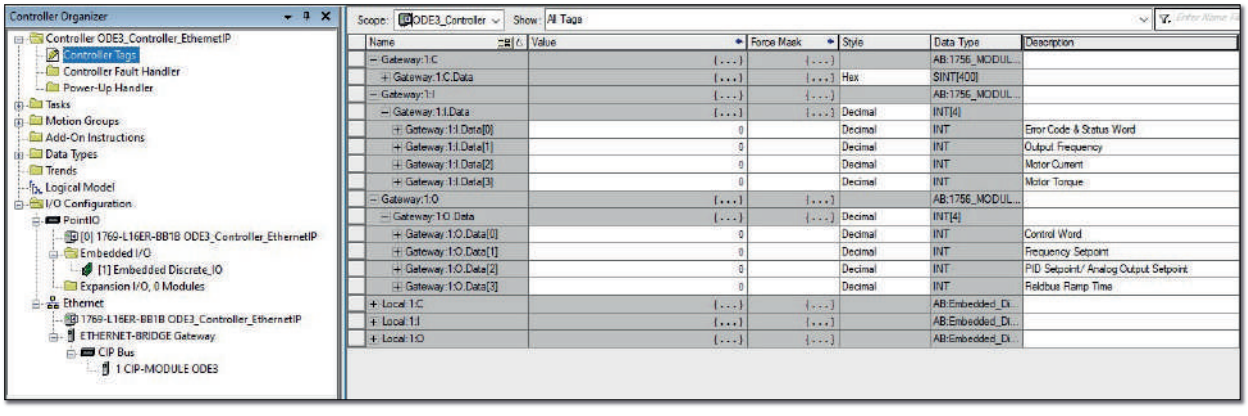

**Step 7.**
Assign the drive name, configure the Assembly Instances and sizes for Standard Telegram




**Step 8.**
Device should be added under the CIP Bus




**Step 8.**
Tags for the ODE3 drive are created int the Controller Tags window



Configuration for Assembly Instances and Size for Standard Telegram (4 Words In & 4 Words Out) are as below:

| Device Settings | | |
|---|---|---|
| Data Type | INT | 16-bit |
| Address | 1 | - |

| Connection Parameters | | |
|---|---|---|
| | **Assembly Instance** | **Size** |
| Input | 6 | 4 |
| Output | 1 | 4 |
| Configuration | 2 | 0 |

**NOTE**

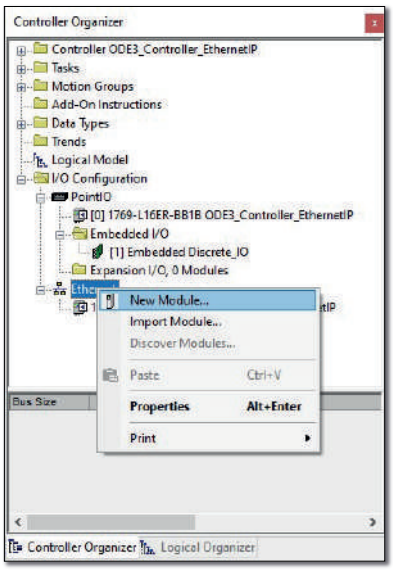
1. Assembly Instance is the Modbus Register number which can be found in the drive Parameter List / Programming guide document.
2. Device Address must be set to 1 and be equal to the drive local address.

### 8.6.4.1.2. Configuration example for ODE3 Extended Telegram (4 Words In / 16 Words Out)

**Step 1.**

Add the New Module to the Ethernet/IP network

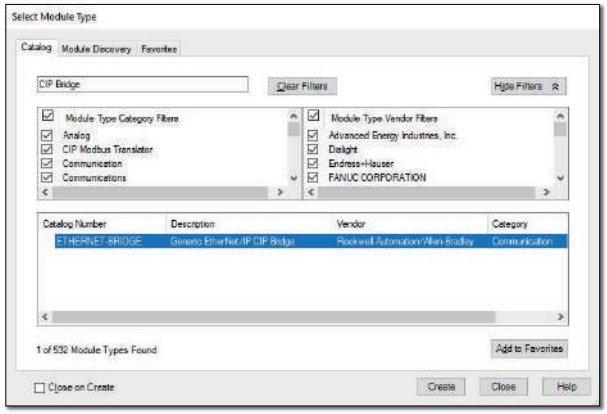
*Click the right button on the Ethernet (under the I/O Configuration) and add the New Module*




**Step 2.**

Search for Invertek devices in the Catalog View

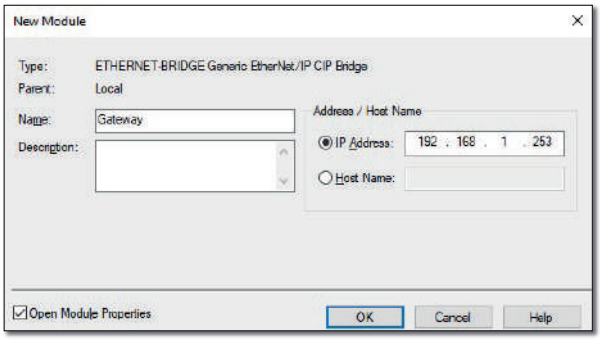
*Please type 'CIP Bridge' in the search box and select ETHERNET-BRIDGE*



**Step 3.**

Assign the device Name and the IP Address to the Drive

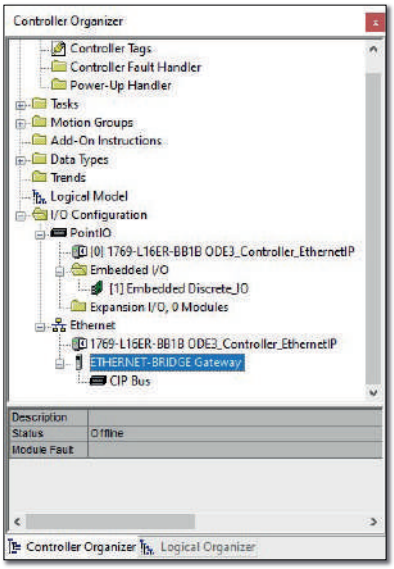
*(Default IP Address of the module is 192.168.1.253)*




**Step 4.**

Ethernet-Bridge device will be added to your project

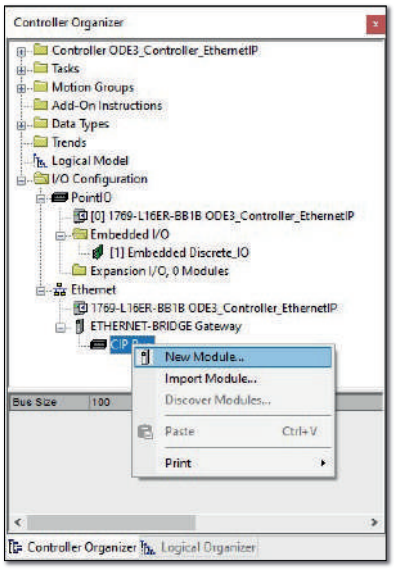
*The Modbus Translator will be added to your Ethernet/IP network represented as an "ETHERNET-BRIDGE"*




**Step 5.**

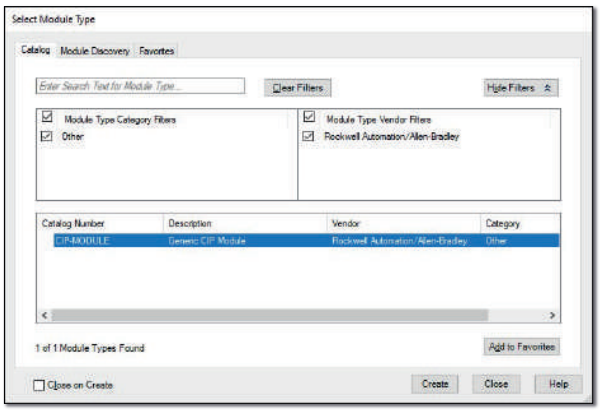
Add the 'New Module' under the 'CIP Bus'

*Click the right button on the CIP Bus (under the ETHERNET-BRDIGE) and add the New Module*

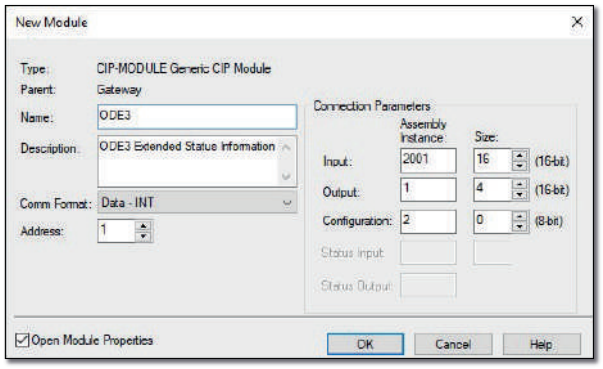



**Step 6.**

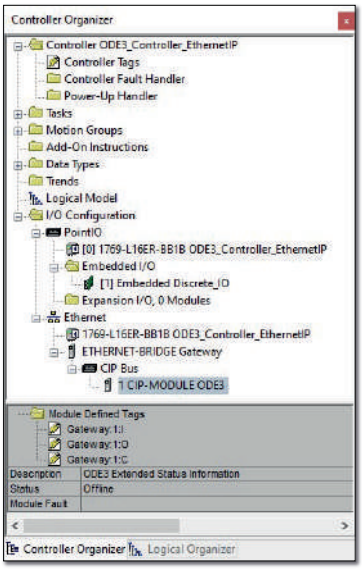
Select the 'CIP-Module' from the list



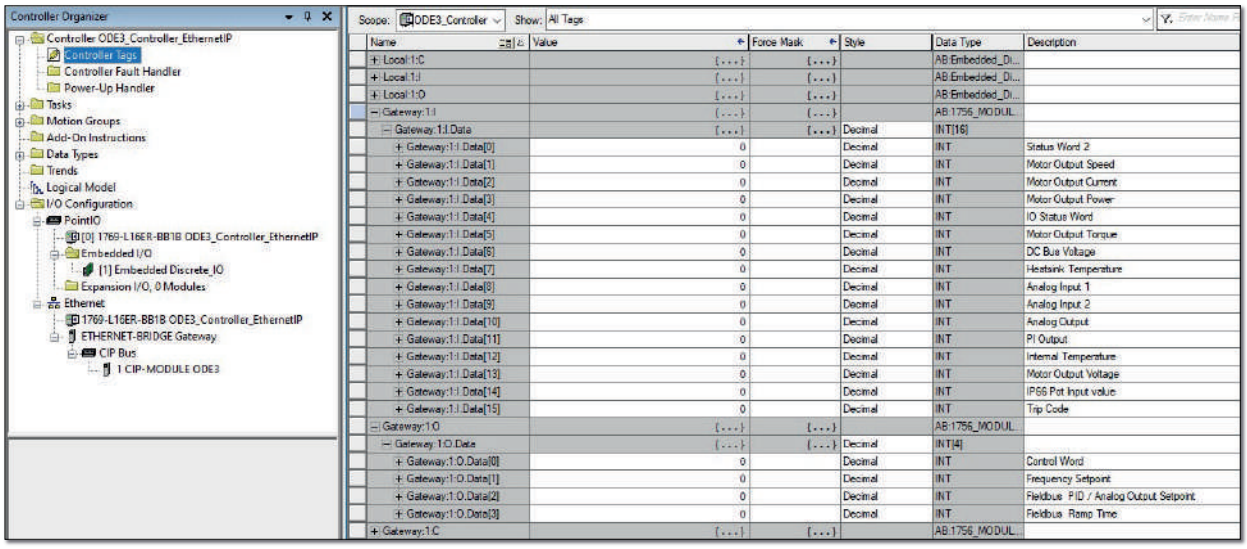
**Step 7.**
Assign the drive name, configure the Assembly Instances and sizes for ODE3 Extended Telegram




**Step 8.**
Device should be added under the CIP Bus




**Step 9.**
Tags for the ODE3 drive are created int the Controller Tags window




Configuration for Assembly Instances and Size for ODE3 Extended Telegram (4 Words In & 16 Words Out) are as below:

| Device Settings | | |
|---|---|---|
| Data Type | INT | 16-bit |
| Address | 1 | - |

| Connection Parameters | | |
|---|---|---|
| | **Assembly Instance** | **Size** |
| Input | 2001 | 16 |
| Output | 1 | 4 |
| Configuration | 2 | 0 |

**NOTE**

1. Assembly Instance is the Modbus Register number which can be found in the drive Parameter List / Programming guide document.
2. Device Address must be set to 1 and be equal to the drive local address.

### 8.6.4.2. Generic device configuration with Enabled Routing (Other PLC type)

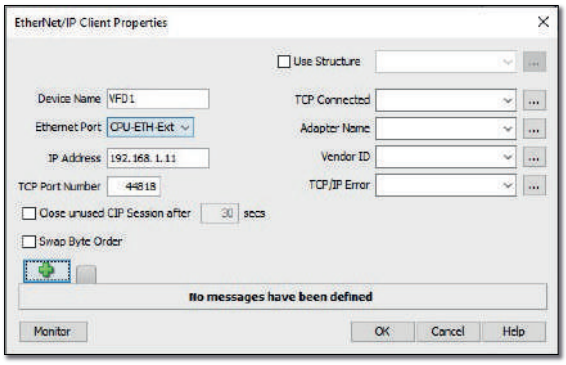
Communication as a Generic deice is also possible with PLC's that support routing through a CIP Modbus Translator.

For detailed information please refer to the programming documentation of the PLC.

A typical example configuration is shown below.

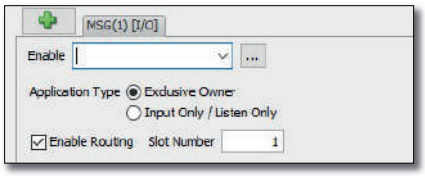
**Network configuration**

*Add a Generic Device to the EtherNet/IP network, assign the device name and IP address*




**Message configuration**

*Please add the I/O Message and configure it as below*

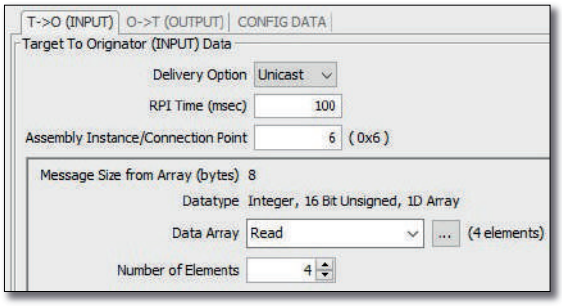



**NOTE**

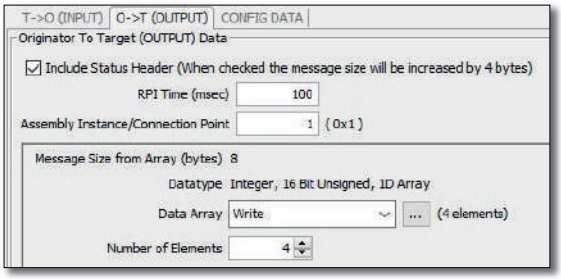
Slot number must be set to 1 and be equal to the drive local network address (Parameter P-36).

**Device configuration for Standard Telegram (4 Words In/ 4 Words Out)**

Target to Originator:

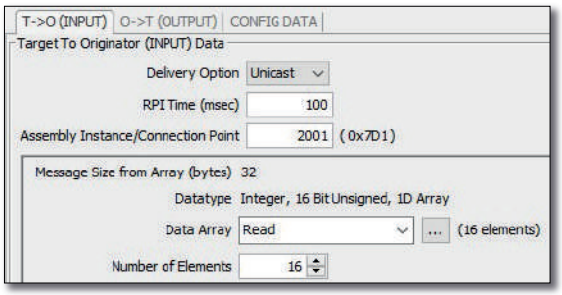



Originator to Target:

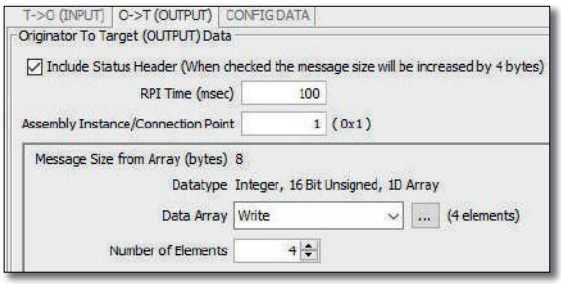



**Device configuration for Extended Status Information (Advanced Telegram with 4 Words In/ 16 Words Out)**

Target to Originator:




Originator to Target:




## 8.7. Advanced connection methods

Communication to the drive may also be possible using one of the two methods shown below. This allows process data to be cyclically exchanged between the Ethernet/IP master and a connected Optidrive.

Both of the following methods are pre-defined within the available EDS files.

### *8.7.1. Method 1: Class 1 connection to Drive Assembly object*

Drive control can be achieved via Class1 connections to the Assembly Object (0x04).

The controller must implement the forward open request (routing) to the OPT-2-ETHEG-IN Port 3, address 1.

For Drive specific allocation refer to Drive Manual and/or Ethernet/IP EDS file.

For Drive specific read/write limitations refer to Drive Manual and/or Ethernet/IP EDS file.

The following connection setting will establish a Class 1 connection to transfer Drive PDI/PDO Modbus registers

| Connection setting | | Value |
|---|---|---|
| Path | | 20 04 24 01 2C 01 2C 06 |
| RPI | | Min 50ms |
| Timeout Multiplier | | Recommend x32 |
| Trigger | | Cyclic |
| Transport type | | Exclusive owner |
| O->T | Size | 8 |
| | Connection Type | Point to Point |
| | Length | Fixed |
| | Transfer Format | 32bit Run/Idle |
| T->O<br>Standard Telegram 4 Word | Size | 8 |
| | Connection Type | Point to Point |
| | Length | Fixed |
| | Transfer Format | Pure data |

### *8.7.2. Method 2: Class 1 connection via OPC-2-ETHIG-IN 'Forward Open Assembly' object*

The OPC-2-ETHIG-IN provides the Vendor Class 'Forward Open Assembly (0x0300)' which negates the need for the control to provide the forward open mapping.

For Drive specific allocation refer to Drive Manual and/or Ethernet/IP EDS file.

For Drive specific read/write limitations refer to Drive Manual and/or Ethernet/IP EDS file.

The following connection setting will establish a Class 1 connection to transfer Drive PDI/PDO registers.

| Connection setting | | Value |
|---|---|---|
| Path | | 21 00 00 03 24 01 2C 01 2C 06 |
| RPI | | Min 50ms |
| Timeout Multiplier | | Recommend x32 |
| Trigger | | Cyclic |
| Transport type | | Exclusive owner |
| O->T<br>(4 Words) | Size | 8 |
| | Instance | 1 |
| | Connection Type | Point to Point |
| | Length | Fixed |
| | Transfer Format | 32bit Run/Idle |
| T->O<br>Standard Telegram<br>(4 Words) | Size (bytes) | 8 |
| | Instance | 1 |
| | Connection Type | Point to Point |
| | Length | Fixed |
| | Transfer Format | Pure data |
| T->O<br>Extended Status Telegram<br>(16 Words)<br>**Valid also for Method 1** | Size (bytes) | 32 |
| | Instance | 2001 |
| | Connection Type | Point to Point |
| | Length | Fixed |
| | Transfer Format | Pure data |

## 8.8. Parameter data transfer

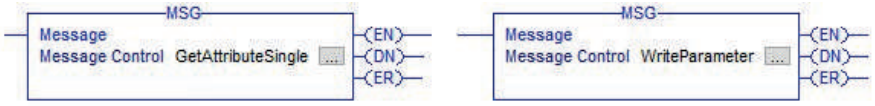
### *8.8.1. Overview*

The OPT-2-ETHEG-IN/ OPT-3-ETIG-IN are Modbus Translator Devices. This means that all data accessible from the drives Modbus RTU interface may also be accessed via the Ethernet/IP interface. For details of the relevant Modbus registers available for each drive, refer to the drive Parameter List / Programming Guide.

The interface module supports acyclic access to all drive parameters. This type of communication is typically used for low priority and occasional access to drive settings and data. For this purpose, the module supports explicit messaging.

### 8.8.2. *Explicit Messaging*

Explicit messaging can be used to read or write a parameter setting.




All drives parameter variables have the data type INT (16 bit, 2-byte objects). The device parameters and the PLC program variables must have the same data lengths.

**Accessing drive parameters**

Explicit messaging must be configured using the settings shown below.

| Explicit Message Read Request Configuration | | |
|---|---|---|
| **Read Message Type** | **Single Parameter Read** | **Multiple Parameters Read** |
| Service ID | 14 (0x0E) | 78 (0x4E) |
| Class ID | 15 (0x0F) | 68 (0x44) |
| Attribute ID | 1 (0x01) | - |
| Instance ID | Modbus Register assigned to the Parameter Number | |
| Data Type | INT (16-bit) | |
| Data Size | 16-bit | 16-bit x Number of Requested Elements |

| Explicit Message Write Request Configuration | | |
|---|---|---|
| **Read Message Type** | **Single Parameter Write** | **Multiple Parameters Write** |
| Service ID | 16 (0x10) | Not supported |
| Class ID | 15 (0x0F) | Not supported |
| Attribute ID | 1 (0x01) | Not supported |
| Instance ID | Modbus Register assigned to the Parameter Number | |
| Data Type | INT (16-bit) | |
| Data Size | 16-bit | - |

#### 8.8.2.1. Parameter data transfer - configuration example based on Allen Bradley Studio 5000 Logix Designer

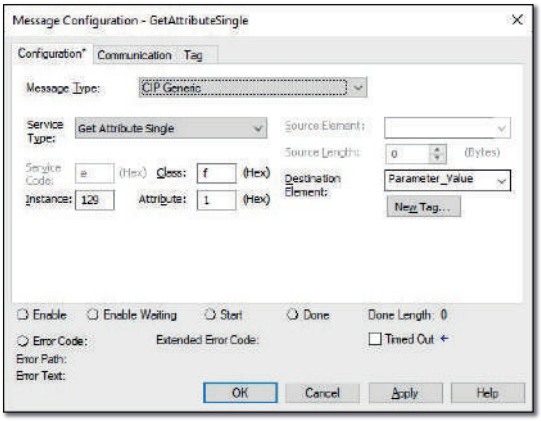
##### 8.8.2.1.1. Read Parameter Value

Please add the MSG function to the program.

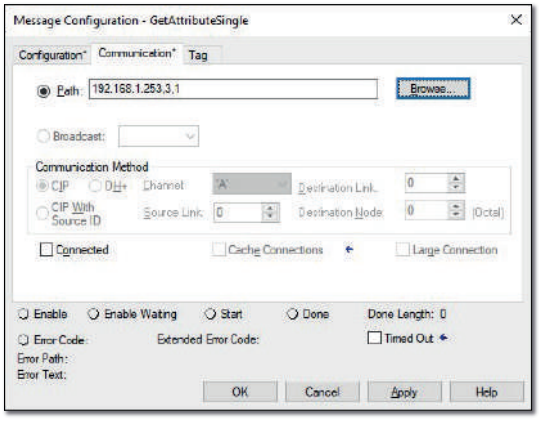



**Massage Configuration – Parameter Read**

Configuration Tab:



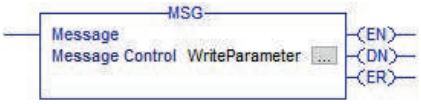

Communication Tab:



| Coniguration Settings | |
|---|---|
| Message Type | CIP Generic |
| Service Type | Get Attribute Single (0x0E) |
| Class ID | 0x0F |
| Instance | The relevant Modbus RTU Register Number (For ODE-3 i.e.: P-01 = 129 [128+01], P-02 = 130 [128+02]) |
| Attribute | 1 |
| Source Length | 2 Bytes |
| Destination Element | Must be a 16-bit data type |
| Path | **'Device Name or IP Address, 3, 1'** |

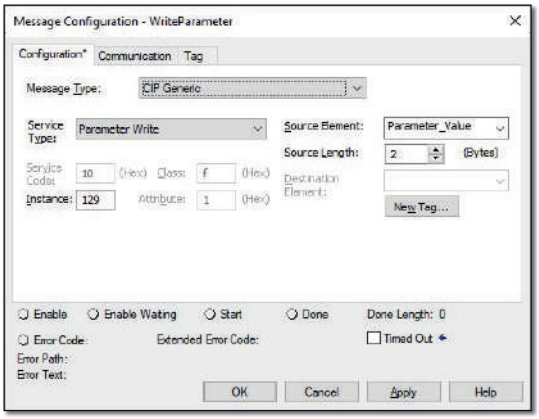
#### 8.8.2.1.2. Write Parameter Value

Please add the MSG function to the program.

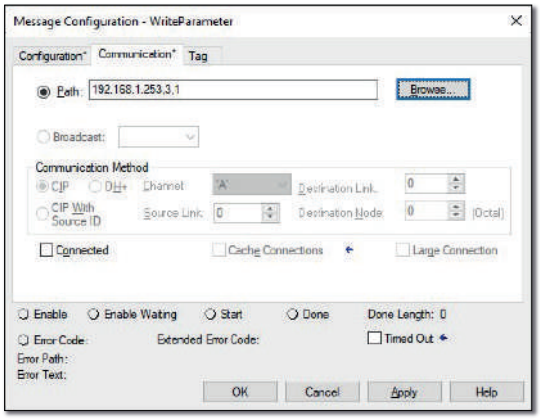



#### Massage Configuration – Parameter Write

Configuration Tab:




Communication Tab:




| Coniguration Settings | |
|---|---|
| Message Type | CIP Generic |
| Service Type | Parameter Write (0x10) |
| Class ID | 0x0F |
| Instance | The relevant Modbus RTU Register Number (For ODE-3 i.e.: P-01 = 129 [128+01], P-02 = 130 [128+02]) |
| Attribute | 1 |
| Source Length | 2 Bytes |
| Destination Element | Must be a 16-bit data type |
| Path | **'Device Name or IP Address, 3, 1'** |

## 8.9. Trouble Shooting

### 8.9.1. *Status Indicator LEDs*

Refer to *6. Ethernet Connection on page 14* for status LED location information.

| Status LED | Function |
|---|---|
| NS | Ethernet Network Status Indicator |
| MS | MS: Ethernet/IP Network Status Indicator |
| COMM | COMM: Modbus Communication Indicator (OPC-2-ETHIG-IN <-> Drive) |
| ERROR | Modbus Error Indicator (OPC-2-ETHIG-IN <-> Drive) |

| Network Status (NS) Indicator | |
|---|---|
| **State** | **Ethernet/IP** |
| Steady Off | Not powered<br>No IP address |
| Steady Green | Online<br>One or more connections active or message received |
| Flashing Green | Online<br>No connections active or no messages received |
| Flashing Red | Connection timeout |
| Steady Red | Duplicate IP |
| Flashing Green and Red | Self-test |

| Module Status (MS) Indicator | |
|---|---|
| **State** | **Indication** |
| Steady Off | No power |
| Steady Green | Operating in normal condition |
| Flashing Green | Drive not configured |
| Flashing Red | Minor fault - Recoverable fault |
| Steady Red | Major fault - Unrecoverable fault |
| Flashing Green / Red | Self-test |

| COMM | |
|---|---|
| **State** | **Indication** |
| Steady Off | Modbus protocol TX/RX inactive |
| Steady/flashing Yellow | Modbus protocol TX/RX active |

| ERROR | |
|---|---|
| **State** | **Indication** |
| Steady Off | Modbus protocol TX/RX Status OK |
| Steady Red | Non-recoverable internal fault – Modbus communications circuit fault |
| Flashing Red | Recoverable Communication fault or configuration error |

| Link Activity LEDs (P1/P2) | | |
|---|---|---|
| **State** | **State** | **Indication** |
| P1 Speed | Steady Yellow | 100Mbps link active |
| | Steady Off | 10Mbps or No link |
| P1 Link Activity | Steady Green | Valid Link |
| | Steady Off | No Link |
| | Flash | TX/RX |
| P2 Speed | Steady Yellow | 100Mbps link active |
| | Steady Off | 10Mbps or No link |
| P2 Link Activity | Steady Green | Valid Link |
| | Steady Off | No Link |
| | Flash | TX/RX |

# 9. Modbus TCP

## 9.1. Overview

The OPT-3-MTPEG-IN device operates as a Modbus TCP to Modbus RTU converter and communicates to the drive using the Modbus RTU protocol. For drives with factory fitted interface, the operating principle remains the same.

## 9.2. Usage Requirement

- When using the Modbus TCP to control the drive it is necessary to ensure that the amount of data and frequency of data exchange does not exceed the amount of data which can be successfully exchanged on the Modbus sub-network within the permitted time.
- Whilst the Optitools Studio PC software supports communication through the Ethernet network for device commissioning, it is not recommended to use this continuously during operation of the drive as the additional communication load may exceed the limit resulting in loss of Cyclic communication.
  - In this case, connect the PC software to the drive serial port using the USB / RS485 adaptor.
    - Use port D1 or D2 of the external Ethernet adaptor.
    - Use port D1 or D2 of the Compact 2 Ethernet adaptor.
    - Use one of the available ports labelled "IOIOI".
  - Do not connect via Ethernet if data logging is required.

## 9.3. Operation

### *9.3.1. Supported Commands*

Modbus TCP supported commands and registers are the same as those for Modbus RTU. Refer to sections *4.3. Modbus RTU Configuration Parameter on page 10* to *4.6. Modbus RTU Indirect Parameter Access on page 10* for further information.

### *9.3.2. IP Address*

The default IP address is 192.168.1.253, Subnet Mask 255.255.255.0

IP configuration can be changed using the internal webserver interface.

## 9.4. Trouble Shooting

### *9.4.1. Status Indicator LEDs*

Refer to *6. Ethernet Connection on page 14* for status LED location information.

| Status LED | Function |
|---|---|
| NS | Ethernet Network Status Indicator |
| MS | MS: Ethernet/IP Network Status Indicator |
| COMM | COMM: Modbus Communication Indicator (OPC-2-ETHIG-IN <-> Drive) |
| ERROR | Modbus Error Indicator (OPC-2-ETHIG-IN <-> Drive) |

| Network Status (NS) Indicator | | |
|---|---|---|
| **State** | **Ethernet/IP** | **Modbus TCP** |
| Steady Off | Not powered<br>No IP address | Not powered<br>No IP address<br>In EXCEPTION state |
| Steady Green | Online<br>One or more connections active or message received | At least one Modbus TCP message received |
| Flashing Green | Online<br>No connections active or no messages received | Online<br>Waiting for first Modbus TCP message |
| Flashing Red | Connection timeout | Connection timeout<br>No valid Modbus TCP message have been received with in the configures "process active timeout" |
| Steady Red | Duplicate IP | Duplicate IP<br>Fatal Error |
| Flashing Green and Red | Self-test | |

| Module Status (MS) Indicator | |
|---|---|
| **State** | **Indication** |
| Steady Off | No power |
| Steady Green | Operating in normal condition |
| Flashing Green | Drive not configured |
| Flashing Red | Minor fault - Recoverable fault |
| Steady Red | Major fault - Unrecoverable fault |
| Flashing Green / Red | Self-test |

| COMM | |
|---|---|
| **State** | **Indication** |
| Steady Off | Modbus protocol TX/RX inactive |
| Steady/flashing Yellow | Modbus protocol TX/RX active |

| ERROR | |
|---|---|
| **State** | **Indication** |
| Steady Off | Modbus protocol TX/RX Status OK |
| Steady Red | Non-recoverable internal fault – Modbus communications circuit fault |
| Flashing Red | Recoverable Communication fault or configuration error |

| Link Activity LEDs (P1/P2) | | |
|---|---|---|
| **State** | **State** | **Indication** |
| P1 Speed | Steady Yellow | 100Mbps link active |
| | Steady Off | 10Mbps or No link |
| P1 Link Activity | Steady Green | Valid Link |
| | Steady Off | No Link |
| | Flash | TX/RX |
| P2 Speed | Steady Yellow | 100Mbps link active |
| | Steady Off | 10Mbps or No link |
| P2 Link Activity | Steady Green | Valid Link |
| | Steady Off | No Link |
| | Flash | TX/RX |

# 10. Fieldbus Gateways

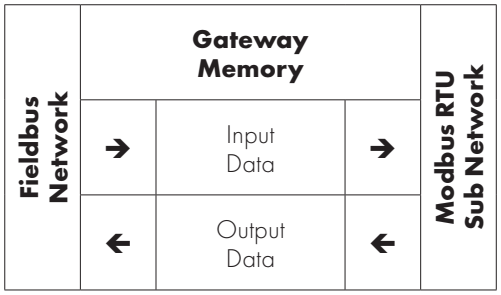
## 10.1. Gateway Concept

The fieldbus gateway acts as an interface between the Modbus RTU interface and a high-level fieldbus network such as Profibus DP or DeviceNet.

The gateway supports up to 8 drives connected as slaves.

**NOTE** When ordering the gateway, the number of slaves must be specified to ensure the correct configuration is loaded.

The gateway internally consists of two segments of memory. Data transferred from the fieldbus Master System is written to the first memory area, and the fieldbus Master may Read data from the second memory area.




The fieldbus Master can normally be configured to Read and Write the entire gateway memory area in a single transaction, or separate transaction per drive may be configured. The gateway is the pre-configured by Invertek to carry out the necessary individual Modbus RTU transactions to communicate with the Sub Network of connected drives.

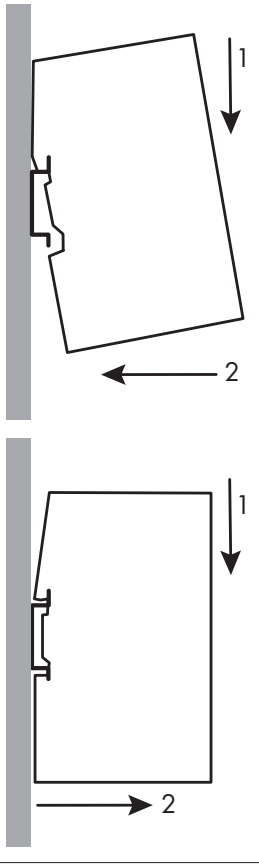
## 10.2. Gateway Included Components

Each gateway is supplied with the following:

- Anybus Communicator Profibus AB7000 OR Anybus Communicator DeviceNet AB7001.
- Male DB9-RJ45 Blue Subnetwork Connection Cable.

**NOTE** PROFIBUS / DeviceNet network cable and connector are **not** included.

## 10.3. Gateway Installation




- Mount the gateway on to the DIN-rail.
- The DIN-rail mechanism works as follows:
  - To snap the gateway on, first press it downwards (1) to compress the spring in the DIN-rail mechanism, then push it against the DIN-rail as to make it snap on (2).
  - To snap the gateway off, push it downwards (1) and pull it out from the DIN-rail (2), as to make it snap off from the DIN-rail.
- Connect the Anybus Communicator to the PROFIBUS-DP / DeviceNet network.
- For Profibus, set the PROFIBUS node ID (see section *10.7.1. Installation on page 51*).
- Connect the gateway to the serial subnetwork using the supplied Blue Male DB9-RJ45 Subnetwork Connection Cable.
- For a network with multiple drives, refer to *10.4.2. Multi Drive Network Example on page 48*.
- Gateways supplied by Invertek drives are pre-configured to operate with 4 connected E3 drives, unless an alternative number is specified when ordering.
- If an alternative number of slaves are required, configuration files to suit between one and 4 slaves may be downloaded from the Invertek Drives website. The user may then load the desired slave configuration to the gateway as follows:
  - Connect the gateway to the PC via the configuration cable.
  - Connect the power cable and apply power.
  - Start the Anybus Configuration Manager program on the PC.
    (The Anybus Configuration Manager software attempts to detect the serial port automatically. If not successful, select the correct port manually in the "Port"-menu).
  - Configure the gateway using the Anybus Configuration Manager and download the relevant configuration to suit the number of connected slave drives.
  - Set up the PROFIBUS communication in accordance with the configuration.

## 10.4. Subnetwork Connection

The drive sub network connects to the connector on the bottom of the gateway, using the supplied DB9-RJ45 cable. For a single drive installation, the cable can be connected directly from the gateway to the Optidrive. For a network of multiple drives, the network can be easily constructed using suitable RJ45 cables and splitters available from your Invertek Drives Sales Partner.

### *10.4.1. Single Drive Network Example*

The gateway is connected to the drive using the supplied Blue Male DB9-RJ45 Subnetwork Connection Cable.



### *10.4.2. Multi Drive Network Example*

The network can be constructed using firstly the supplied Blue Male DB9-RJ45 Subnetwork Connection Cable, and in addition, RJ45 Splitters (OPT-2-J45SP-IN) and RJ45 cables (0.5m – OPT-2J4505-IN, 1m – OPT-J4510-IN, 3m – OPT-2-J4530-IN). Alternative cables may be used; Invertek recommend using Cat 6 shielded twisted pair cables with pin-to-pin construction.



## 10.5. Gateway Memory Mapping

The PLC programmer can read/write the PLC memory mapping to gateway memory to monitor/control drives in the sub network.

### *10.5.1. Input Memory*

This part of the memory contains the real-time drive information that can be read by the PLC.

| Drive Modbus RTU Address | Data | Start Address | Data Length | Modbus Register (Refer to section 11 for further information) |
|---|---|---|---|---|
| 1 | Trip code | 0x0000 | 8 bits | 6 |
| | Drive status | 0x0001 | 8 bits | |
| | Motor speed in Hz | 0x0002 | 16 bits | 7 |
| | Motor current | 0x0004 | 16 bits | 8 |
| | Not Used | 0x0006 | 16 bits | |
| 2 | Trip code | 0x0008 | 8 bits | 6 |
| | Drive status | 0x0009 | 8 bits | |
| | Motor speed in Hz | 0x000A | 16 bits | 7 |
| | Motor current | 0x000C | 16 bits | 8 |
| | Not Used | 0x000E | 16 bits | |
| 3 | Trip code | 0x0010 | 8 bits | 6 |
| | Drive status | 0x0011 | 8bits | |
| | Motor speed in Hz | 0x0012 | 16 bits | 7 |
| | Motor current | 0x0014 | 16 bits | 8 |
| | Not Used | 0x0016 | 16 bits | |
| 4 | Trip code | 0x0018 | 8 bits | 6 |
| | Drive status | 0x0019 | 8 bits | |
| | Motor speed in Hz | 0x001A | 16 bits | 7 |
| | Motor current | 0x001C | 16 bits | 8 |
| | Not Used | 0x001E | 16 bits | |
| 5 | Trip code | 0x0020 | 8 bits | 6 |
| | Drive status | 0x0021 | 8 bits | |
| | Motor speed in Hz | 0x0022 | 16 bits | 7 |
| | Motor current | 0x0024 | 16 bits | 8 |
| | Not Used | 0x0026 | 16 bits | |
| 6 | Trip code | 0x0028 | 8 bits | 6 |
| | Drive status | 0x0029 | 8 bits | |
| | Motor speed in Hz | 0x002A | 16 bits | 7 |
| | Motor current | 0x002C | 16 bits | 8 |
| | Not Used | 0x002E | 16 bits | |
| 7 | Trip code | 0x0030 | 8 bits | 6 |
| | Drive status | 0x0031 | 8 bits | |
| | Motor speed in Hz | 0x0032 | 16 bits | 7 |
| | Motor current | 0x0034 | 16 bits | 8 |
| | Not Used | 0x0036 | 16 bits | |
| 8 | Trip code | 0x0038 | 8 bits | 6 |
| | Drive status | 0x0039 | 8 bits | |
| | Motor speed in Hz | 0x003A | 16 bits | 7 |
| | Motor current | 0x003C | 16 bits | 8 |
| | Not Used | 0x003E | 16 bits | |

### *10.5.2. Output Memory*

This part of the memory contains the real-time drive information that can be read by the PLC.

| Drive Modbus RTU Address | Data | Start Address | Data Length | Modbus Register (Refer to section 11 for further information) |
|---|---|---|---|---|
| 1 | Control command | 0x0200 | 16 bits | 1 |
| | Speed reference in HZ | 0x0202 | 16 bits | 2 |
| | No Function | 0x0204 | 16 bits | - |
| | Ramp Time | 0x0206 | 16 bits | 4 |
| 2 | Control command | 0x0208 | 16 bits | 1 |
| | Speed reference in HZ | 0x020A | 16 bits | 2 |
| | No Function | 0x020C | 16 bits | - |
| | Ramp Time | 0x020E | 16 bits | 4 |
| 3 | Control command | 0x0210 | 16 bits | 1 |
| | Speed reference in HZ | 0x0212 | 16 bits | 2 |
| | No Function | 0x0214 | 16 bits | - |
| | Ramp Time | 0x0216 | 16 bits | 4 |
| 4 | Control command | 0x0210 | 16 bits | 1 |
| | Speed reference in HZ | 0x0212 | 16 bits | 2 |
| | No Function | 0x0214 | 16 bits | - |
| | Ramp Time | 0x0216 | 16 bits | 4 |
| 5 | Control command | 0x0220 | 16 bits | 1 |
| | Speed reference in HZ | 0x0222 | 16 bits | 2 |
| | No Function | 0x0224 | 16 bits | - |
| | Ramp Time | 0x0226 | 16 bits | 4 |
| 6 | Control command | 0x0228 | 16 bits | 1 |
| | Speed reference in HZ | 0x022A | 16 bits | 2 |
| | No Function | 0x022C | 16 bits | - |
| | Ramp Time | 0x022E | 16 bits | 4 |
| 7 | Control command | 0x0230 | 16 bits | 1 |
| | Speed reference in HZ | 0x0232 | 16 bits | 2 |
| | No Function | 0x0234 | 16 bits | - |
| | Ramp Time | 0x0236 | 16 bits | 4 |
| 8 | Control command | 0x0230 | 16 bits | 1 |
| | Speed reference in HZ | 0x0232 | 16 bits | 2 |
| | No Function | 0x0234 | 16 bits | - |
| | Ramp Time | 0x0236 | 16 bits | 4 |

## 10.6. Controlling the Optidrive(s)

The following points should be noted when attempting to control the Optidrive(s):

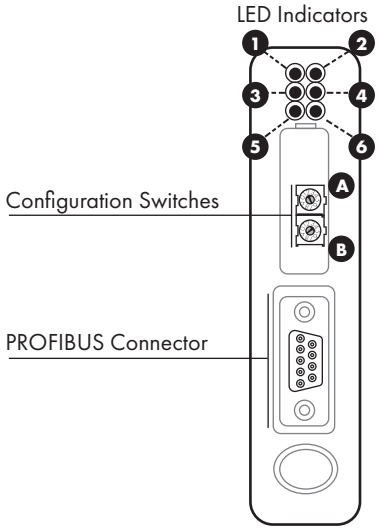
- The drive must be set for Modbus RTU control using P-12.
- Digital Input 1 which acts as a hardware enable must be ON for the drive to start, otherwise the drive will not enable, and the Sub Network Status LED will illuminate Red when the user tries to start the drive.
- The Enable / Run signal is Edge triggered, and so the drive must receive a control word with Bit 0 = 0, followed by a control word with Bit 0 = 1 to start.
- If P-12 = 3 and the user writes any data to the Ramp Time memory area, the gateway will indicate a Sub Network Status error (red flash), as the drive rejects the data which cannot be used.

## 10.7. Profibus DP Gateway Features – OD-PROFB-IN

- Complete PROFIBUS-DP slave functionality according to IEC 61158.
- Supports all common baud rates up to 12 Mbit (detected automatically).
- Up to 64 bytes of I/O data in each direction, allowing up to 8 Optidrives to be connected to a single gateway.
- Galvanically isolated bus electronics.

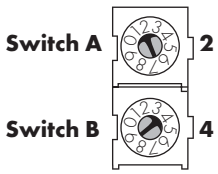
### *10.7.1. Installation*

#### 10.7.1.1. Overview - Module Front



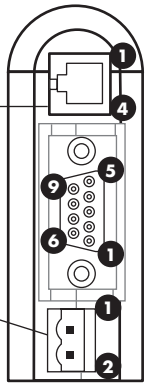

| | | | |
|---|---|---|---|
| **1** | Online | Green | Online |
| | | Off | Not Online |
| **2** | Offline | Red | Offline |
| | | Off | Not Offline |
| **3** | Not Used | - | - |
| **4** | Fieldbus Diagnostics | Off | No diagnostics present |
| | | Red, Flashing 1Hz | Configuration Error |
| | | Red, Flashing 2Hz | User parameter data error |
| | | Red, Flashing 4Hz | Initialisation Error |
| **5** | Subnet Status | Flashing Green | Running, but one or more transaction errors |
| | | Green | Running |
| | | Red | Transaction error / subnet stopped |
| **6** | Device Status | Off | Power Off |
| | | Alternating Red / Green | Invalid / missing configuration |
| | | Green | Initialising |
| | | Flashing Green | Running |
| | | Red | Bootloader Mode |
| | | Flashing Red | Diagnostic Code |
| **A** | Set the PROFIBUS node address by using the switches as follows: | | |
| **B** | Node address = (switch B * 10) + (switch A * 1) | | |

**Example:**
Setting node address 42




**Bottom View**
PC Connector:
1. GND
2. GND
3. RS232 Rx
4. RS232 Tx

Power:
1. +24 V DC
2. GND




| DB9 | |
|---|---|
| **1** | +5V |
| **2** | RS232 Rx (Not Used) |
| **3** | RS232 Tx (Not Used) |
| **4** | NC |
| **5** | Signal 0V |
| **6** | RS422 Rx+ (Not Used) |
| **7** | RS422 Rx- (Not Used) |
| **8** | RS485+ Modbus RTU |
| **9** | RS485- Modbus RTU |

| Power | |
|---|---|
| **1** | +24VDC, 300mA |
| **2** | 0V |

| Profibus Connector | Pin no | Description |
|---|---|---|
| 5 Female 1 / 9 6 | **1** | Shield |
| | **3** | B-line |
| | **4** | RTS |
| | **5** | GND bus |
| | **6** | +5V bus out |
| | **8** | A-line |
| | **2, 7, 9** | NC |

### *10.7.2. Profibus Master Configuration*

The latest applicable GSD file may be downloaded from the HMS website, www.anybus.com.

The actual configuration process will differ for different Profibus Master Systems and is not possible to explain in this document. Example configurations for Siemens PLC are provided on the HMS website.

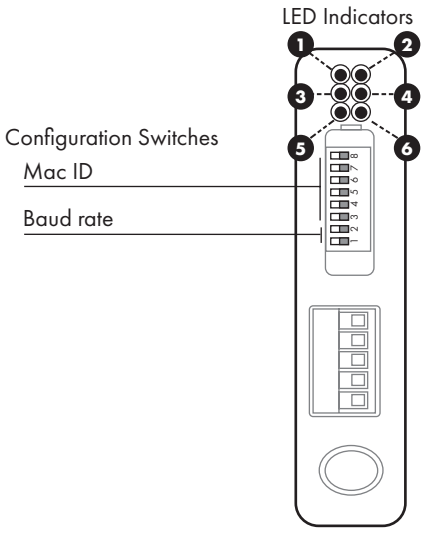
When configuring the communication between the Master System and the gateway, 4 words of Input Process Data and 4 words of Output Process Data should be allocated per drive connected the gateway, up to a maximum of 32 Input and Output words. If necessary, a configuration may be chosen in the Profibus Master which supports more than the connected number of drives, e.g. if 3 drives are connected to the gateway, the Master System can be configured for 12, 16 or even 32 words of Input and Output process data. The additional words will simply not contain any data.

## 10.8. DeviceNet Gateway Features – OD-DEVNT-IN

- Communications Adapter, profile no. 12
- Group two server
- Mac ID and baud rate configuration via on-board switches
- Polled, Change-of-state and Bit strobed I/O

### *10.8.1. Installation*

#### 10.8.1.1. Overview - Module Front




| | | | |
|---|---|---|---|
| **1** | Network Status | Off | Not online |
| | | Green | Link ok, online, connected |
| | | Flashing Green | Online, not connected |
| | | Red | Critical link failure |
| | | Flashing Red | Connection timeout |
| **2** | Module Status | Off | No power |
| | | Green | Device operational |
| | | Flashing Green | Data size bigger than configured |
| | | Red | Unrecoverable fault |
| | | Flashing Red | Minor fault |
| **3** | Not Used | - | - |
| **4** | Not Used | - | - |
| **5** | Fieldbus Diagnostics | Flashing Green | Running, but one or more transaction errors |
| | | Green | Running |
| | | Red | Transaction error / subnet stopped |
| **6** | Device Status | Off | Power Off |
| | | Alternating Red / Green | Invalid / missing configuration |
| | | Green | Initialising |
| | | Flashing Green | Running |
| | | Red | Bootloader Mode |
| | | Flashing Red | Diagnostic Code |

#### 10.8.1.2. Configuration Switches – Baud Rate

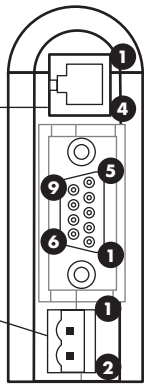
| Switch 1 | Switch 2 | Baud Rate |
|---|---|---|
| OFF | OFF | 125k |
| OFF | ON | 250k |
| ON | OFF | 500k |
| ON | ON | N/A |

#### 10.8.1.3. Configuration Switches – MAC ID

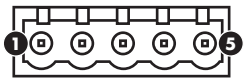
| MAC ID | Switch 3 | Switch 4 | Switch 5 | Switch 6 | Switch 7 | Switch 8 |
|---|---|---|---|---|---|---|
| 0 | OFF | OFF | OFF | OFF | OFF | OFF |
| 1 | OFF | OFF | OFF | OFF | OFF | ON |
| 2 | OFF | OFF | OFF | OFF | ON | OFF |
| 3-62 | ... | ... | ... | ... | ... | ... |
| 63 | ON | ON | ON | ON | ON | ON |

**Bottom View**
PC Connector:
1. GND
2. GND
3. RS232 Rx
4. RS232 Tx

Power:
1. +24 V DC
2. GND




| DB9 | |
|---|---|
| **1** | +5V |
| **2** | RS232 Rx (Not Used) |
| **3** | RS232 Tx (Not Used) |
| **4** | NC |
| **5** | Signal 0V |
| **8** | RS485+ Modbus RTU |
| **9** | RS485- Modbus RTU |
| | |
| **Power** | |
| **1** | +24VDC, 300mA |
| **2** | 0V |

| DeviceNet Connector | Pin no | Description |
|---|---|---|
|  | **1** | V- |
| | **2** | CAN L |
| | **3** | Shield |
| | **4** | CAN H |
| | **5** | V+ |



### *10.8.2. DeviceNet Master Configuration*

The latest version of the EDS file may be downloaded from the HMS website, www.anybus.com.

The actual configuration process will differ for different DeviceNet Master Systems and is not possible to explain in this document. Example configurations for Rockwell PLC are provided on the HMS website.

When configuring the communication between the Master System and the gateway, 4 words of Input Process Data and 4 words of Output Process Data should be allocated per drive connected the gateway, up to a maximum of 32 Input and Output words. If necessary, a configuration may be chosen in the Master which supports more than the connected number of drives, e.g. if 3 drives are connected to the gateway, the Master System can be configured for 12, 16 or even 32 words of Input and Output process data. The additional words will simply not contain any data.

## 10.9. Diagnostics and Troubleshooting

| Symptom | Suggested Actions |
|---|---|
| No Communication, Master > Gateway | Check all network cables<br>Check correct bus termination<br>Check correct node address on gateway<br>Check GSD / EDS file is recognised and used by the Master<br>Check the Status LEDs 1 and 2 |
| Profibus Communication OK,<br>Not possible to control the Optidrive(s) | Check the subnetwork Status LED<br>Check all sub network connections<br>Check correct baud rate set in drives<br>Check drives are addressed sequentially from 1<br>Check that data is written to the correct memory area(s) |

# 11. Control & Status Registers

## 11.1. Control Registers

When controlling the drive through any fieldbus network it is recommended to use the registers below. These registers support the Modbus RTU Function Code Write Multiple Registers and so all registers can be set in a single transaction greatly speeding up the drive control.

These registers are pre-mapped to the CAN RX PDO1 and are also used in the EDS file for Ethernet/IP communication.

The functions are described more fully in section *11.2. Standard Status Registers on page 55*.

| Name | Modbus RTU Register | CAN Open Index | Sub Index | PDO Map | Parameter Number | Upper Byte | Lower Byte | Format | Type | Scaling |
|---|---|---|---|---|---|---|---|---|---|---|
| PDO0 | 1 | 2000h | 0 | Y | - | Control Word | | WORD | R/W | See Below |
| PDO1 | 2 | 2001h | 0 | Y | - | Frequency Setpoint | | S16 | R/W | 1dp, e.g. 100 = 10.0Hz |
| PDO2 | 3 | 2002h | 0 | Y | - | PID Setpoint, Analog Output | | - | R/W | 0 – 4096 = 0 – 100% |
| PDO3 | 4 | 2003h | 0 | Y | - | Ramp Time | | U16 | R/W | 2dp, e.g. 500 = 5.00s |

### *11.1.1. Drive Control Word PDO0*

| Bit | Function When "0" | Function When "1" |
|---|---|---|
| 15 | No Function Assigned | |
| 14 | | |
| 13 | | |
| 12 | | |
| 11 | | |
| 10 | | |
| 9 | Digital output OFF | Digital Output ON |
| 8 | Relay Output OFF | Relay Output ON |
| 7 | No Function Assigned | |
| 6 | | |
| 5 | | |
| 4 | | |
| 3 | Operation Permitted | Coast Stop |
| 2 | No Action | Reset Active Fault |
| 1 | Operation Permitted | Fast Stop |
| 0 | Stop | Run |

For normal operation, Bit 3 has the highest priority, bit 0 has the lowest priority (bit 3>bit 1>bit 0).

Note that the Run / Stop (bit 0), Fast Stop (bit 1) and Coast Stop (bit 3) only operate under the following conditions:

- Fieldbus control (or CAN) is selected in P-12
- P-31 = 0 or 1

Otherwise, Run / Stop function is controlled by drive control terminals.

Reset function (bit 2) is always active when the drive operates in Fieldbus or CAN mode.

Bits 8 and 9 may optionally be used to control the state of the built in Analog Output in Digital Mode and the Output relay. This function is activated if selected by the relevant parameter:

- Relay Output P-18
- Digital Output, P-25

Refer to the programming Guide for further information.

### *11.1.2. Frequency Setpoint PDO1*

Frequency Setpoint value is transferred with one decimal place (200 = 20.0Hz).

The maximum value is limited by P-01.

Sending a value that exceeds P-01 will result in an Exception error.

### *11.1.3. PID Setpoint, Analog Output Control PDO2*

This word may optionally be used for the following functions:

- To set the setpoint to the PID controller
  - Requires P-44 = 2
  - The value range is 0 – 4096 = 0 – 100.0
  - Values > 4096 are treated as 100.0%
- To directly control the analog output in analog mode
  - Requires P-25 = 13
  - The value range is 0 – 4096 = 0 – 10Volts Output
  - Values > 4096 are treated as 100.0%

### *11.1.4. Ramp Time PDO3*

Active only when P-12 = 8 (CAN) or 4 (All other fieldbus).

This register specifies the drive acceleration and deceleration ramp time. The same value is applied simultaneously to the acceleration and deceleration ramp times.

The value has two decimal places, e.g., 500 = 5.00 seconds.

## 11.2. Standard Status Registers

When controlling the drive through any fieldbus network the registers below can be used to provide a simple status feedback from the drive.

Registers 6, 7 and 8 are pre-mapped to the first CAN PDO and are also used in the EDS file for Ethernet/IP communication.

The functions are described more fully in section *11.2. Standard Status Registers on page 55.*

| Name | Modbus RTU Register | CAN Open Index | Sub Index | PDO Map | Parameter Number | Upper byte | Lower Byte | Format | Type | Scaling |
|---|---|---|---|---|---|---|---|---|---|---|
| PDI0 | 6 | 200Ah | 0 | Y | - | Error code | Drive status | WORD | R | See Below |
| PDI1 | 7 | 200Bh | 0 | Y | - | Output Frequency | | S16 | R | 1dp, e.g. 100 = 10.0Hz |
| PDI2 | 8 | 200Dh | 0 | Y | - | Motor Current | | U16 | R | 1dp, e.g. 100 = 10.0A |
| PDI3 | 9 | 200Eh | 0 | Y | - | Motor Torque | | S16 | R | 4096 = 100% |

### 11.2.1. Drive status and error code Word PDI0

| Bit | Function When "0" | Function When "1" |
|---|---|---|
| 15 | In the event of a trip, the associated code is shown in this byte | |
| 14 | | |
| 13 | | |
| 12 | | |
| 11 | | |
| 10 | | |
| 9 | | |
| 8 | | |
| 7 | | |
| 6 | Not Ready | Drive Ready |
| 5 | | |
| 4 | | |
| 3 | | |
| 2 | - | Drive In Standby Mode |
| 1 | Drive OK | Drive Tripped |
| 0 | Drive Stopped | Drive Running |

Bit 6: Drive Ready to Run is defined as:

- Not tripped.
- Hardware enable signal present (DI1 ON).
- No mains loss condition.

## 11.3. Extended Status Registers

| Modbus RTU Register | CAN Open Index | Sub Index | PDO Map | Parameter Number | Upper byte | Lower Byte | Format | Type | Scaling |
|---|---|---|---|---|---|---|---|---|---|
| 2001 | - | - | - | - | Status Word 2 | | WORD | R | See Below |
| 2002 | - | - | - | - | Motor Output Speed | | S16 | R | 1dp, e.g. 100 = 10.0Hz |
| 2003 | - | - | - | - | Motor Output Current | | U16 | R | 1dp, e.g. 100 = 10.0A |
| 2004 | - | - | - | - | Motor Output Power | | U16 | R | 2dp, e.g. 100 = 1.00kW |
| 2005 | - | - | - | - | IO Status Word | | WORD | R | See Below |
| 2006 | - | - | - | - | Motor Output Torque | | U16 | R | 4096 = 100% |
| 2007 | - | - | - | P0-08 | DC Bus Voltage | | U16 | R | 600 = 600 Volts |
| 2008 | - | - | - | P0-09 | Heatsink Temperature | | S16 | R | 50 = 50°C |
| 2009 | - | - | - | P0-01 | Analog Input 1 | | S16 | R | 1dp, e.g. 500 = 50.0% |
| 2010 | - | - | - | P0-02 | Analog Input 2 | | U16 | R | 1dp, e.g. 500 = 50.0% |
| 2011 | - | - | - | - | Analog Output | | U16 | R | 1dp, e.g. 500 = 50.0% |
| 2012 | - | - | - | P0-05 | PI Output | | U16 | R | 1dp, e.g. 500 = 50.0% |
| 2013 | - | - | - | P0-20 | Internal Temperature | | S16 | R | 50 = 50°C |
| 2014 | - | - | - | P0-07 | Motor Output Voltage | | U16 | R | 200 = 200 Volts RMS |
| 2015 | - | - | - | - | IP66 Pot Input value | | U16 | R | 1dp, e.g. 500 = 50.0% |
| 2016 | - | - | - | - | Trip Code | | U16 | R | See Below |

### *11.3.1. Status Word 2 - Register 2001*

Status Word 2 provides an optional additional status word which may be used in additional or as an alternative to the status word in register 6. This status word is the first word in a block of 16 registers which may be read using a single "Read Multiple Registers" command enabling an efficient method to transfer important status information.

| Bit | Definition | Bit is HIGH under the following conditions: |
|---|---|---|
| 0 | Ready | No trip / fault<br>No mains loss<br>Hardware enable input is present |
| 1 | Running | Drive running |
| 2 | Tripped | Drive tripped |
| 3 | Standby | In Standby Mode |
| 4 | Fire Mode | Fire mode is active |
| 5 | Reserved | N/A |
| 6 | Speed Set-point Reached (At Speed) | Drive is enabled<br>Output Frequency = Set point |
| 7 | Below Minimum Speed | Drive is enabled<br>Output Frequency / Speed < P-02 |
| 8 | Overload | Output current > P-08 |
| 9 | Mains Loss | Mains power not detected |
| 10 | Heatsink > 85°C | Heatsink temperature > 85°C |
| 11 | Control Board > 80°C | Control PCB temperature > 80°C |
| 12 | Switching Frequency Reduction | PWM switching frequency is reduced from set value |
| 13 | Reverse Rotation | Motor rotates is in reverse direction |
| 14 | Reserved | N/A |
| 15 | Live Toggle Bit | This bit will toggle each time this register is read |

### *11.3.2. IO Status Word - Register 2005*

This register provides an extended status indication of drive input and output signal status.

| Bit | Definition | Bit is HIGH under the following conditions: |
|---|---|---|
| 0 | DI1 Status | DI1 ON |
| 1 | DI2 Status | DI2 ON |
| 2 | DI3 Status | DI3 ON |
| 3 | DI4 Status | DI4 ON |
| 4, 5 | Reserved | N/A |
| 6 | IP66 Switch FWD | IP66 FWD Switch FWD (IP66 Switched Drives only) |
| 7 | IP66 Switch REV | IP66 FWD Switch REV (IP66 Switched Drives only) |
| 8 | Digital Output Status | DO HIGH OR AO > 0 (Terminals 8 & 9) |
| 9 | Relay Output Status | Output Relay Closed |
| 10,11 | Reserved | N/A |
| 12 | Analog Input 1 Signal Lost (4-20mA) | AI1 Signal < 3mA (only with 4 – 20mA signal type selected) |
| 13 | Analog Input 2 signal Lost (4-20mA) | AI2 Signal < 3mA (only with 4 – 20mA signal type selected) |
| 13 | Reserved | N/A |
| 14 | IP66 Pot Input > 50% | IP66 integrated pot > 50% (IP66 Switched Units Only) |

### *11.3.3. Trip Code Register 2016*

In the event of a trip, this register returns the trip code number associated. Refer to the parameter list for a list of trip codes.

## 11.4. Additional Modbus RTU Registers / CAN Index Data – Control & Monitoring

| Modbus RTU Register | CAN Open Index | Sub Index | PDO Map | Parameter Number | Upper byte | Lower Byte | Format | Type | Scaling |
|---|---|---|---|---|---|---|---|---|---|
| 5 | 2004h | 0 | Y | - | High Resolution Frequency Setpoint | | S16 | R | See Below |
| 10 | 200Fh | 0 | Y | - | Motor Power | | U16 | R | 2dp, e.g. 100 = 1.00kW |
| 11 | 2012h | 0 | Y | P0-04 | Digital Input Status | | WORD | R | See Below |
| 12 | - | - | | P0-20 | Rating ID | | U16 | R | Internal Value |
| 13 | - | - | | P0-20 | Power rating | | U16 | R | 2dp, e.g. 37 = 0.37kW / HP |
| 14 | - | - | | P0-20 | Voltage rating | | U16 | R | See Below |
| 15 | 27E8h | 0 | N | P0-18 | IO processor software version | | U16 | R | 2dp, e.g. 300 = 3.00 |
| 16 | 27EAh | 0 | N | P0-18 | Motor control processor software version | | U16 | R | 2dp, e.g. 300 = 3.00 |
| 17 | - | - | | P0-20 | Drive type | | U16 | R | Internal Value |
| 18 | 201Ch | 0 | Y | P0-48 | Scope Channel 1 Data | | S16 | R | Internal Format |
| 19 | 201Dh | 0 | Y | P0-48 | Scope Channel 2 Data | | S16 | R | Internal Format |
| - | 201Eh | 0 | Y | P0-49 | Scope Channel 3 Data | | S16 | R | Internal Format |
| - | 201Fh | 0 | Y | P0-49 | Scope Channel 4 Data | | S16 | R | Internal Format |
| 20 | 2013h | 0 | Y | P0-01 | Analog 1 input result | | U16 | R | 1dp, e.g. 500 = 50.0% |
| 21 | 2014h | 0 | Y | P0-02 | Analog 2 input result | | U16 | R | 1dp, e.g. 500 = 50.0% |
| - | 2015h | 0 | Y | - | Analog Output % | | U16 | R | 1dp, e.g. 500 = 50.0% |
| 22 | - | - | | P0-03 | Pre-Ramp Speed Reference Value | | S16 | R | 1dp, e.g. 500 = 50.0Hz |
| 23 | 2011h | 0 | Y | P0-08 | DC Bus Voltage | | U16 | R | 600 = 600 Volts |
| 24 | - | | | P0-09 | Drive Power Stage Temperature | | S16 | R | 50 = 50°C |
| - | 2043h | 0 | Y | - | Control board temperature | | S16 | R | 50 = 50°C |

| Modbus RTU Register | CAN Open Index | Sub Index | PDO Map | Parameter Number | Upper byte | Lower Byte | Format | Type | Scaling |
|---|---|---|---|---|---|---|---|---|---|
| 25 | - | - | | P0-30 | Drive Serial Number 4 | | U16 | R | See Below |
| 26 | - | - | | P0-30 | Drive Serial Number 3 | | U16 | R | |
| 27 | - | - | | P0-30 | Drive Serial Number 2 | | U16 | R | |
| 28 | - | - | | P0-30 | Drive Serial Number 1 | | U16 | R | |
| 29 | 2017h | 0 | Y | - | Relay Output Status | | WORD | R | Bit 0 Indicates Relay Status 1 = Relay Contacts Closed |
| 30 | - | - | | - | Reserved | | - | R | No Function |
| 31 | - | - | | - | Reserved | | - | R | No Function |
| 32 | 203Ch | 0 | Y | P0-26 | kWh Meter | | U16 | R | 1dp, e.g. 100 = 10.0kWh |
| 33 | 203Dh | 0 | Y | P0-26 | MWh Meter | | U16 | R | 10 = 10MWh |
| 34 | 203Eh | 0 | Y | P0-10 | Running Time – Hours | | U16 | R | 1 = 1 Hour |
| 35 | 203Fh | 0 | Y | P0-10 | Running Time – Minutes & Seconds | | U16 | R | 100 = 100 Seconds |
| 36 | 2040h | 0 | Y | P0-14 | Run time since last enable – Hours | | U16 | R | 1 = 1 Hour |
| 37 | 2041h | 0 | Y | P0-14 | Run time since last enable – Minutes & seconds | | U16 | R | 100 = 100 Seconds |
| 38 | - | - | | - | Reserved | | U16 | R | No Function |
| 39 | 2010h | 0 | Y | P0-20 | Internal Drive Temperature | | S16 | R | 20 = 20C |
| 40 | 2044h | 0 | Y | - | Speed Reference (Internal Format) | | U16 | R | 3000 = 50Hz |
| 41 | - | - | | - | Reserved | | - | R | No Function |
| 42 | 2046h | 0 | Y | | Digital Pot / Keypad Reference | | U16 | R | 3000 = 50Hz |
| 43 | 2048h | 0 | Y | P0-07 | Output Voltage | | U16 | R | 100 = 100 Volts AC RMS |
| 44 | - | - | | - | Parameter Access Index | | U16 | R | See Below |
| 45 | - | - | | - | Parameter Access Value | | S16 | R | See Below |
| 46 | - | - | N | - | Parameter Checksum | | U16 | R | See Below |
| - | 2049h | 0 | Y | P0-05 | PI Output | | U16 | R | 1000 = 100.0% |
| - | 23E8h | 0 | N | - | Scope Index 12 | | RW | | |
| - | 23E9h | 0 | N | - | Scope Index 34 | | RW | | |
| - | 27D0h | 0 | N | P0-11 | Run Time Since Last Trip 1 – Hours | | U16 | R | 1 = 1 Hour |
| - | 27D1h | 0 | N | P0-11 | Run Time Since Last Trip 1 - Seconds | | U16 | R | 100 = 100 Seconds |
| - | 27D2h | 0 | N | P0-12 | Run Time Since Last Trip 2 – Hours | | U16 | R | 1 = 1 Hour |
| - | 27D3h | 0 | N | P0-12 | Run Time Since Last Trip 2 - Seconds | | U16 | R | 100 = 100 Seconds |
| - | 27D4h | 0 | N | P0-13 | Trip Log 2 & 1 | | WORD | R | |
| - | 27D5h | 0 | N | P0-13 | Trip Log 4 & 3 | | WORD | R | |
| - | 27D6h | 0 | N | P0-13 | Trip 1 Time – Hours | | U16 | R | 1 = 1 Hour |
| - | 26D7h | 0 | N | P0-13 | Trip 1 Time - Seconds | | U16 | R | 100 = 100 Seconds |
| - | 27D8h | 0 | N | P0-13 | Trip 2 Time – Hours | | U16 | R | 1 = 1 Hour |
| - | 27D9h | 0 | N | P0-13 | Trip 2 Time - Seconds | | U16 | R | 100 = 100 Seconds |
| - | 27DAh | 0 | N | P0-13 | Trip 3 Time – Hours | | U16 | R | 1 = 1 Hour |
| - | 27DBh | 0 | N | P0-13 | Trip 3 Time - Seconds | | U16 | R | 100 = 100 Seconds |
| - | 27DCh | 0 | N | P0-13 | Trip 4 Time – Hours | | U16 | R | 1 = 1 Hour |
| - | 27DDh | 0 | N | P0-13 | Trip 4 Time - Seconds | | U16 | R | 100 = 100 Seconds |

| Modbus RTU Register | CAN Open Index | Sub Index | PDO Map | Parameter Number | Upper byte | Lower Byte | Format | Type | Scaling |
|---|---|---|---|---|---|---|---|---|---|
| - | 27DEh | 0 | N | P0-23 | Time Heatsink > 85℃ – Hours | | U16 | R | 1 = 1 Hour |
| - | 27DFh | 0 | N | P0-23 | Time Heatsink > 85℃ - Seconds | | U16 | R | 100 = 100 Seconds |
| - | 27E0h | 0 | N | P0-24 | Time Internal > 80℃ – Hours | | U16 | R | 1 = 1 Hour |
| - | 27E1h | 0 | N | P0-24 | Time Internal > 80℃ - Seconds | | U16 | R | 100 = 100 Seconds |
| - | 27E2h | 0 | N | P0-27 | Fan Run Time – Hours | | U16 | R | 1 = 1 Hour |
| - | 27E3h | 0 | N | P0-27 | Fan Run Time - Seconds | | U16 | R | 100 = 100 Seconds |
| - | 27E4h | 0 | N | - | Fire Mode Active Time – Hours | | U16 | R | 1 = 1 Hour |
| - | 27E5h | 0 | N | - | Fire Mode Active Time - Seconds | | U16 | R | 100 = 100 Seconds |
| - | 27E6h | 0 | N | - | Power on Time – Hours | | U16 | R | 1 = 1 Hour |
| - | 27E7h | 0 | N | - | Power on Time - Seconds | | U16 | R | 100 = 100 Seconds |
| - | 27E9h | 0 | N | P0-28 | IO Checksum | | WORD | R | |
| - | 27EBh | 0 | N | P0-28 | DSP Checksum | | WORD | R | |
| - | 27ECh | 0 | N | P0-19 | Ambient Temperature Log 1 | | S16 | R | 50 = 50°C |
| - | 27Edh | 0 | N | P0-19 | Ambient Temperature Log 2 | | S16 | R | 50 = 50°C |
| - | 27EEh | 0 | N | P0-19 | Ambient Temperature Log 3 | | S16 | R | 50 = 50°C |
| - | 27EFh | 0 | N | P0-19 | Ambient Temperature Log 4 | | S16 | R | 50 = 50°C |
| - | 27F0h | 0 | N | P0-19 | Ambient Temperature Log 5 | | S16 | R | 50 = 50°C |
| - | 27F1h | 0 | N | P0-19 | Ambient Temperature Log 6 | | S16 | R | 50 = 50°C |
| - | 27F2h | 0 | N | P0-19 | Ambient Temperature Log 7 | | S16 | R | 50 = 50°C |
| - | 27F3h | 0 | N | P0-19 | Ambient Temperature Log 8 | | S16 | R | 50 = 50°C |
| - | 27F4h | 0 | N | P0-15 | DC Bus Voltage Log 1 | | U16 | R | 600 = 600 Volts |
| - | 27F5h | 0 | N | P0-15 | DC Bus Voltage Log 2 | | U16 | R | 600 = 600 Volts |
| - | 27F6h | 0 | N | P0-15 | DC Bus Voltage Log 3 | | U16 | R | 600 = 600 Volts |
| - | 27F7h | 0 | N | P0-15 | DC Bus Voltage Log 4 | | U16 | R | 600 = 600 Volts |
| - | 27F8h | 0 | N | P0-15 | DC Bus Voltage Log 5 | | U16 | R | 600 = 600 Volts |
| - | 27F9h | 0 | N | P0-15 | DC Bus Voltage Log 6 | | U16 | R | 600 = 600 Volts |
| - | 27FAh | 0 | N | P0-15 | DC Bus Voltage Log 7 | | U16 | R | 600 = 600 Volts |
| - | 27FBh | 0 | N | P0-15 | DC Bus Voltage Log 8 | | U16 | R | 600 = 600 Volts |
| - | 27FCh | 0 | N | P0-16 | Heatsink Temperature Log 1 | | S16 | R | 50 = 50°C |
| - | 27FDh | 0 | N | P0-16 | Heatsink Temperature Log 2 | | S16 | R | 50 = 50°C |
| - | 27FEh | 0 | N | P0-16 | Heatsink Temperature Log 3 | | S16 | R | 50 = 50°C |
| - | 27FFh | 0 | N | P0-16 | Heatsink Temperature Log 4 | | S16 | R | 50 = 50°C |
| - | 2800h | 0 | N | P0-16 | Heatsink Temperature Log 5 | | S16 | R | 50 = 50°C |
| - | 2801h | 0 | N | P0-16 | Heatsink Temperature Log 6 | | S16 | R | 50 = 50°C |
| - | 2802h | 0 | N | P0-16 | Heatsink Temperature Log 7 | | S16 | R | 50 = 50°C |
| - | 2803h | 0 | N | P0-16 | Heatsink Temperature Log 8 | | S16 | R | 50 = 50°C |
| - | 2804h | 0 | N | P0-17 | Motor Current Log 1 | | U16 | R | 1dp, e.g. 100 = 10.0A |
| - | 2805h | 0 | N | P0-17 | Motor Current Log 2 | | U16 | R | 1dp, e.g. 100 = 10.0A |
| - | 2806h | 0 | N | P0-17 | Motor Current Log 3 | | U16 | R | 1dp, e.g. 100 = 10.0A |
| - | 2807h | 0 | N | P0-17 | Motor Current Log 4 | | U16 | R | 1dp, e.g. 100 = 10.0A |
| - | 2808h | 0 | N | P0-17 | Motor Current Log 5 | | U16 | R | 1dp, e.g. 100 = 10.0A |
| - | 2809h | 0 | N | P0-17 | Motor Current Log 6 | | U16 | R | 1dp, e.g. 100 = 10.0A |
| - | 280Ah | 0 | N | P0-17 | Motor Current Log 7 | | U16 | R | 1dp, e.g. 100 = 10.0A |
| - | 280Bh | 0 | N | P0-17 | Motor Current Log 8 | | U16 | R | 1dp, e.g. 100 = 10.0A |

| Modbus RTU Register | CAN Open Index | Sub Index | PDO Map | Parameter Number | Upper byte | Lower Byte | Format | Type | Scaling |
|---|---|---|---|---|---|---|---|---|---|
| - | 280Ch | 0 | N | P0-18 | DC Ripple Log 1 | | U16 | R | 1 = 1 Volt |
| - | 280Dh | 0 | N | P0-18 | DC Ripple Log 2 | | U16 | R | 1 = 1 Volt |
| | 280Eh | 0 | N | P0-18 | DC Ripple Log 3 | | U16 | R | 1 = 1 Volt |
| - | 280Fh | 0 | N | P0-18 | DC Ripple Log 4 | | U16 | R | 1 = 1 Volt |
| - | 2810h | 0 | N | P0-18 | DC Ripple Log 5 | | U16 | R | 1 = 1 Volt |
| - | 2811h | 0 | N | P0-18 | DC Ripple Log 6 | | U16 | R | 1 = 1 Volt |
| - | 2812h | 0 | N | P0-18 | DC Ripple Log 7 | | U16 | R | 1 = 1 Volt |
| - | 2813h | 0 | N | P0-18 | DC Ripple Log 8 | | U16 | R | 1 = 1 Volt |
| - | 2814h | 0 | N | P0-25 | Estimated Rotor Speed | | S16 | R | |
| - | 2815h | 0 | N | P0-32 | Actual PWM Frequency | | U16 | R | |
| - | 2816h | 0 | N | P0-31 | Motor Current iD | | U16 | R | |
| - | 2817h | 0 | N | P0-31 | Motor Current iQ | | U16 | R | |
| - | 2818h | 0 | N | P0-33 | O-I Trip Counter | | U16 | R | |
| - | 2819h | 0 | N | P0-34 | O-V Trip Counter | | U16 | R | |
| - | 281Ah | 0 | N | P0-35 | U-V Trip Counter | | U16 | R | |
| - | 281Bh | 0 | N | P0-36 | O-T Trip Counter | | U16 | R | |
| - | 281Ch | 0 | N | P0-37 | bO-I Trip Counter | | U16 | R | |
| - | 281Dh | 0 | N | P0-38 | O-Heat Trip Counter | | U16 | R | |

### *11.4.1. High Resolution Speed Reference*

This register allows the user to set the speed reference value in the internal format, e.g. 3000 = 50.0Hz. This allows control resolution to 1 RPM with a 2-pole motor. The maximum allowed value is limited by P-01.

Either register 2 or register 5 can be used for speed reference control, however only one reference should be used in any control system, otherwise unexpected behaviour can result.

### *11.4.2. Scope Channel Data Values*

These registers show the scope present data sample value for the first two scope channels. The channel data source selection is carried out through Optitools Studio.

### *11.4.3. Modbus RTU Registers 25 - 28: Drive Serial Number*

The drive serial number may be read using these four registers. The serial number has 11 digits, stored as follows:

| Register 28 | | Register 27 | | | | Register 26 | | Register 25 | | |
|---|---|---|---|---|---|---|---|---|---|---|
| x | x | x | x | x | x | x | x | x | x | x |

e.g.

| | | | | | | | | | | | |
|---|---|---|---|---|---|---|---|---|---|---|---|
| Register 25 | | | 1 | | | | | | | | |
| Register 26 | | | 1 | | | | | | | | |
| Register 27 | | | 8745 | | | | | | | | |
| Register 28 | | | 57 | | | | | | | | |
| Drive Serial Number | 5 | 7 | 8 | 7 | 4 | 5 | 0 | 1 | 0 | 0 | 1 |

### *11.4.4. Parameter Checksum Modbus Register 46*

A checksum is calculated based on the present value of all user adjustable parameters and stored in Modbus Register 46. This may be read to determine if parameter settings have been adjusted.

# 12. Technical Data (External Interface)

## 12.1. Environmental

| | | | |
|---|---|---|---|
| Ambient Temperature | Storage and Transportation | -40 ... 60°C / -40 ... 140°F | |
| | Operating | -10 ... 50°C / 14 ... 122°F | UL approved |
| | | 40 ... 50°C / 104 ... 122°F | Without UL approval |
| Altitude | Operating | =<1000m | UL approved |
| | | =<4000m | Without UL approval |
| Relative Humidity | Operating | < 95% | Non-condensing, frost and moisture free |

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