SafeMOTION

User's manual

Version: **4.7 (2020-17-03)**

Order no.: **MAACPMSAFEMC-ENG**

1 General information

1.1 Manual history

Information:

This user's manual is only valid together with the "ACOPOSmulti" (MAACPM-ENG), "Decentralized motion control" (MAACPMDDE-ENG) and "Integrated safety technology" (MASAFETY-ENG) user's manuals.

Information:

B&R makes every effort to keep user's manuals as current as possible.
From a safety point of view, however, the current version must be downloaded from the B&R website (www.br-automation.com).

Version	Date	Comment
4.7	2020-03-17	Chapter "Safety technology / Integrated safety functions": Updated description for SBT, SLT and Safe Torque; updated SafeMOTION Help Tool V7.1. Chapter "System characteristics": Corrected description for "Detecting module-internal errors".
4.6	2019-08-01	Chapter "Safety technology / Integrated safety functions": Added new parameter "Encoder monitoring - Safe Encoder Mounting", updated description "Accuracy of current measurement" for SBTA/SLT, updated SafeMOTION Help Tool V6.0. ACOPOS P3 safety characteristics: Safe Operating Stop (SOS), Safe Stop 1 (SS1), Safe Stop 2 (SS2), Safely Limited Speed (SLS), Safe Direction (SDI), Safely Limited Increment (SLI), Safely Limited Acceleration (SLA), Safe Maximum Speed (SMS), Safely Limited Position (SLP), Safe Maximum Position (SMP), Safe Homing - Adjusted values.
4.5	2018-11-06	Added chapter "Safety technology / Integrated safety functions: Blackout mode, Safe Speed Observer, Safely Limited Torque". Added new parameter "SSO - External load enabled".
4.4	2017-11-13	Chapter "Safety technology": Added new parameter "FFS - Caused by encoder error" for FUNCTIONAL FAIL SAFE.
4.3	2017-07-13	Chapter ACOPOS P3 SafeMOTION / Technical data / 8EI SafeMOTION servo drives: Added 1-axis modules.
4.2	2016-12-12	Added chapter "ACOPOS P3 SafeMOTION". Chapter "System characteristics / Safety functions": Added table "ACOPOS P3 SafeMOTION". Chapter "System characteristics / System requirements": Added "ACOPOS P3 SafeMOTION". Added chapter "Safety technology / Integrated safety technology - SafeMOTION / Safe power transmission system / ACOPOS P3 SafeMOTION". Chapter "Safety technology / Configuring the safety functions / Safe pulse disabling": Added "ACOPOS P3 SafeMOTION". Chapter "Safety technology / Configuring the safety functions / Safe motor holding brake output": Added "ACOPOS P3 SafeMOTION". Added chapter "Safety technology / Safety characteristics - ACOPOS P3 SafeMOTION". Chapter "Safety technology / Integrated safety functions / Safe machine options": Added data structure for ACOPOS P3 SafeMOTION. Chapter "Safety technology / SafeMOTION register description / Parameters in the I/O configuration of the SafeMOTION module": • Group "Encoders": Modified description. • Group: Safety features: Added axis 1. • Group: Safety features: Added axis 2. • Group: Safety features: Added axis 3. Chapter "Safety technology / SafeMOTION register description / Parameters in SafeDESIGNER": Added information regarding SafeMOTION parameters for ACOPOS P3 SafeMOTION. Chapter "Safety technology / SafeMOTION register description / Channel list": Added channel list for ACOPOS P3 SafeMOTION. Chapter "Safety technology / Programming the safety application": • Modified figure "Inverter unit timing". • SafeMOTION Help Tool: Updated for ACOPOS P3 SafeMOTION / openSAFETY. • Application in SafeDESIGNER: Added table "Library openSAFETY_BuR_Motion_SF". • Accessing data on the SafeMOTION module / ACOPOS parameter ID: Added status and control bits for ACOPOS P3 SafeMOTION. • Library SafeMC: Added description of function blocks READ_SAFEOUT_DATA2 (read SafeOUT data 2) and READ_SAFEIN_DATA2 (read SafeIN data 2). Chapter "PLCopen Safety": Replaced figures for function blocks in library PLCopen_Motion_SF_2 for harmonization purposes. Chapter "PLCopen Safety": Added description of library openSAFETY_BuR_Motion_SF. Chapter "Standards and certifications": Added ACOPOS P3, harmonized with user's manual standards. Appendix: Added overview of safety level for safety functions used by the ACOPOS product family.
4.1	2016-10-10	Added chapter "ACOPOSmotor SafeMOTION". Chapter "System characteristics / Safety functions": Added table "ACOPOSmotor SafeMOTION". Chapter "System characteristics / System requirements": Added ACOPOSmotor SafeMOTION. Added chapter "Safety technology / Integrated safety technology - SafeMOTION / Safe power transmission system / ACOPOSmotor SafeMOTION". Chapter "Safety technology / Configuring the safety functions / Safe pulse disabling": Added ACOPOSmotor SafeMOTION.

Table 1: Manual history

<table>
<tr><th>Version</th><th>Date</th><th>Comment</th></tr>
<tr><td></td><td></td><td>Chapter "Safety technology / Configuring the safety functions / Safe motor holding brake output": Added ACOPOSmotor SafeMOTION.
Added chapter "Safety technology / Safety characteristics - ACOPOSmotor SafeMOTION".
Chapter "Safety technology / SafeMOTION register description / Parameters in the I/O configuration of the SafeMOTION module": Group "General": Revised description of SafeMODULE ID.
Chapter "Standards and certifications"
Updated "Applicable European directives".
Updated "Mechanical conditions in accordance with EN 61800-2" for 8CVI and 8DI.
Standards and definitions for safety technology: Removed standard-specific paragraphs regarding stop category.</td></tr>
<tr><td>4.0</td><td>2016-03-14</td><td>Renamed ACOPOSmulti SafeMOTION user manual to SafeMOTION user's manual.
SafeMOTION user's manual: Changed parameter names (chapter Safety technology / SafeMOTION register description / Parameter names)</td></tr>
<tr><td>3.10</td><td>2015-06-10</td><td>Chapter "Safety technology / Integrated safety technology / Safe machine options / Data structure": Corrected values for "Encoder type" SafeMOTION EnDat 2.2.</td></tr>
<tr><td>3.00</td><td>2015-01-21</td><td>Start of revision history publication
Merged ACOPOSmulti SafeMC EnDat 2.2, V2.4 and ACOPOSmulti user's manuals with SafeMC SinCos V1.1: ACOPOSmulti SafeMOTION.
The same model number (MAACPMSAFEMC) applies to ACOPOSmulti SafeMOTION.
<table>
<tr><th>Version</th><th>Date</th><th>Comment</th></tr>
<tr><td>1.00</td><td>2010-03-26</td><td>Start of revision history publication</td></tr>
<tr><td>2.2</td><td>2012-03-19</td><td>Updated manual for Safety Release 1.4.</td></tr>
<tr><td>2.3</td><td>2012-09-24</td><td>Chapter "General information": Disclaimer added
Chapter "System characteristics": Added "Detection of errors within the module".
Chapter "Safety technology / Integrated safety technology in the ACOPOSmulti with SafeMC / The safe power transmission system": Updated encoder options and danger notice.
Chapter "Safety technology / Safety characteristics": Added danger warning about measuring instruments.</td></tr>
<tr><td>2.4</td><td>2014-02-17</td><td>Chapter "General information / Protection against touching electrical parts": Updated danger warning.
Chapter "ACOPOSmulti with SafeMC": Added information about motor and encoder cables sorted by model number and danger warning about safe motor holding brake (X4A/X4B connectors).
Chapter "ACOPOSmulti with SafeMC / Overview": Added additional PE connection for 8BVE expansion modules.
Chapter "Safety technology / The safe power transmission system": Added information about motor cables.
Chapter "Safety technology / Principle - Implementing safety functions": Changed danger warning.
Chapter "Safety technology / Safe motor holding brake output": Added danger warning about safe motor holding brake output.
Chapter "Safety technology / Encoder mounting with proof of fatigue strength": Changed title (previously "Fault exclusion").
Chapter "Safety technology / Encoder mounting without proof of fatigue strength – Safe lag error monitoring": Shared content with ACOPOSmulti with SafeMC SinCos user's manual (previously "Safe monitoring without fault exclusion").
Chapter "Safety technology / Safety characteristics of integrated safety functions": Updated description of Safe Operating Stop (SOS).
Chapter "Safety technology / Integrated safety functions": Added SafePosition, SafeSpeed.
Chapter "Safety technology / Parameters in the I/O configuration of the SafeMC module": Removed group "General, Parameters".
Chapter "Safety technology / Programming the safety application": Added SBT with reference to ACOPOSmulti SafeMC SinCos, shared content.
Chapter "Safety technology / Programming the safety application / SafeMC Help Tool": Updated Safe Brake Test (SBT).
Chapter "Safety technology / Application in SafeDESIGNER": Added reference to ACOPOSmulti SafeMC SinCos, shared content.
Chapter "Safety technology / ACOPOSmulti parameter IDs": Shared content with ACOPOSmulti SafeMC SinCos, update.
Chapter "Safety technology / Library "SafeMC": Optimized and restructured description, added SBT (shared content with ACOPOSmulti SafeMC SinCos).
Chapter "Safety technology / Replacing a safe encoder/motor": Shared content with ACOPOSmulti with SafeMC SinCos user's manual.
Chapter "PLCopen Safety / SF_SafeMC_BR_V2": Section "Integrated safety functions" identical to section "Integrated safety functions" in chapter "Safety technology".
Chapter "PLCopen safety / Encoder mounting with proof of fatigue strength": Shared content with ACOPOSmulti with SafeMC SinCos user's manual (previously "Fault exclusion").</td></tr>
</table>
Table 2: Manual history - ACOPOSmulti SafeMC EnDat 2.2</td></tr>
</table>

Table 1: Manual history

<table>
<tr><th>Version</th><th>Date</th><th>Comment</th></tr>
<tr><td></td><td></td><td>
<table>
<tr><th>Version</th><th>Date</th><th>Comment</th></tr>
<tr><td></td><td></td><td>Chapter "PLCopen Safety / Encoder mounting without proof of fatigue strength – Safe lag error monitoring": Shared content with ACOPOSmulti with SafeMC SinCos user's manual (previously "Safe monitoring without fault exclusion").
Chapter "Standards and certifications": Removed EN 954-1, change ...in accordance with IFA (previously BGIA)... 2/2012, Additional environmental limit values in accordance with EN 61800-2: Removed footnote.</td></tr>
</table>
Table 2: Manual history - ACOPOSmulti SafeMC EnDat 2.2
<table>
<tr><th>Version</th><th>Date</th><th>Comment</th></tr>
<tr><td>1.0</td><td>September 2013</td><td>Start of revision history publication</td></tr>
<tr><td>1.1</td><td>February 2014</td><td>Chapter "Safety technology / Integrated safety functions / Safe Position, Safe Speed: Changed danger warnings, changed information, added example.
Chapter "Safety technology / Programming the safety application / SafeMC Help Tool": Updated Safe Brake Test (SBT).
Chapter "Standards and certifications": Change ...in accordance with IFA (previously BGIA)... 2/2012</td></tr>
<tr><td></td><td>March 2014</td><td>Chapter "Safety technology / Safety requirements for SinCos measuring instruments:
... Requirements from the "Error list for movement and position sensors in accordance with EN 61800-5-2:2007", Table D.16
... Performance level (PL) of the encoder with diagnosis of encoder evaluation
... Safety integrity level (SIL) of the encoder with diagnosis of encoder evaluation
"Excerpt" removed, replaced with "in accordance with..."; error list table: Added footnote regarding linear encoders.</td></tr>
</table>
Table 3: Manual history - ACOPOSmulti SafeMC SinCos
</td></tr>
</table>

Table 1: Manual history

1.1.1 Publications

Model number	Medium	Contents
MAACPMSAFEMC-ENG	Electronic	Complete
MAACPM-ENG	Electronic	Complete
MAACPP3-ENG	Electronic	Complete
MAACPMDDE-ENG	Electronic	Complete
MASAFETY-ENG	Electronic	Complete

Table 4: Publications

1.1.2 Release information

<table>
<tr><th>Manual version</th><th>Valid for</th></tr>
<tr><td>V4.4
V4.3
V4.2
V4.1
V4.0</td><td>SafeMOTION Safety Release 1.10</td></tr>
<tr><td>V3.00</td><td>SafeMOTION Safety Release 1.9
<table>
<tr><th>Manual version</th><th>Valid for</th></tr>
<tr><td>V1.00</td><td>Safety Release 1.3</td></tr>
<tr><td>V2.2
V2.3
V2.4</td><td>Safety Release 1.3 and Safety Release 1.4</td></tr>
</table>
Table 6: ACOPOSmulti SafeMC EnDat 2.2 - Release information
<table>
<tr><th>Manual version</th><th>Valid for</th></tr>
<tr><td>V1.0</td><td>Safety Release 1.4 to Safety Release 1.7 - ACOPOSmulti with SafeMC SinCos</td></tr>
</table>
Table 7: ACOPOSmulti with SafeMC SinCos - Release information
</td></tr>
</table>

Table 5: Release information

1.2 Safety guidelines

1.2.1 Organization of notices

Safety notices

Contain **only** information that warns of dangerous functions or situations.

Signal word	Description
Danger!	Failure to observe these safety guidelines and notices will result in death, severe injury or substantial damage to property.
Warning!	Failure to observe these safety guidelines and notices can result in death, severe injury or substantial damage to property.
Caution!	Failure to observe these safety guidelines and notices can result in minor injury or damage to property.
Notice!	Failure to observe these safety guidelines and notices can result in damage to property.

General notices

Contain **useful** information for users and instructions for avoiding malfunctions.

Signal word	Description
Information:	Useful information, application tips and instructions for avoiding malfunctions.

1.2.2 General information

B&R drive systems and servo motors have been designed, developed and manufactured for conventional use in industrial environments.

They were not designed, developed and manufactured for any use involving serious risks or hazards that could lead to death, injury, serious physical impairment or loss of any kind without the implementation of exceptionally stringent safety precautions.

In particular, these risks include the use of these devices to monitor nuclear reactions in nuclear power plants, in flight control or flight safety systems as well as in the control of mass transportation systems, medical life support systems or weapons systems.

Servo drives, inverter modules and frequency inverters from B&R are not dual-use goods per Annex I of Council Regulation (EC) No. 428/2009 | 3A225 as amended by Commission Delegated Regulation (EU) No. 2015/2420.
The electrical output frequency of these modules is monitored; if the limit frequency is exceeded, the current movement is aborted and an error is reported.

Servo drives, inverter modules and frequency inverters with the dual-use option are dual-use goods per Annex I of Council Regulation (EC) No. 428/2009 | 3A225 as amended by Commission Delegated Regulation (EU) No. 2015/2420.
The electrical output frequency of these modules is not monitored.

Modules with the dual-use option are subject to various export restrictions.

> ## Danger!
>
> **Drive systems and servo motors can have exposed parts with voltages applied (e.g. terminals) or hot surfaces. Additional hazards include moving machine parts. The removal of required covers, inappropriate use of the devices or their improper installation or operation can result in severe personal injury or damage to property.**

All tasks such as the transport, installation, commissioning and servicing of devices are only permitted to be carried out by qualified personnel. Qualified personnel are those familiar with the transport, mounting, installation, commissioning and operation of devices who also have the appropriate qualifications to perform these tasks. National accident prevention regulations must be observed.

The safety notices, information about connection conditions (nameplate and documentation) and limit values specified in the technical data must be read carefully before installation and commissioning and are to be observed in all cases.

1.2.3 Qualified personnel

Use of safety-related products is restricted to the following persons:

- Qualified personnel who are familiar with relevant safety concepts for automation technology as well as applicable standards and regulations
- Qualified personnel who plan, develop, install and commission safety equipment in machines and systems

Qualified personnel in the context of this manual's safety guidelines are those who, because of their training, experience and instruction combined with their knowledge of relevant standards, regulations, accident prevention guidelines and operating conditions, are qualified to carry out essential tasks and recognize and avoid potentially dangerous situations.

In this regard, sufficient language skills are also required in order to be able to properly understand this manual.

1.2.4 Intended use

Servo drives are components designed to be installed in electrical systems or machines. They are not permitted to be used unless the machine meets directive 2006/42/EC (machinery directive) as well as directive 2004/108/EC (EMC directive).

B&R drive systems are only permitted to be directly operated on grounded industrial power systems (TN, TN-C-S). When used in residential areas, commercial areas or small businesses, additional protective and filter measures must be implemented by the user.

> **Danger!**
>
> **Drive systems are not permitted to be operated directly on TT, IT and corner-grounded TN-S systems!**

Technical data as well as connection and environmental specifications can be found on the type plate and in this user's manual. Specifications regarding connection and environmental conditions must be observed!

> **Danger!**
>
> **Electronic devices are never completely failsafe. If the drive systems fails, the user is responsible for making sure that the motor is brought to a secure state.**

1.2.5 Safety technology disclaimer

The proper use of all B&R products must be guaranteed by the customer through the implementation of suitable training, instruction and documentation measures. The guidelines set forth in system user's manuals must be taken into consideration here as well. B&R has no obligation to provide verification or warnings with regard to the customer's purpose of using the delivered product.

Changes to the devices are not permitted when using safety-related components. Only certified products are permitted to be used. Currently valid product versions in each case are listed in the corresponding certificates. Current certificates are available on the B&R website (www.br-automation.com) in the Downloads section for the respective product. The use of non-certified products or product versions is not permitted.

All relevant information regarding these safety products must be read in the latest version of the related data sheet and the corresponding safety notices observed before the safety products are permitted to be operated. Certified data sheets are available on the B&R website (www.br-automation.com) in the Downloads section for the respective product.

B&R and its employees are not liable for any damages or loss resulting from the incorrect use of these products. The same applies to misuse that may result from specifications or statements made by B&R in connection with sales, support or application activities. It is the sole responsibility of the user to check all specifications and statements made by B&R for proper application as it pertains to safety-related applications. In addition, the user assumes sole responsibility for the proper design of the safety function as it pertains to safety-related applications.

1.2.6 Protection against electrostatic discharge

Electrical components that can be damaged by electrostatic discharge (ESD) must be handled accordingly.

1.2.6.1 Packaging

Electrical components with a housing do not require special ESD packaging but must be handled properly (see section 1.2.6.2 "Guidelines for proper ESD handling" on page 25).

Electrical components without a housing are protected by ESD-suitable packaging.

1.2.6.2 Guidelines for proper ESD handling

Electrical components with a housing

- Do not touch the connector contacts on connected cables.
- Do not touch the contact tips on circuit boards.

Electrical components without a housing

The following points apply in addition to the points listed under "Electrical components with a housing":

- Any persons handling electrical components or devices with installed electrical components must be grounded.
- Components are only permitted to be touched on their narrow sides or front plate.
- Components must always be placed on or stored in a suitable medium (ESD packaging, conductive foam, etc.).
  Metallic surfaces are not suitable storage surfaces!
- Components must not be subjected to electrostatic discharge (e.g. caused by charged plastics).
- Observe a minimum distance of 10 cm from monitors and television sets.
- Measuring instruments and equipment must be grounded.
- Probe tips of galvanically isolated measuring instruments must be temporarily discharged on suitably grounded surfaces before taking measurements.

Individual components

- ESD protective measures for individual components are thoroughly implemented at B&R (conductive floors, footwear, arm bands, etc.).
- These special ESD protection measures for individual components are not necessary for customers handling B&R products.

1.2.7 Transport and storage

During transport and storage, devices must be protected against undue stress (mechanical loads, temperature, moisture, corrosive atmospheres, etc.).

Drive systems contain components sensitive to electrostatic charges that can be damaged by inappropriate handling. It is therefore necessary to provide the required protective measures against electrostatic discharge when installing or removing these drive systems.

1.2.8 Handling and installation

> ## Warning!
>
> **B&R drive systems and servo motors can be heavy.**
>
> **During handling and installation of heavy B&R drive systems or servo motors, there is therefore the danger of personal injury or damage to property (through shearing, impacts, cutting or crushing). Suitable protective equipment (e.g. safety glasses, protective gloves, safety shoes, etc.) must be used whenever necessary!**

Installation must be performed according to this documentation using suitable equipment and tools.

Devices are only permitted to be installed by qualified personnel without voltage applied. Before installation, voltage to the control cabinet must be switched off and prevented from being switched on again.

General safety guidelines and national accident prevention regulations for working with high voltage systems must be observed.

Electrical installation must be carried out in accordance with applicable guidelines (e.g. line cross sections, fuses, protective ground connections, see also 2.5 "Dimensioning" on page 149).

1.2.9 Operation

1.2.9.1 Protection against touching electrical parts

> **Danger!**
>
> **To operate drive systems, it is necessary for certain parts to carry dangerous voltage levels over 60 VDC. Touching one of these parts can result in a life-threatening electric shock. This could lead to death, severe injury or damage to property.**

Before switching on a drive system, it is important to ensure that it is properly connected to ground potential (PE rail). Ground connections must be established even when testing or operating the drive system for a short time!

Before switching on the device, all parts that carry voltage must be securely covered. During operation, all covers and control cabinet doors must remain closed.

> **Danger!**
>
> **If the safety functions integrated in the drive system are used in an application, then they must be fully validated before the drive system is switched on for the first time. This could lead to death, severe injury or damage to property.**

Control and power connections can still carry voltage even if the motor is not turning. Touching these connections while the device is switched on is prohibited.

Before performing any work on drive systems, they must first be disconnected from the power system and prevented from being switched on again.

> **Danger!**
>
> **Dangerously high voltage!**
>
> **Before performing service work, disconnect the power supply and wait 5 minutes to ensure that the capacitors have discharged. Observe regulations!**
> **This delay time of 5 minutes begins as soon as all of the synchronous motors connected to the drive system that has been disconnected from the power supply have come to a standstill. If the synchronous motors are not stationary when the drive system is disconnected from the power supply, then the delay time must be extended accordingly.**

SafeMOTION modules are labeled with the following warning:

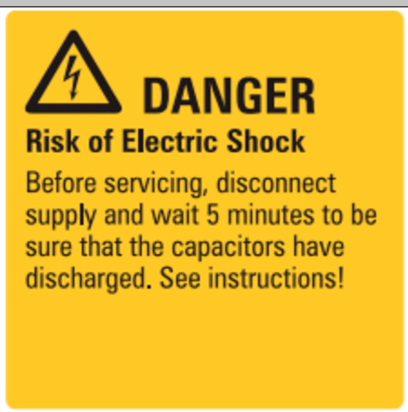
<table>
<tr><th>ACOPOSmulti SafeMOTION inverter module
ACOPOSmotor SafeMOTION</th><th>ACOPOS P3 SafeMOTION servo drives</th></tr>
<tr><td>

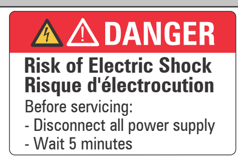
Figure 1: Warning sticker on the ACOPOSmulti module</td><td>
</td></tr>
</table>

Table 8: Warning sticker on SafeMOTION modules

The connections on the drive system for signal voltages in the voltage range 5 to 30 V are safely isolated circuits. The signal voltage connections and interfaces are therefore only permitted to be connected to devices or electrical components that have sufficient isolation per EN 61800-5-1 and protective extra-low voltage that corresponds to voltage class DVC A (SELV, PELV).

Never remove the electrical connections of drive systems while voltage is applied. In the worst case, arcs may occur that can subsequently cause personal injury and/or damage to contacts.

1.2.9.2 Protection against hazardous movements

Danger!

Improper control of motors can result in unintended hazardous movements! Such incorrect behavior can have various causes:

- **Incorrect installation or faults when handling components**
- **Improper or incomplete wiring**
- **Defective devices (drive system, motor, position encoder, cables, brake)**
- **Incorrect control (e.g. caused by software error)**

Some of the errors listed above can be detected and prevented by the drive system's internal monitoring. Nevertheless, it is still possible for the motor shaft to move any time after the device is switched on! For this reason, higher-level safety precautions need to be put in place to ensure that personnel and machines are protected.

The moving parts on machines must be shielded in such a way as to prevent unintentional access by personnel. This type of protection can be achieved by using stable mechanical protective equipment such as protective covers, protective fences, protective gates or photoelectric sensors.

Removing, bypassing or circumventing these protective measures and entering the area where movement takes place is prohibited.

A sufficient number of emergency stop buttons must be installed in direct proximity to the machine and be easily accessible at all times. This emergency stop equipment must be checked before the machine is put into operation.

On free running motors, the key (if present) must be removed or measures taken to prevent its ejection. The holding brake built into motors cannot prevent hoisting equipment from dropping hanging loads.

1.2.10 Functional safety data and specifications

For the characteristic values of individual safety functions, see 6.3 "Safety characteristics of integrated safety functions " on page 316.

Characteristic values are calculated based on a proof test interval of maximum 20 years. Since a proof test cannot be carried out for B&R drive systems, the proof test interval is the same as the system's mission time.

In accordance with the EN ISO 13849, EN 62061 and IEC 61508 standards, the safety functions described in 6 "Safety technology" on page 282 cannot be used beyond the specified mission time.

Danger!

Operating SafeMOTION modules beyond the specified mission time is not permitted!

The user must ensure that all SafeMOTION modules are replaced by new SafeMOTION modules or removed from operation before their mission time expires.

Information:

The end date of the mission time (MTE) is stored on all modules of B&R drive systems that perform a safety function and can be read out by the user as follows (for details, see Automation Help):

- **Parameter ID 10312 - EPROM_MISSION_TIME_END**
- **Library ACP10_MC - Function block MC_BR_GetHardwareInfo**

The end date of the mission time (MTE) can also be read directly from the housing of modules:

- **MTE: YYYYMMDD (YYYY ... Year, MM ... Month, DD ... Day)**

1.3 Environmentally friendly disposal

All B&R drive systems and servo motors are designed to inflict as little harm as possible on the environment.

1.3.1 Separation of materials

It is necessary to separate out the different materials so that devices can undergo an environmentally friendly recycling process.

Component	Disposal
Drive systems, servo motors, cables	Electronic recycling
Cardboard/Paper packaging	Paper/Cardboard recycling

Table 9: Environmentally friendly separation of materials

Disposal must take place per applicable legal regulations.

1.4 Cybersecurity disclaimer for products

B&R products communicate via a network interface and were developed for secure connection with internal and, if necessary, other networks such as the Internet.

Information:

In the following, B&R products are referred to as "product" and all types of networks (e.g. internal networks and the Internet) are referred to as "network".

It is the sole responsibility of the customer to establish and continuously ensure a secure connection between the product and the network. In addition, appropriate security measures must be implemented and maintained to protect the product and entire network from any security breaches, unauthorized access, interference, digital intrusion, data leakage and/or theft of data or information.

B&R Industrial Automation GmbH and its subsidiaries are not liable for damages and/or losses in connection with security breaches, unauthorized access, interference, digital intrusion, data leakage and/or theft of data or information.

The aforementioned appropriate security measures include, for example:

- Segmentation of the network (e.g. separation of the IT network from the control network[1)])
- Use of firewalls
- Use of authentication mechanisms
- Encryption of data
- Use of anti-malware software

Before B&R releases products or updates, they are subjected to appropriate functional testing. Independently of this, we recommend that our customers develop their own test processes in order to be able to check the effects of changes in advance. Such changes include, for example:

- Installation of product updates
- Significant system modifications such as configuration changes
- Deployment of updates or patches for third-party software (non-B&R software)
- Hardware replacement

These tests should ensure that implemented security measures remain effective and that systems in the customer's environment behave as expected.

[1)] The term "control network" refers to computer networks used to connect control systems. The control network can be divided into zones, and there can be several separate control networks within a company or site. The term "control systems" refers to all types of B&R products such as controllers (e.g. X20), HMI systems (e.g. Power Panel T30), process control systems (e.g. APROL) and supporting systems such as engineering workstations with Automation Studio.

2 ACOPOSmulti SafeMOTION

2.1 Configuration of an ACOPOSmulti drive system

The ACOPOSmulti drive system consists of a mounting plate, various modules (power supply, auxiliary supply, inverter, expansion and capacitor modules), plug-in modules as well as a line filter and – only in combination with 8BVP active power supply modules – a regeneration choke.

There are 10 steps necessary to configure the ACOPOSmulti:

1. Determine the cooling method.
    - Standard cooling (wall mounting)
    - Feed-through cooling (feed-through mounting)
    - Oil/Water cooling (cold plate mounting)
2. Define or verify the supply voltage range and network configuration.
3. Select the ACOPOSmulti inverter modules according to the application requirements.
    - 1-axis modules
    - 2-axis modules
4. Select the ACOPOSmulti plug-in modules for the motor encoder and external axis encoder according to the application requirements.
5. Determine if it should be possible to extend the ACOPOSmulti drive system:
   If so, determine the number of optional slots on the mounting plate for other ACOPOSmulti modules
6. Select ACOPOSmulti power supply modules according to the application requirements (active/passive power supply module) based on the total power of the ACOPOSmulti inverter modules needed (derating information must be taken into consideration if the supply voltage <3x 400 VAC)
    - Passive power supply modules[2)]
    - Active power supply modules
7. Check the maximum chargeable DC bus capacitance.
8. Select the ACOPOSmulti auxiliary supply module based on the total power required for the 24 VDC supply of the selected ACOPOSmulti module, ACOPOSmulti plug-in modules as well as the peripheral supply (e.g. PLC, actuators, motor holding brakes, sensors)
    - 24 V internal
    - 24 V internal, 24 V external
    - 24 V internal, 24 V external, 24 V external supply
    - 42 V external

> **Danger!**
>
> **ACOPOSmulti auxiliary supply modules (8B0C0320Hx00.00A-1) are not permitted to be used in combination with ACOPOSmulti SafeMOTION inverter modules!**

9. Determine the total number of slots by adding the widths of all selected ACOPOSmulti modules (including optional slots).
10. Select the ACOPOSmulti mounting plate according to the total number of slots required and specified cooling method.

2) Step 8 can be skipped if the 24 VDC is supplied to the selected ACOPOSmulti inverter modules by passive power supply module 8B0P0110Hx00.000-1.

2.2 Status indicators

Status indicators are located on the black cover of each module.

2.2.1 8BVI SafeMOTION inverter modules

2.2.1.1 1-axis modules

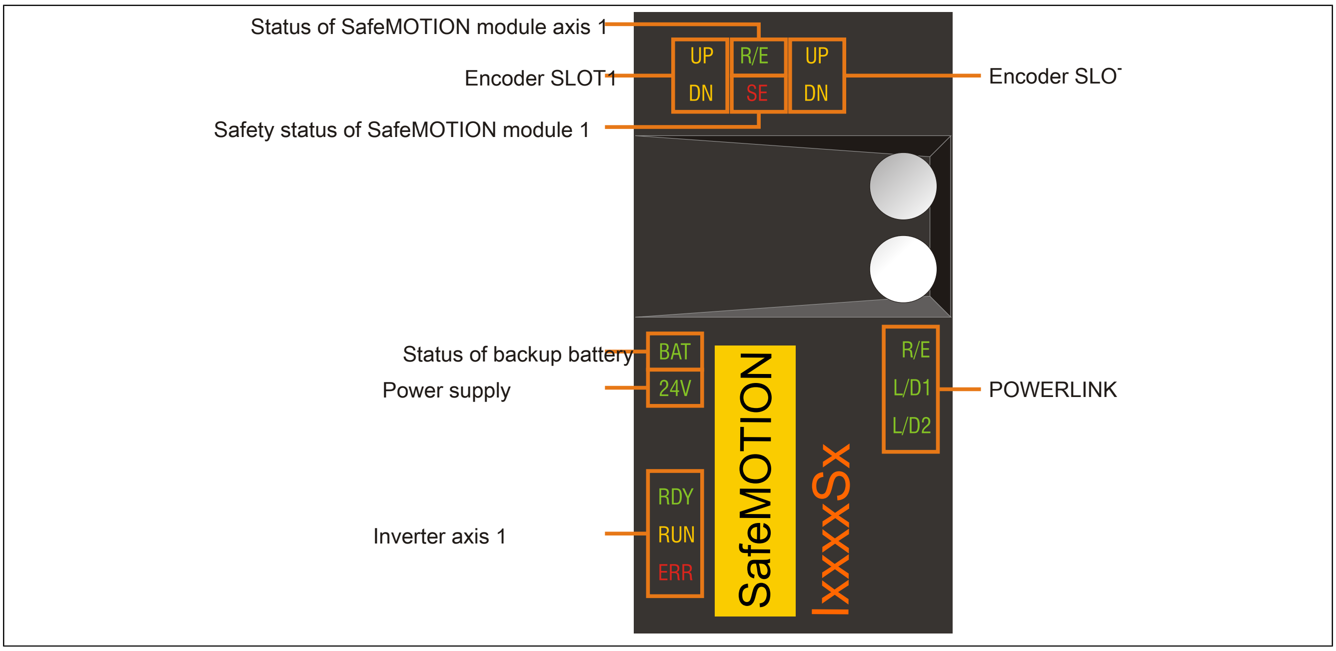


Figure 2: 8BVI SafeMOTION inverter modules (1-axis modules) - Status indicator groups

2.2.1.1.1 LED status indicators

Status indicator group	Label	Color	Function	Description
POWERLINK	R/E	Green/Red	Ready/Error	see "POWERLINK - LED status indicators" on page 32
	L/D1	Green	Link/Data activity on port 1	
	L/D2		Link/Data activity on port 2	
Inverter axis 1	RDY	Green	Ready	see "RDY, RUN, ERR (8BVI, 8BVP, 8B0P) - LED status indicators" on page 32
	RUN	Orange	Run	
	ERR	Red	Error	
Status of backup battery	BAT	Green/Red	Ready/Error	see "Backup battery (ACOPOSmulti SafeMOTION EnDat 2.2) - LED status indicators" on page 32
Power supply	24 V	Green	24 V OK	The 24 V module power supply voltage is within the tolerance range.
Encoder SLOT1	UP	Orange	Encoder direction of rotation +	Indicates that the position of the connected encoder is changing in the positive direction. The faster the encoder position changes, the brighter the LED is lit.
	DN		Encoder direction of rotation -	Indicates that the position of the connected encoder is changing in the negative direction. The faster the encoder position changes, the brighter the LED is lit.
Encoder SLOT2	UP	Orange	Encoder direction of rotation +	see Encoder SLOT1
	DN		Encoder direction of rotation -	
Status of SafeMOTION module axis 1	R/E	Green/Red	Ready/Error	see "SafeMOTION module - LED status indicators" on page 33
Safety status of SafeMOTION module 1	SE	Red	Safe/Error	

Table 10: 8BVI SafeMOTION inverter modules (1-axis modules) - LED status indicators

2.2.1.2 2-axis modules

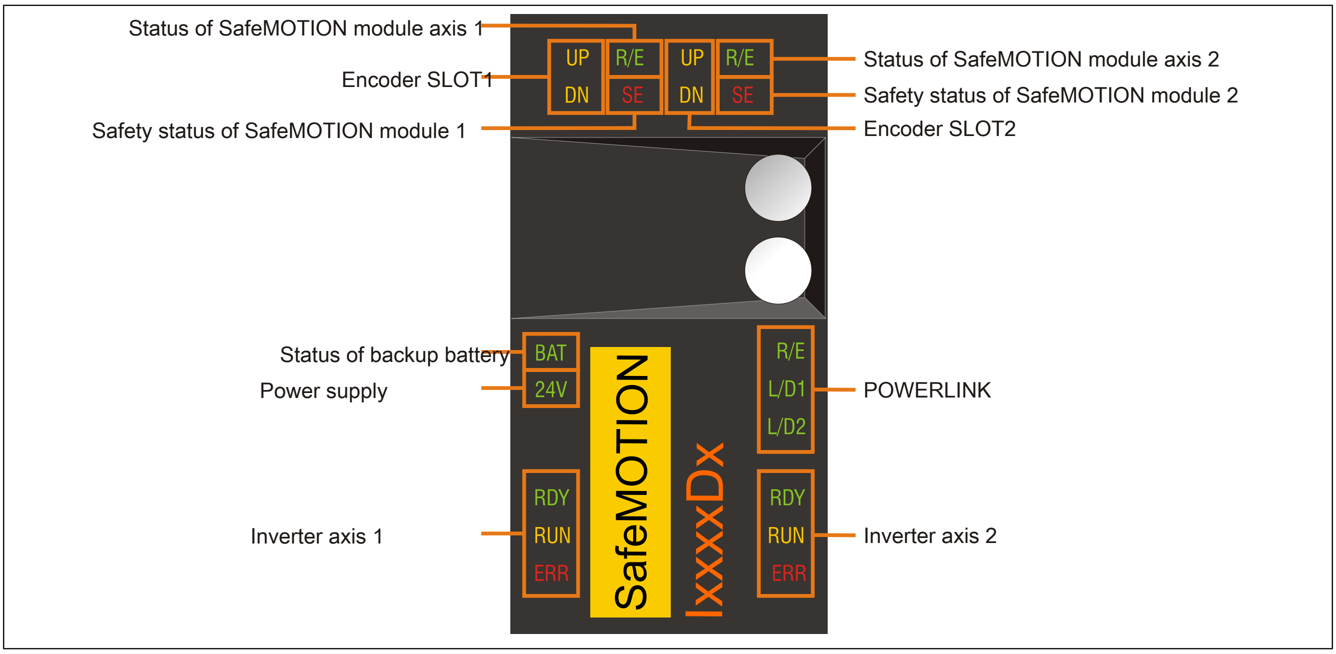


Figure 3: 8BVI SafeMOTION inverter modules (2-axis modules) - Status indicator groups

2.2.1.2.1 LED status indicators

Status indicator group	Label	Color	Function	Description
POWERLINK	R/E	Green/Red	Ready/Error	see "POWERLINK - LED status indicators" on page 32
	L/D1	Green	Link/Data activity on port 1	
	L/D2		Link/Data activity on port 2	
Inverter axis 1	RDY	Green	Ready	see "RDY, RUN, ERR (8BVI, 8BVP, 8B0P) - LED status indicators" on page 32
	RUN	Orange	Run	
	ERR	Red	Error	
Inverter axis 2	RDY	Green	Ready	See inverter axis 1
	RUN	Orange	Run	
	ERR	Red	Error	
Status of backup battery	BAT	Green/Red	Ready/Error	see "Backup battery (ACOPOSmulti SafeMOTION EnDat 2.2) - LED status indicators" on page 32
Power supply	24 V	Green	24 V OK	The 24 V module power supply voltage is within the tolerance range.
Encoder SLOT1	UP	Orange	Encoder direction of rotation +	The encoder position of the connected encoder is changing in the positive direction. The faster the encoder position changes, the brighter the LED is lit.
	DN		Encoder direction of rotation -	The encoder position of the connected encoder is changing in the negative direction. The faster the encoder position changes, the brighter the LED is lit.
Encoder SLOT2	UP	Orange	Encoder direction of rotation +	See encoder SLOT1.
	DN		Encoder direction of rotation -	
Status of SafeMOTION module axis 1	R/E	Green/Red	Ready/Error	see "SafeMOTION module - LED status indicators" on page 33
Safety status of SafeMOTION module 1	SE	Red	Safe/Error	
Status of SafeMOTION module axis 2	R/E	Green/Red	Ready/Error	
Safety status of SafeMOTION module 2	SE	Red	Safe/Error	

Table 11: 8BVI SafeMOTION inverter modules (2-axis modules) - LED status indicators

2.2.1.3 RDY, RUN, ERR (8BVI, 8BVP, 8B0P) - LED status indicators

Label	Color	Function	Description	
RDY	Green	Ready	Solid green	The module is operational and the power stage can be enabled (operating system present and booted, no permanent or temporary errors).
			Blinking green [1]	The module is not ready for operation. **Examples:** • No signal on one or both enable inputs • DC bus voltage outside the tolerance range • Overtemperature on the motor (temperature sensor) • Motor feedback not connected or defective • Motor temperature sensor not connected or defective • Overtemperature on the module (IGBT junction, heat sink, etc.) • Disturbance on network
RUN	Orange	Run	Solid orange	The module's power stage is enabled.
ERR	Red	Error	Solid red [1]	There is a permanent error on the module. **Examples:** • Permanent overcurrent • Invalid data in EPROM

Table 12: RDY, RUN, ERR (8BVI, 8BVP, 8B0P) - LED status indicators

1) Firmware V2.130 and later.

2.2.1.4 POWERLINK - LED status indicators

Label	Color	Function	Description	
R/E	Green/Red	Ready/Error	LED off	The module is not supplied with power or network interface initialization has failed.
			Solid red	The POWERLINK node number of the module is 0.
			Blinking red/green	The client is in an error state (drops out of cyclic operation).
			Blinking green (1x)	The client detects a valid POWERLINK frame on the network.
			Blinking green (2x)	Cyclic operation on the network is taking place, but the client itself is not yet a participant.
			Blinking green (3x)	Cyclic operation of the client is in preparation.
			Solid green	The client is participating in cyclic operation.
			Flickering green	The client is not participating in cyclic operation and also does not detect any other stations on the network participating in cyclic operation.
L/D1	Green	Link/Data activity on port 1	Solid green	A physical connection has been established to another station on the network.
			Blinking green	Activity on port 1
L/D2	Green	Link/Data activity on port 2	Solid green	A physical connection has been established to another station on the network.
			Blinking green	Activity on port 2

Table 13: POWERLINK - LED status indicators

2.2.1.5 Backup battery (ACOPOSmulti SafeMOTION EnDat 2.2) - LED status indicators

Label	Color	Function	Description	
BAT	Green/Red	Ready/Error	LED off	**Possible causes:** • The voltage of the installed backup battery is within the tolerance range, but an EnDat encoder with backup battery is not connected. • A battery-backed EnDat encoder is connected and registering "Battery OK", but the module's firmware version does not support EnDat encoders with battery backup.
			Solid green	A battery-backed EnDat encoder is connected and registering "Battery OK" (voltage of the installed backup battery is within the tolerance range).
			Solid red	A battery-backed EnDat encoder is connected and registering "Battery not OK". **Possible causes:** • Voltage of the installed backup battery outside of tolerance range • No backup battery installed in module

Table 14: Backup battery - LED status indicators

2.2.1.6 SafeMOTION module - LED status indicators

There are 3 additional LEDs for each safe axis behind the front cover of an ACOPOSmulti SafeMOTION inverter module:

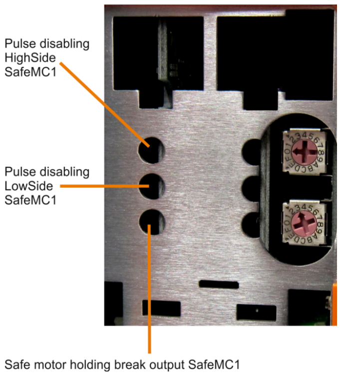


Figure 4: 1-axis modules

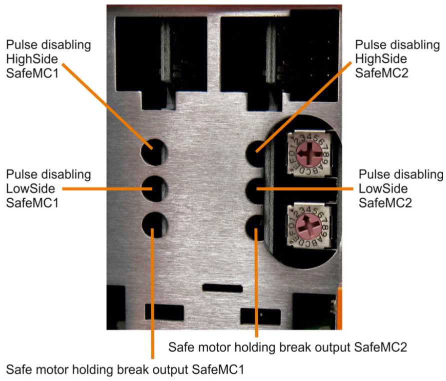


Figure 5: 2-axis modules

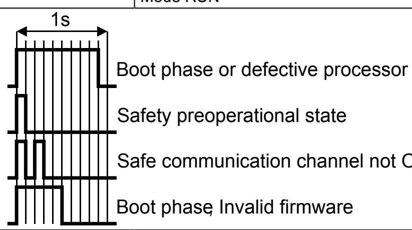
LED	Color		Description
R/E	Green	Red	
	Off	Off	Module not supplied with power, no communication
	Single flash		Mode "Unlink"
	Double flash		Updating the firmware
	Blinking		Mode PREOPERATIONAL
	On		Mode RUN
	On	Single flash, inverse	Safety-related firmware invalid
		Triple flash, inverse	Updating safety-related firmware
		On	Communication error
	Off	On	Error
LED status indicator Pulse disabling output, high-side	Red		Warning/Error on the channel During the startup phase, the channel LEDs are always lit constantly red.
	Orange		24 V on the output
	Off		0 V on the output
LED status indicator Pulse disabling output, low-side	Red		Warning/Error on the channel During the startup phase, the channel LEDs are always lit constantly red.
	Orange		24 V on the output
	Off		0 V on the output
LED status indicator Motor holding brake output	Red		Warning/Error on the channel During the startup phase, the channel LEDs are always lit constantly red.
	Orange		24 V on the output
	Off		0 V on the output
SE	Red	Off	Mode RUN
			
		On	Non-acknowledgeable error state, FAIL SAFE state
	The two "SE" indicators are two separate LEDs that show the states of safety processor 1 and safety processor 2. This is only distinguishable when the front cover is open, however.		

Table 15: SafeMOTION module - LED status indicators

Danger!

Constantly lit "SE" LEDs indicate a non-acknowledgeable FAIL SAFE state. The cause of this could be a defective module or faulty configuration.
Check the entries in the logbook! If you are able to rule out a faulty configuration, then the module is defective and must be replaced immediately.

It is your responsibility to ensure that all necessary repair measures or corrections to the configuration are initiated after an error occurs since subsequent errors can result in dangerous situations!

2.2.1.7 Status changes when starting up the operating system loader

The following intervals are used for the LED status indicators:

Width of box: 50 ms
Repeats after: 3,000 ms

Status	LED	Display
1. Boot procedure for base hardware active	RDY	
	RUN	
	ERR	
2. Network configuration active	RDY	
	RUN	
	ERR	
3. Waiting for network telegram	RDY	
	RUN	
	ERR	
4. Network communication active	RDY	
	RUN	
	ERR	
5. ACOPOS operating system being transferred/burned 1)	RDY	
	RUN	
	ERR	

Table 16: Status changes when starting up the operating system loader

1) Firmware V2.140 and later.

2.2.1.8 Setting the POWERLINK node number

The POWERLINK node number can be set using the two coded hexadecimal rotary switches located behind the black cover.

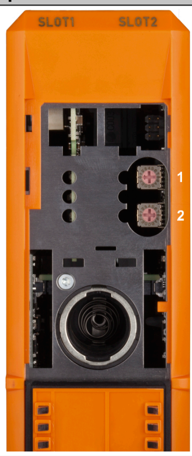
Figure		Coded rotary switches	POWERLINK node number
Cover closed	**Cover open**		
		1	Position 16
		2	Position 1
		The POWERLINK node number change takes effect the next time the ACOPOSmulti drive system is switched on. **Information:** **Node numbers in the range from 0x01 to 0xFD are allowed.** ***Recommendation*: For compatibility reasons, avoid node numbers between 0xF0 and 0xFD since these are intended for future system expansions.** **Node numbers 0x00, 0xFE and 0xFF are reserved and therefore not permitted to be set.**	

Table 17: Setting the POWERLINK node number

2.3 Data sheets

2.3.1 Module overview

Safe single-width inverter modules (1-axis modules)

Model number	Short description	Page
8BVI0014HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 1.9 A, HV, cold plate or feed-through mounting	36
8BVI0014HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 1.9 A, HV, cold plate or feed-through mounting	36
8BVI0014HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 1.9 A, HV, wall mounting	36
8BVI0014HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 1.9 A, HV, wall mounting	36
8BVI0028HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 3.8 A, HV, cold plate or feed-through mounting	41
8BVI0028HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 3.8 A, HV, cold plate or feed-through mounting	41
8BVI0028HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 3.8 A, HV, wall mounting	41
8BVI0028HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 3.8 A, HV, wall mounting	41
8BVI0055HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 7.6 A, HV, cold plate or feed-through mounting	47
8BVI0055HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 7.6 A, HV, cold plate or feed-through mounting	47
8BVI0055HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 7.6 A, HV, wall mounting	47
8BVI0055HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 7.6 A, HV, wall mounting	47
8BVI0110HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 15.1 A, HV, cold plate or feed-through mounting	52
8BVI0110HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 15.1 A, HV, cold plate or feed-through mounting	52
8BVI0110HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 15.1 A, HV, wall mounting	52
8BVI0110HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 15.1 A, HV, wall mounting	52

Safe double-width inverter modules (1-axis modules)

Model number	Short description	Page
8BVI0220HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 22 A, HV, cold plate or feed-through mounting	63
8BVI0220HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 22 A, HV, cold plate or feed-through mounting	63
8BVI0220HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 22 A, HV, wall mounting	63
8BVI0220HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 22 A, HV, wall mounting	63
8BVI0330HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 33 A, HV, cold plate or feed-through mounting	69
8BVI0330HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 33 A, HV, cold plate or feed-through mounting	69
8BVI0330HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 33 A, HV, wall mounting	69
8BVI0330HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 33 A, HV, wall mounting	69
8BVI0440HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 44 A, HV, cold plate or feed-through mounting	74
8BVI0440HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 44 A, HV, cold plate or feed-through mounting	74
8BVI0440HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 44 A, HV, wall mounting	74
8BVI0440HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 44 A, HV, wall mounting	74

Safe 4x width inverter modules (1-axis modules)

Model number	Short description	Page
8BVI0660HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 66 A, HV, cold plate or feed-through mounting	118
8BVI0660HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 66 A, HV, cold plate or feed-through mounting	118
8BVI0660HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 66 A, HV, wall mounting	118
8BVI0660HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 66 A, HV, wall mounting	118
8BVI0880HCSA.004-1	ACOPOSmulti SafeMOTION SinCos inverter module, 88 A, HV, cold plate or feed-through mounting	124
8BVI0880HCSS.004-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 88 A, HV, cold plate or feed-through mounting	124
8BVI0880HWSA.004-1	ACOPOSmulti SafeMOTION SinCos inverter module, 88 A, HV, wall mounting	124
8BVI0880HWSS.004-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 88 A, HV, wall mounting	124

Safe 8x width inverter modules (1-axis modules)

Model number	Short description	Page
8BVI1650HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 165 A, HV, cold plate or feed-through mounting	137

Safe single-width inverter modules (2-axis modules)

Model number	Short description	Page
8BVI0014HCDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 1.9 A, HV, cold plate or feed-through mounting, 2 axes	86
8BVI0014HWDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 1.9 A, HV, wall mounting, 2 axes	86
8BVI0028HCDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 3.8 A, HV, cold plate or feed-through mounting, 2 axes	90
8BVI0028HWDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 3.8 A, HV, wall mounting, 2 axes	90
8BVI0055HCDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 7.6 A, HV, cold plate or feed-through mounting, 2 axes	95
8BVI0055HWDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 7.6 A, HV, wall mounting, 2 axes	95

Safe double-width inverter modules (2-axis modules)

Model number	Short description	Page
8BVI0110HCDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 15.1 A, HV, cold plate or feed-through mounting, 2 axes	104
8BVI0110HWDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 15.1 A, HV, wall mounting, 2 axes	104
8BVI0220HCDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 22 A, HV, cold plate or feed-through mounting, 2 axes	108
8BVI0220HWDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 22 A, HV, wall mounting, 2 axes	108

2.3.2 Safe single-width inverter modules (1-axis modules)

2.3.2.1 8BVI0014HCSS.000-1, 8BVI0014HWSS.000-1, 8BVI0014HCSA.000-1, 8BVI0014HWSA.000-1

2.3.2.1.1 General information

- Clearly structured, straightforward implementation via network-based safety technology
- Modular expandability through virtual wiring
- Immediate triggering of safety function due to short cycle times
- Easy implementation with transparent control and status information, even in the standard application
- Compact design

2.3.2.1.2 Order data

Model number	Short description	Figure
	Cold plate or feed-through mounting	
8BVI0014HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 1.9 A, HV, cold plate or feed-through mounting	
8BVI0014HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 1.9 A, HV, cold plate or feed-through mounting	
	Wall mounting	
8BVI0014HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 1.9 A, HV, wall mounting	
8BVI0014HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 1.9 A, HV, wall mounting	
	Required accessories	
	Terminal block sets	
8BZVI0055SS.000-1A	Screw clamp set for ACOPOSmulti 8BVI00xxHxSS and 8BVI00xxHxSA modules: 1x 8TB3104.204G-11, 1x 8TB2104.203L-00, 1x 8TB2108.2010-00	
	Optional accessories	
	Accessory sets	
8BXB000.0000-00	ACOPOSmulti accessory set for encoder buffering consists of the following: 1 lithium battery AA 3.6 V, 1 cover for battery compartment	
	Fan modules	
8BXF001.0000-00	ACOPOSmulti fan module, replacement fan for ACOPOSmulti modules (8BxP/8B0C/8BVI/8BVE/8B0K)	
	POWERLINK/Ethernet cables	
X20CA0E61.00020	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.2 m	
X20CA0E61.00025	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.25 m	
X20CA0E61.00030	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.3 m	
X20CA0E61.00035	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.35 m	
X20CA0E61.00050	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.5 m	
X20CA0E61.00100	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 1 m	
	Plug-in modules	
8BAC0120.000-1	ACOPOSmulti plug-in module, EnDat 2.1 interface	
8BAC0120.001-2	ACOPOSmulti plug-in module, EnDat 2.2 interface	
8BAC0121.000-1	ACOPOSmulti plug-in module, HIPERFACE interface	
8BAC0122.000-1	ACOPOSmulti plug-in module, resolver interface 10 kHz	
8BAC0123.000-1	ACOPOSmulti plug-in module, incremental encoder and SSI absolute encoder interface for RS422 signals	
8BAC0123.001-1	ACOPOSmulti plug-in module, incremental encoder interface for 5 V single-ended and 5 V differential signals	
8BAC0123.002-1	ACOPOSmulti plug-in module, incremental encoder interface for 24 V single-ended and 24 V differential signals	
8BAC0124.000-1	ACOPOSmulti plug-in module, SinCos interface	
8BAC0125.000-1	ACOPOSmulti plug-in module, SinCos EnDat 2.1/SSI/BiSS interface	
8BAC0130.000-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 2 digital outputs, 500 mA, max. 1.25 kHz, 2 digital inputs 24 VDC	
8BAC0130.001-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 4 digital outputs, 500 mA, max. 1.25 kHz	
8BAC0132.000-1	ACOPOSmulti plug-in module, 4 analog inputs ±10 V	
8BAC0133.000-1	ACOPOSmulti plug-in module, 3 RS422 outputs for ABR encoder emulation, 1 MHz	
	Shield component sets	
8SCS000.0000-00	ACOPOSmulti shield component set: 1 shield plate 1x type 0, 1 hose clamp, B 9 mm, D 12-22 mm	
8SCS002.0000-00	ACOPOSmulti shield component set: 1x clamping plate; 2x clamps D 4-13.5 mm; 4x screws	

Table 18: 8BVI0014HCSS.000-1, 8BVI0014HCSA.000-1, 8BVI0014HWSS.000-1, 8BVI0014HWSA.000-1 - Order data

Model number	Short description	Figure
8SCS009.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK8-14, 1x shield connection clamp SK14	
	Terminal blocks	
8TB2104.203L-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, L keying: 1010	
8TB2108.2010-00	8-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	
8TB3104.204G-11	4-pin screw clamp, single row, spacing: 7.62 mm, label 4: PE W V U, G keying: 0110	

Table 18: 8BVI0014HCSS.000-1, 8BVI0014HCSA.000-1, 8BVI0014HWSS.000-1, 8BVI0014HWSA.000-1 - Order data

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

ACOPOSmulti SafeMOTION SinCos

Information:

Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.

Information:

Only 8BCS encoder cables from B&R are permitted to be connected to the encoder interfaces on B&R standard motors.

For details, see 6.1.2 "Safe power transmission system " on page 283.

2.3.2.1.3 Technical data

Model number	8BVI0014HCSS.000-1	8BVI0014HWSS.000-1	8BVI0014HCSA.000-1	8BVI0014HWSA.000-1
General information				
B&R ID code	0xAA0C	0xAA0E	0xE0B0	0xE0B1
Cooling and mounting type	Cold plate or feed-through mounting	Wall mounting	Cold plate or feed-through mounting	Wall mounting
Slots for plug-in modules	2 [1]			
Certifications				
CE	Yes			
Functional safety[2]	Yes (openSAFETY)			
UL	cULus E225616 Power conversion equipment			
EAC	Yes			
KC	Yes		-	
DC bus connection				
Voltage				
Nominal	750 VDC			
Continuous power consumption [3]	1.46 kW			
Power dissipation depending on switching frequency [4]				
Switching frequency 5 kHz	[0.6 * I_M^2 + 1.3 * I_M + 60] W			
Switching frequency 10 kHz	[0.97 * I_M^2 + 0.5 * I_M + 110] W			
Switching frequency 20 kHz	[1.7 * I_M^2 - 0.7 * I_M + 225] W			
DC bus capacitance	165 µF			
Variant	ACOPOSmulti backplane			
24 VDC power supply				
Input voltage	25 VDC ±1.6%			
Input capacitance	23.5 µF			
Max. power consumption	18 W + P_{SMC1} + P_{SLOT2} + $P_{24\,V\,Out}$ + $P_{HoldingBrake}$ [5]		25 W + P_{SMC1} + P_{SLOT2} + $P_{24\,V\,Out}$ + $P_{HoldingBrake}$ [6]	
Variant	ACOPOSmulti backplane			
24 VDC output				
Quantity	2			

Table 19: 8BVI0014HCSS.000-1, 8BVI0014HWSS.000-1, 8BVI0014HCSA.000-1, 8BVI0014HWSA.000-1 - Technical data

Model number	8BVI0014HCSS.000-1	8BVI0014HWSS.000-1	8BVI0014HCSA.000-1	8BVI0014HWSA.000-1
Output voltage				
DC bus voltage (U_{DC}): 260 to 315 VDC	25 VDC * (U_{DC}/315)			
DC bus voltage (U_{DC}): 315 to 800 VDC	24 VDC ±6%			
Fuse protection	250 mA (slow-blow) electronic, automatic reset			
Motor connection [7]				
Quantity	1			
Continuous power per motor connection [3]	1.4 kW			
Continuous current per motor connection [3]	1.9 A_{eff}			
Reduction of continuous current depending on switching frequency [8]				
Switching frequency 5 kHz	-	No reduction [9]	-	No reduction [9]
Switching frequency 10 kHz	-	No reduction	-	No reduction
Switching frequency 20 kHz	-	0.11 A/K (starting at 33°C) [10]	-	0.11 A/K (starting at 33°C) [10]
Reduction of continuous current depending on switching frequency and mounting type [11]				
Switching frequency 5 kHz				
Cold plate mounting [12]	No reduction [9]	-	No reduction [9]	-
Feed-through mounting	No reduction [9]	-	No reduction [9]	-
Switching frequency 10 kHz				
Cold plate mounting [12]	No reduction	-	No reduction	-
Feed-through mounting	No reduction	-	No reduction	-
Switching frequency 20 kHz				
Cold plate mounting [12]	0.13 A/K (starting at 46°C)	-	0.13 A/K (starting at 46°C)	-
Feed-through mounting	0.1 A/K (starting at 41°C)	-	0.1 A/K (starting at 41°C)	-
Reduction of continuous current depending on installation elevation				
Starting at 500 m above sea level	0.19 A_{eff} per 1000 m			
Peak current	4.7 A_{eff}			
Nominal switching frequency	5 kHz			
Possible switching frequencies [13]	5 / 10 / 20 kHz			
Electrical stress of connected motor per IEC TS 60034-25 [14]	Limit value curve A			
Protective measures				
Overload protection	Yes			
Short circuit and ground fault protection	Yes			
Max. output frequency	598 Hz [15]			
Variant				
U, V, W, PE	Male connector			
Shield connection	Yes			
Terminal connection cross section				
Flexible and fine-stranded wires				
With wire end sleeves	0.25 to 4 mm²			
Approbation data				
UL/C-UL-US	30 to 10			
CSA	28 to 10			
Terminal cable cross section dimension of shield connection	12 to 22 mm			
Max. motor cable length depending on switching frequency				
Switching frequency 5 kHz	25 m			
Switching frequency 10 kHz	25 m			
Switching frequency 20 kHz	10 m			
Motor holding brake connection				
Quantity	1			
Output voltage [16]	24 VDC +5.8% / -0% [17]			
Continuous current	1.1 A			
Max. internal resistance	0.5 Ω			
Extinction potential	Approx. 30 V			
Max. extinction energy per switching operation	1.5 Ws			
Max. switching frequency	0.5 Hz			
Protective measures				
Overload and short-circuit protection	Yes			
Open circuit monitoring	Yes			
Undervoltage monitoring	Yes			
Response threshold for open circuit monitoring	Approx. 0.25 A			

Table 19: 8BVI0014HCSS.000-1, 8BVI0014HWSS.000-1, 8BVI0014HCSA.000-1, 8BVI0014HWSA.000-1 - Technical data

Model number	8BVI0014HCSS.000-1	8BVI0014HWSS.000-1	8BVI0014HCSA.000-1	8BVI0014HWSA.000-1
Response threshold for undervoltage monitoring	24 VDC -2% / -4%			
Encoder interfaces [18]				
Quantity	1			
Type	EnDat 2.2 [19]		SinCos	
Connections	9-pin female DSUB connector		15-pin female DSUB connector	
Status indicators	UP/DN LEDs			
Electrical isolation				
Encoder - ACOPOSmulti	No			
Encoder monitoring	Yes			
Max. encoder cable length	100 m Depends on the cross section of the power supply wires of the encoder cable [20]		50 m [21]	
Encoder power supply				
Output voltage	Typ. 12.5 V		5 V ±5% [22]	
Load capacity	350 mA		300 mA [23]	
Sense lines	-		2, compensation of max. 2 x 0.7 V	
Protective measures				
Short-circuit proof	Yes			
Overload-proof	Yes			
Synchronous serial interface				
Signal transmission	RS485			
Data transfer rate	6.25 Mbit/s		781.25 kbit/s	
Sine/Cosine inputs				
Signal transmission	-		Differential signals, symmetrical	
Differential voltage				
In motion	-		0.5 to 1.35 V [24]	
At standstill	-		0.8 to 1.35 V [25]	
Differential voltage deviation per signal period	-		±10% [26]	
Common-mode voltage	-		Max. ±7 V	
Terminating resistor	-		120 Ω	
Max. input frequency	-		200 kHz	
Signal frequency (-5 dB)	-		<300 kHz	
Signal frequency (-3 dB)	-		DC up to 200 kHz	
ADC resolution	-		12-bit	
Reference input				
Signal transmission	-		Differential signal, symmetrical	
Differential voltage for low	-		≤-0.2 V	
Differential voltage for high	-		≥0.2 V	
Common-mode voltage	-		Max. -5 V to +9 V	
Terminating resistor	-		120 Ω	
Position				
Resolution @ 1 V_{SS} [27]	-		Number of encoder lines * 5700	
Accuracy [28]	-		---	
Noise [28]	-		---	
Max. power consumption per encoder interface	P_{SMC}[W] = 19 V * $I_{Encoder}$[A] [29]		P_{SMC}[W] = 25 V * (0.376 A + 0.35 * $I_{Encoder}$[A]) [29]	
Trigger inputs				
Quantity	2			
Circuit	Sink			
Electrical isolation				
Input - Inverter module	Yes			
Input - Input	Yes			
Input voltage				
Nominal	24 VDC			
Maximum	30 VDC			
Switching threshold				
Low	<5 V			
High	>15 V			
Input current at nominal voltage	Approx. 10 mA			
Switching delay				
Rising edge	52 µs ±0.5 µs (digitally filtered)			
Falling edge	53 µs ±0.5 µs (digitally filtered)			
Modulation compared to ground potential	Max. ±38 V			
Electrical properties				
Discharge capacitance	0.14 µF			
Operating conditions				
Permissible mounting orientations				
Hanging vertically	Yes			
Horizontal, face up	Yes			
Standing horizontally	No			

Table 19: 8BVI0014HCSS.000-1, 8BVI0014HWSS.000-1, 8BVI0014HCSA.000-1, 8BVI0014HWSA.000-1 - Technical data

Model number	8BVI0014HCSS.000-1	8BVI0014HWSS.000-1	8BVI0014HCSA.000-1	8BVI0014HWSA.000-1
Installation elevation above sea level				
Nominal	0 to 500 m			
Maximum [30]	4000 m			
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)			
Overvoltage category per EN 61800-5-1	III			
Degree of protection per EN 60529	IP20 [31]			
Ambient conditions				
Temperature				
Operation				
Nominal	5 to 40°C			
Maximum [32]	55°C			
Storage	-25 to 55°C			
Transport	-25 to 70°C			
Relative humidity				
Operation	5 to 85%			
Storage	5 to 95%			
Transport	Max. 95% at 40°C			
Mechanical properties				
Dimensions [33]				
Width	53 mm			
Height	317 mm			
Depth				
Wall mounting	-	263 mm	-	263 mm
Cold plate	212 mm	-	212 mm	-
Feed-through mounting	209 mm	-	209 mm	-
Weight	Approx. 2.1 kg	Approx. 2.6 kg	Approx. 2.1 kg	Approx. 2.6 kg
Module width	1			

Table 19: 8BVI0014HCSS.000-1, 8BVI0014HWSS.000-1, 8BVI0014HCSA.000-1, 8BVI0014HWSA.000-1 - Technical data

1) SLOT 2 is available. SLOT 1 of the ACOPOSmulti module is occupied by the SafeMOTION module.
2) Achievable safety classifications (safety integrity level, safety category, performance level) are documented in the user's manual (section "Safety technology").
3) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
4) I_M ... Current on motor connection X5A [A_{eff}]
5) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
$P_{24\,V\,Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
6) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
$P_{24\,V\,Out}$ ... Power [W] that is output to the connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
7) Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.
8) Valid in the following conditions: 750 VDC DC bus voltage. The temperature specifications refer to the ambient temperature.
9) Value for the nominal switching frequency.
10) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
11) Valid for the following conditions: 750 VDC DC bus voltage, minimum permissible coolant flow volume (3 l/min).
12) The temperature specifications refer to the return temperature of the cold plate mounting plate.
13) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
14) If necessary, the stress of the motor isolation system can be reduced by an additional externally wired dv/dt choke. For example, the RWK 305 three-phase du/dt choke from Schaffner (www.schaffner.com) can be used. Important: Even when using a dv/dt choke, it is necessary to ensure that an EMC-compatible, low inductance shield connection is used!
15) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
16) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
17) The specified value is only valid under the following conditions:
- The 24 VDC supply for the module is provided by an 8B0C auxiliary supply module installed on the same mounting plate.
If the 24 VDC supply for the module is applied to the mounting plate using an 8BVE expansion module, then the output voltage is reduced because of voltage drops on the expansion cable. In this case, undervoltage monitoring must be disabled.
18) Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.
19) An EnDat 2.2 functional safety encoder is required when using ACOPOSmulti SafeMOTION inverter modules! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!
20) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 100 m is not permitted to be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A]
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
21) The maximum permissible cable length is 50 m.

22) During the power-on procedure for the encoder power supply voltage (2 seconds), the monitoring limit for the supply voltage is increased from 5.25 V to 6 V. In this phase, overvoltages up to 6 V are not detected.
A short-term overvoltage of maximum 6 V is not permitted to damage the encoder electronics in any way.
An undervoltage on the encoder power supply will result in a sine or cosine signal outside the specification.
23) An actual reserve of 12 mA exists for the terminating resistor.
24) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2\sqrt{(Sin - nSin)^2 + (Cos - nCos)^2}$ is monitored according to the specified limits.
25) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2\sqrt{(Sin - nSin)^2 + (Cos - nCos)^2}$ is also monitored according to the specified limits from the time the evaluation circuit is switched on until a signal period has passed.
26) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2\sqrt{(Sin - nSin)^2 + (Cos - nCos)^2}$ is permitted to deviate by a maximum of ±10% per signal period.
27) This value does not correspond to the encoder resolution that must be configured in Automation Studio (16384 * number of encoder lines).
28) Limited by the encoder in practice.
29) $I_{Encoder}$ ... Max. power consumption of the connected encoder [A].
30) Continuous operation at elevations ranging from 500 m to 4,000 m above sea level is possible (taking the specified continuous current reductions into consideration).
31) This value only applies in its delivered state (SLOT2 of the module is sealed by a slot cover / shield plate). If SLOT2 on the module is not sealed, then the level of protection is reduced to IP10. It is important to note that a 8SCS005.0000-00 shield set (slot cover / shield plate) or plug-in module must always be inserted!
32) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous current reductions into consideration), but this will result in a shorter service life.
33) These dimensions refer to the actual device dimensions including the respective mounting plate. Make sure to leave additional space above and below the devices for mounting, connections and air circulation.

2.3.2.1.4 Wiring

For details, see section 2.3.2.5 "Wiring: Safe single-width inverter modules (1-axis modules)" on page 58.

For general information, see section 2.6 "Wiring" on page 150.

2.3.2.2 8BVI0028HCSS.000-1, 8BVI0028HWSS.000-1, 8BVI0028HCSA.000-1, 8BVI0028HWSA.000-1

2.3.2.2.1 General information

- Clearly structured, straightforward implementation via network-based safety technology
- Modular expandability through virtual wiring
- Immediate triggering of safety function due to short cycle times
- Easy implementation with transparent control and status information, even in the standard application
- Compact design

2.3.2.2.2 Order data

Model number	Short description	Figure
	Cold plate or feed-through mounting	
8BVI0028HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 3.8 A, HV, cold plate or feed-through mounting	
8BVI0028HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 3.8 A, HV, cold plate or feed-through mounting	
	Wall mounting	
8BVI0028HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 3.8 A, HV, wall mounting	
8BVI0028HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 3.8 A, HV, wall mounting	
	Required accessories	
	Terminal block sets	
8BZVI0055SS.000-1A	Screw clamp set for ACOPOSmulti 8BVI00xxHxSS and 8BVI00xxHxSA modules: 1x 8TB3104.204G-11, 1x 8TB2104.203L-00, 1x 8TB2108.2010-00	
	Optional accessories	
	Accessory sets	
8BXB000.0000-00	ACOPOSmulti accessory set for encoder buffering consists of the following: 1 lithium battery AA 3.6 V, 1 cover for battery compartment	
	Fan modules	
8BXF001.0000-00	ACOPOSmulti fan module, replacement fan for ACOPOSmulti modules (8BxP/8B0C/8BVI/8BVE/8B0K)	
	POWERLINK/Ethernet cables	
X20CA0E61.00020	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.2 m	
X20CA0E61.00025	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.25 m	
X20CA0E61.00030	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.3 m	
X20CA0E61.00035	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.35 m	
X20CA0E61.00050	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.5 m	
X20CA0E61.00100	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 1 m	
	Plug-in modules	

Table 20: 8BVI0028HCSS.000-1, 8BVI0028HCSA.000-1, 8BVI0028HWSS.000-1, 8BVI0028HWSA.000-1 - Order data

Model number	Short description	Figure
8BAC0120.000-1	ACOPOSmulti plug-in module, EnDat 2.1 interface	
8BAC0120.001-2	ACOPOSmulti plug-in module, EnDat 2.2 interface	
8BAC0121.000-1	ACOPOSmulti plug-in module, HIPERFACE interface	
8BAC0122.000-1	ACOPOSmulti plug-in module, resolver interface 10 kHz	
8BAC0123.000-1	ACOPOSmulti plug-in module, incremental encoder and SSI absolute encoder interface for RS422 signals	
8BAC0123.001-1	ACOPOSmulti plug-in module, incremental encoder interface for 5 V single-ended and 5 V differential signals	
8BAC0123.002-1	ACOPOSmulti plug-in module, incremental encoder interface for 24 V single-ended and 24 V differential signals	
8BAC0124.000-1	ACOPOSmulti plug-in module, SinCos interface	
8BAC0125.000-1	ACOPOSmulti plug-in module, SinCos EnDat 2.1/SSI/BiSS interface	
8BAC0130.000-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 2 digital outputs, 500 mA, max. 1.25 kHz, 2 digital inputs 24 VDC	
8BAC0130.001-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 4 digital outputs, 500 mA, max. 1.25 kHz	
8BAC0132.000-1	ACOPOSmulti plug-in module, 4 analog inputs ±10 V	
8BAC0133.000-1	ACOPOSmulti plug-in module, 3 RS422 outputs for ABR encoder emulation, 1 MHz	
	Shield component sets	
8SCS000.0000-00	ACOPOSmulti shield component set: 1 shield plate 1x type 0, 1 hose clamp, B 9 mm, D 12-22 mm	
8SCS002.0000-00	ACOPOSmulti shield component set: 1x clamping plate; 2x clamps D 4-13.5 mm; 4x screws	
8SCS009.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK8-14, 1x shield connection clamp SK14	
	Terminal blocks	
8TB2104.203L-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, L keying: 1010	
8TB2108.2010-00	8-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	
8TB3104.204G-11	4-pin screw clamp, single row, spacing: 7.62 mm, label 4: PE W V U, G keying: 0110	

Table 20: 8BVI0028HCSS.000-1, 8BVI0028HCSA.000-1, 8BVI0028HWSS.000-1, 8BVI0028HWSA.000-1 - Order data

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

ACOPOSmulti SafeMOTION SinCos

Information:

Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.

Information:

Only 8BCS encoder cables from B&R are permitted to be connected to the encoder interfaces on B&R standard motors.

For details, see 6.1.2 "Safe power transmission system " on page 283.

2.3.2.2.3 Technical data

Model number	8BVI0028HCSS.000-1	8BVI0028HWSS.000-1	8BVI0028HCSA.000-1	8BVI0028HWSA.000-1
General information				
B&R ID code	0xAA10	0xAA12	0xCD74	0xE0B2
Cooling and mounting type	Cold plate or feed-through mounting	Wall mounting	Cold plate or feed-through mounting	Wall mounting
Slots for plug-in modules	2 [1]	2 [2]	2 [1]	

Table 21: 8BVI0028HCSS.000-1, 8BVI0028HWSS.000-1, 8BVI0028HCSA.000-1, 8BVI0028HWSA.000-1 - Technical data

Model number	8BVI0028HCSS.000-1	8BVI0028HWSS.000-1	8BVI0028HCSA.000-1	8BVI0028HWSA.000-1
Certifications				
CE	Yes			
Functional safety[3)]	Yes (openSAFETY)			
UL	cULus E225616 Power conversion equipment			
EAC	Yes			
KC	Yes		-	
DC bus connection				
Voltage				
Nominal	750 VDC			
Continuous power consumption [4)]	2.87 kW			
Power dissipation depending on switching frequency [5)]				
Switching frequency 5 kHz	$[0.6 * I_M^2 + 1.3 * I_M + 60]$ W			
Switching frequency 10 kHz	$[0.97 * I_M^2 + 0.5 * I_M + 110]$ W			
Switching frequency 20 kHz	$[1.7 * I_M^2 - 0.7 * I_M + 225]$ W			
DC bus capacitance	165 µF			
Variant	ACOPOSmulti backplane			
24 VDC power supply				
Input voltage	25 VDC ±1.6%			
Input capacitance	23.5 µF			
Max. power consumption	18 W + P_{SMC1} + P_{SLOT2} + $P_{24 V Out}$ + $P_{HoldingBrake}$[6)]	18 W + P_{SMC1} + P_{SLOT2} + $P_{24 V Out}$ + $P_{HoldingBrake}$[7)]	25 W + P_{SMC1} + P_{SLOT2} + $P_{24 V Out}$ + $P_{HoldingBrake}$[7)]	
Variant	ACOPOSmulti backplane			
24 VDC output				
Quantity	2			
Output voltage				
DC bus voltage (U_{DC}): 260 to 315 VDC	25 VDC * (U_{DC}/315)			
DC bus voltage (U_{DC}): 315 to 800 VDC	24 VDC ±6%			
Fuse protection	250 mA (slow-blow) electronic, automatic reset			
Motor connection [8)]				
Quantity	1			
Continuous power per motor connection [4)]	2.8 kW			
Continuous current per motor connection [4)]	3.8 A_{eff}			
Reduction of continuous current depending on switching frequency [9)]				
Switching frequency 5 kHz	-	No reduction [10)]	-	No reduction [10)]
Switching frequency 10 kHz	-	No reduction	-	No reduction
Switching frequency 20 kHz	-	0.12 A/K (from 33°C) [11)]	-	0.12 A/K (starting at 33°C) [11)]
Reduction of continuous current depending on switching frequency and mounting type [12)]				
Switching frequency 5 kHz				
Cold plate mounting [13)]	No reduction [10)]	-	No reduction [10)]	-
Feed-through mounting	No reduction [10)]	-	No reduction [10)]	-
Switching frequency 10 kHz				
Cold plate mounting [13)]	0.6 A/K (starting at 58 °C)	-	0.6 A/K (starting at 58°C)	-
Feed-through mounting	No reduction	-	No reduction	-
Switching frequency 20 kHz				
Cold plate mounting [13)]	0.1 A/K (starting at 34 °C) [14)]	-	0.1 A/K (starting at 34°C) [14)]	-
Feed-through mounting	0.09 A/K (starting at 18 °C) [11)]	-	0.1 A/K (starting at 18°C) [11)]	-
Reduction of continuous current depending on installation elevation				
Starting at 500 m above sea level	0.38 A_{eff} per 1000 m			
Peak current	9.5 A_{eff}			
Nominal switching frequency	5 kHz			
Possible switching frequencies [15)]	5 / 10 / 20 kHz	5/10/20 kHz	5 / 10 / 20 kHz	
Electrical stress of connected motor per IEC TS 60034-25 [16)]	Limit value curve A			
Protective measures				
Overload protection	Yes			
Short circuit and ground fault protection	Yes			
Max. output frequency	598 Hz [17)]	598 Hz [18)]	598 Hz [19)]	
Variant				
U, V, W, PE	Male connector			
Shield connection	Yes			

Table 21: 8BVI0028HCSS.000-1, 8BVI0028HWSS.000-1, 8BVI0028HCSA.000-1, 8BVI0028HWSA.000-1 - Technical data

Model number	8BVI0028HCSS.000-1	8BVI0028HWSS.000-1	8BVI0028HCSA.000-1	8BVI0028HWSA.000-1
Terminal connection cross section				
Flexible and fine-stranded wires				
With wire end sleeves	0.25 to 4 mm²			
Approbation data				
UL/C-UL-US	30 to 10			
CSA	28 to 10			
Terminal cable cross section dimension of shield connection	12 to 22 mm			
Max. motor cable length depending on switching frequency				
Switching frequency 5 kHz	25 m			
Switching frequency 10 kHz	25 m			
Switching frequency 20 kHz	10 m			
Motor holding brake connection				
Quantity	1			
Output voltage [20]	24 VDC +5.8% / -0% [21]			
Continuous current	1.1 A			
Max. internal resistance	0.5 Ω			
Extinction potential	Approx. 30 V			
Max. extinction energy per switching operation	1.5 Ws			
Max. switching frequency	0.5 Hz			
Protective measures				
Overload and short-circuit protection	Yes			
Open circuit monitoring	Yes			
Undervoltage monitoring	Yes			
Response threshold for open circuit monitoring	Approx. 0.25 A			
Response threshold for undervoltage monitoring	24 VDC -2% / -4%			
Encoder interfaces [22]				
Quantity	1			
Type	EnDat 2.2 [23]		SinCos	
Connections	9-pin female DSUB connector		15-pin female DSUB connector	
Status indicators	UP/DN LEDs			
Electrical isolation				
Encoder - ACOPOSmulti	No			
Encoder monitoring	Yes			
Max. encoder cable length	100 m Depends on the cross section of the power supply wires of the encoder cable [24]	100 m Depends on the cross section of the power supply wires in the encoder cable [25]	50 m [26]	
Encoder power supply				
Output voltage	Typ. 12.5 V		5 V ±5% [27]	
Load capacity	350 mA		300 mA [28]	
Sense lines	-		2, compensation of max. 2 x 0.7 V	
Protective measures				
Short-circuit proof	Yes			
Overload-proof	Yes			
Synchronous serial interface				
Signal transmission	RS485			
Data transfer rate	6.25 Mbit/s		781.25 kbit/s	
Sine/Cosine inputs				
Signal transmission	-		Differential signals, symmetrical	
Differential voltage				
In motion	-		0.5 to 1.35 V [29]	
At standstill	-		0.8 to 1.35 V [30]	
Differential voltage deviation per signal period	-		±10% [31]	
Common-mode voltage	-		Max. ±7 V	
Terminating resistor	-		120 Ω	
Max. input frequency	-		200 kHz	
Signal frequency (-5 dB)	-		<300 kHz	
Signal frequency (-3 dB)	-		DC up to 200 kHz	
ADC resolution	-		12-bit	
Reference input				
Signal transmission	-		Differential signal, symmetrical	
Differential voltage for low	-		≤-0.2 V	
Differential voltage for high	-		≥0.2 V	
Common-mode voltage	-		Max. -5 V to +9 V	
Terminating resistor	-		120 Ω	

Table 21: 8BVI0028HCSS.000-1, 8BVI0028HWSS.000-1, 8BVI0028HCSA.000-1, 8BVI0028HWSA.000-1 - Technical data

Model number	8BVI0028HCSS.000-1	8BVI0028HWSS.000-1	8BVI0028HCSA.000-1	8BVI0028HWSA.000-1
Position				
Resolution @ 1 V_{SS} 32)	-		Number of encoder lines * 5700	
Accuracy 33)	-		---	
Noise 33)	-		---	
Max. power consumption per encoder interface	P_{SMC}[W] = 19 V * $I_{Encoder}$[A] 34)		P_{SMC}[W] = 25 V * (0.376 A + 0.35 * $I_{Encoder}$[A]) 34)	
Trigger inputs				
Quantity	2			
Circuit	Sink			
Electrical isolation				
Input - Inverter module	Yes			
Input - Input	Yes			
Input voltage				
Nominal	24 VDC			
Maximum	30 VDC			
Switching threshold				
Low	<5 V			
High	>15 V			
Input current at nominal voltage	Approx. 10 mA			
Switching delay				
Rising edge	52 μs ±0.5 μs (digitally filtered)			
Falling edge	53 μs ±0.5 μs (digitally filtered)			
Modulation compared to ground potential	Max. ±38 V			
Electrical properties				
Discharge capacitance	0.14 μF			
Operating conditions				
Permissible mounting orientations				
Hanging vertically	Yes			
Horizontal, face up	Yes			
Standing horizontally	No			
Installation elevation above sea level				
Nominal	0 to 500 m			
Maximum 35)	4000 m			
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)			
Overvoltage category per EN 61800-5-1	III			
Degree of protection per EN 60529	IP20 36)			
Ambient conditions				
Temperature				
Operation				
Nominal	5 to 40°C			
Maximum 37)	55°C			
Storage	-25 to 55°C			
Transport	-25 to 70°C			
Relative humidity				
Operation	5 to 85%			
Storage	5 to 95%			
Transport	Max. 95% at 40°C			
Mechanical properties				
Dimensions 38)				
Width	53 mm			
Height	317 mm			
Depth				
Wall mounting	-	263 mm	-	263 mm
Cold plate	212 mm	-	212 mm	-
Feed-through mounting	209 mm	-	209 mm	-
Weight	Approx. 2.1 kg	Approx. 2.6 kg	Approx. 2.1 kg	Approx. 2.6 kg
Module width	1			

Table 21: 8BVI0028HCSS.000-1, 8BVI0028HWSS.000-1, 8BVI0028HCSA.000-1, 8BVI0028HWSA.000-1 - Technical data

1) SLOT 2 is available. SLOT 1 of the ACOPOSmulti module is occupied by the SafeMOTION module.
2) SLOT 2 is not occupied. SLOT 1 of the ACOPOSmulti module is occupied by the SafeMOTION module.
3) Achievable safety classifications (safety integrity level, safety category, performance level) are documented in the user's manual (section "Safety technology").
4) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
5) I_M ... Current on motor connection X5A [A_{eff}]
6) P_{SMC1} ... Max. power consumption P_{SMC}[W] of the SafeMOTION module in SLOT1 (see section "Encoder interfaces").
P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
$P_{24\ V\ Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
7) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
$P_{24\ V\ Out}$ ... Power [W] that is output to the connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
8) Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.
9) Valid in the following conditions: 750 VDC DC bus voltage. The temperature specifications refer to the ambient temperature.

10) Value for the nominal switching frequency.
11) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
12) Valid for the following conditions: 750 VDC DC bus voltage, minimum permissible coolant flow volume (3 l/min).
13) The temperature specifications refer to the return temperature of the cold plate mounting plate.
14) The module cannot supply the full continuous current at this switching frequency. This unusual value for the return temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
Caution! Condensation can occur at low flow temperatures and return temperatures.
15) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
16) If necessary, the stress of the motor isolation system can be reduced by an additional externally wired dv/dt choke. For example, the RWK 305 three-phase du/dt choke from Schaffner (www.schaffner.com) can be used. Important: Even when using a dv/dt choke, it is necessary to ensure that an EMC-compatible, low inductance shield connection is used!
17) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use per Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
18) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output (Power unit: Limit speed exceeded).
19) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
20) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
21) The specified value is only valid under the following conditions:
- The 24 VDC supply for the module is provided by an 8B0C auxiliary supply module installed on the same mounting plate.
If the 24 VDC supply for the module is applied to the mounting plate using an 8BVE expansion module, then the output voltage is reduced because of voltage drops on the expansion cable. In this case, undervoltage monitoring must be disabled.
22) Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.
23) An EnDat 2.2 functional safety encoder is required when using ACOPOSmulti SafeMOTION inverter modules! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!
24) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 100 m is not permitted to be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A]
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
25) The maximum encoder cable length l_{Max} can be calculated as follows (the maximum permissible encoder cable length of 100 m must not be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A].
A ... Cross section of the power supply wires [mm²].
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178).
26) The maximum permissible cable length is 50 m.
27) During the power-on procedure for the encoder power supply voltage (2 seconds), the monitoring limit for the supply voltage is increased from 5.25 V to 6 V. In this phase, overvoltages up to 6 V are not detected.
A short-term overvoltage of maximum 6 V is not permitted to damage the encoder electronics in any way.
An undervoltage on the encoder power supply will result in a sine or cosine signal outside the specification.
28) An actual reserve of 12 mA exists for the terminating resistor.
29) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2 \sqrt{(Sin - nSin)^2 + (Cos - nCos)^2}$ is monitored according to the specified limits.
30) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2 \sqrt{(Sin - nSin)^2 + (Cos - nCos)^2}$ is also monitored according to the specified limits from the time the evaluation circuit is switched on until a signal period has passed.
31) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2 \sqrt{(Sin - nSin)^2 + (Cos - nCos)^2}$ is permitted to deviate by a maximum of ±10% per signal period.
32) This value does not correspond to the encoder resolution that must be configured in Automation Studio (16384 * number of encoder lines).
33) Limited by the encoder in practice.
34) $I_{Encoder}$ ... Max. power consumption of the connected encoder [A].
35) Continuous operation at elevations ranging from 500 m to 4,000 m above sea level is possible (taking the specified continuous current reductions into consideration).
36) This value only applies in its delivered state (SLOT2 of the module is sealed by a slot cover / shield plate). If SLOT2 on the module is not sealed, then the level of protection is reduced to IP10. It is important to note that a 8SCS005.0000-00 shield set (slot cover / shield plate) or plug-in module must always be inserted!
37) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous current reductions into consideration), but this will result in a shorter service life.
38) These dimensions refer to the actual device dimensions including the respective mounting plate. Make sure to leave additional space above and below the devices for mounting, connections and air circulation.

2.3.2.2.4 Wiring

For details, see section 2.3.2.5 "Wiring: Safe single-width inverter modules (1-axis modules)" on page 58.

For general information, see section 2.6 "Wiring" on page 150.

2.3.2.3 8BVI0055HCSS.000-1, 8BVI0055HWSS.000-1, 8BVI0055HCSA.000-1, 8BVI0055HWSA.000-1

2.3.2.3.1 General information

- Clearly structured, straightforward implementation via network-based safety technology
- Modular expandability through virtual wiring
- Immediate triggering of safety function due to short cycle times
- Easy implementation with transparent control and status information, even in the standard application
- Compact design

2.3.2.3.2 Order data

Model number	Short description	Figure
	Cold plate or feed-through mounting	
8BVI0055HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 7.6 A, HV, cold plate or feed-through mounting	
8BVI0055HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 7.6 A, HV, cold plate or feed-through mounting	
	Wall mounting	
8BVI0055HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 7.6 A, HV, wall mounting	
8BVI0055HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 7.6 A, HV, wall mounting	
	Required accessories	
	Terminal block sets	
8BZVI0055SS.000-1A	Screw clamp set for ACOPOSmulti 8BVI00xxHxSS and 8BVI00xxHxSA modules: 1x 8TB3104.204G-11, 1x 8TB2104.203L-00, 1x 8TB2108.2010-00	
	Optional accessories	
	Accessory sets	
8BXB000.0000-00	ACOPOSmulti accessory set for encoder buffering consists of the following: 1 lithium battery AA 3.6 V, 1 cover for battery compartment	
	Fan modules	
8BXF001.0000-00	ACOPOSmulti fan module, replacement fan for ACOPOSmulti modules (8BxP/8B0C/8BVI/8BVE/8B0K)	
	POWERLINK/Ethernet cables	
X20CA0E61.00020	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.2 m	
X20CA0E61.00025	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.25 m	
X20CA0E61.00030	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.3 m	
X20CA0E61.00035	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.35 m	
X20CA0E61.00050	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.5 m	
X20CA0E61.00100	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 1 m	
	Plug-in modules	
8BAC0120.000-1	ACOPOSmulti plug-in module, EnDat 2.1 interface	
8BAC0120.001-2	ACOPOSmulti plug-in module, EnDat 2.2 interface	
8BAC0121.000-1	ACOPOSmulti plug-in module, HIPERFACE interface	
8BAC0122.000-1	ACOPOSmulti plug-in module, resolver interface 10 kHz	
8BAC0123.000-1	ACOPOSmulti plug-in module, incremental encoder and SSI absolute encoder interface for RS422 signals	
8BAC0123.001-1	ACOPOSmulti plug-in module, incremental encoder interface for 5 V single-ended and 5 V differential signals	
8BAC0123.002-1	ACOPOSmulti plug-in module, incremental encoder interface for 24 V single-ended and 24 V differential signals	
8BAC0124.000-1	ACOPOSmulti plug-in module, SinCos interface	
8BAC0125.000-1	ACOPOSmulti plug-in module, SinCos EnDat 2.1/SSI/BiSS interface	
8BAC0130.000-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 2 digital outputs, 500 mA, max. 1.25 kHz, 2 digital inputs 24 VDC	
8BAC0130.001-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 4 digital outputs, 500 mA, max. 1.25 kHz	
8BAC0132.000-1	ACOPOSmulti plug-in module, 4 analog inputs ±10 V	
8BAC0133.000-1	ACOPOSmulti plug-in module, 3 RS422 outputs for ABR encoder emulation, 1 MHz	
	Shield component sets	
8SCS000.0000-00	ACOPOSmulti shield component set: 1 shield plate 1x type 0, 1 hose clamp, B 9 mm, D 12-22 mm	
8SCS002.0000-00	ACOPOSmulti shield component set: 1x clamping plate; 2x clamps D 4-13.5 mm; 4x screws	
8SCS009.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK8-14, 1x shield connection clamp SK14	

Table 22: 8BVI0055HCSS.000-1, 8BVI0055HCSA.000-1, 8BVI0055HWSS.000-1, 8BVI0055HWSA.000-1 - Order data

Model number	Short description	Figure
	Terminal blocks	
8TB2104.203L-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, L keying: 1010	
8TB2108.2010-00	8-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	
8TB3104.204G-11	4-pin screw clamp, single row, spacing: 7.62 mm, label 4: PE W V U, G keying: 0110	

Table 22: 8BVI0055HCSS.000-1, 8BVI0055HCSA.000-1, 8BVI0055HWSS.000-1, 8BVI0055HWSA.000-1 - Order data

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

ACOPOSmulti SafeMOTION SinCos

Information:

Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.

Information:

Only 8BCS encoder cables from B&R are permitted to be connected to the encoder interfaces on B&R standard motors.

For details, see 6.1.2 "Safe power transmission system " on page 283.

2.3.2.3.3 Technical data

Model number	8BVI0055HCSS.000-1	8BVI0055HWSS.000-1	8BVI0055HCSA.000-1	8BVI0055HWSA.000-1
General information				
B&R ID code	0xAA14	0xAA16	0xDD6B	0xE0B3
Cooling and mounting type	Cold plate or feed-through mounting	Wall mounting	Cold plate or feed-through mounting	Wall mounting
Slots for plug-in modules	2 1)			
Certifications				
CE	Yes			
Functional safety 2)	Yes (openSAFETY)			
UL	cULus E225616 Power conversion equipment			
EAC	Yes			
KC	Yes		-	
DC bus connection				
Voltage				
Nominal	750 VDC			
Continuous power consumption 3)	5.6 kW			
Power dissipation depending on switching frequency 4)				
Switching frequency 5 kHz	$[0.6 * I_M^2 + 1.3 * I_M + 60]$ W			
Switching frequency 10 kHz	$[0.97 * I_M^2 + 0.5 * I_M + 110]$ W			
Switching frequency 20 kHz	$[1.7 * I_M^2 - 0.7 * I_M + 225]$ W			
DC bus capacitance	165 µF			
Variant	ACOPOSmulti backplane			
24 VDC power supply				
Input voltage	25 VDC ±1.6%			
Input capacitance	23.5 µF			
Max. power consumption	$18\ W + P_{SMC1} + P_{SLOT2} + P_{24\ V\ Out} + P_{HoldingBrake}$ 5)		$25\ W + P_{SMC1} + P_{SLOT2} + P_{24\ V\ Out} + P_{HoldingBrake}$ 6)	
Variant	ACOPOSmulti backplane			
24 VDC output				
Quantity	2			

Table 23: 8BVI0055HCSS.000-1, 8BVI0055HWSS.000-1, 8BVI0055HCSA.000-1, 8BVI0055HWSA.000-1 - Technical data

Model number	8BVI0055HCSS.000-1	8BVI0055HWSS.000-1	8BVI0055HCSA.000-1	8BVI0055HWSA.000-1
Output voltage				
DC bus voltage (U_{DC}): 260 to 315 VDC	25 VDC * (U_{DC}/315)			
DC bus voltage (U_{DC}): 315 to 800 VDC	24 VDC ±6%			
Fuse protection	250 mA (slow-blow) electronic, automatic reset			
Motor connection [7]				
Quantity	1			
Continuous power per motor connection [3]	5.5 kW			
Continuous current per motor connection [3]	7.6 A_{eff}			
Reduction of continuous current depending on switching frequency [8]				
Switching frequency 5 kHz	-	No reduction [9]	-	No reduction [9]
Switching frequency 10 kHz	-	0.2 A/K (starting at 49°C)	-	0.2 A/K (starting at 49°C)
Switching frequency 20 kHz	-	0.13 A/K (starting at 4°C) [10]	-	0.13 A/K (starting at 4°C) [10]
Reduction of continuous current depending on switching frequency and mounting type [11]				
Switching frequency 5 kHz				
Cold plate mounting [12]	0.65 A/K (starting at 57°C) [9]	-	0.65 A/K (starting at 57°C) [9]	-
Feed-through mounting	No reduction [9]	-	No reduction [9]	-
Switching frequency 10 kHz				
Cold plate mounting [12]	0.28 A/K (starting at 46°C)	-	0.28 A/K (starting at 46°C)	-
Feed-through mounting	0.15 A/K (starting at 34°C) [10]	-	0.15 A/K (starting at 34°C) [10]	-
Switching frequency 20 kHz				
Cold plate mounting [12]	0.14 A/K (starting at 5°C) [13]	-	0.14 A/K (starting at 5°C) [13]	-
Feed-through mounting	0.08 A/K (starting at -33°C) [10]	-	0.08 A/K (starting at -33°C) [10]	-
Reduction of continuous current depending on installation elevation				
Starting at 500 m above sea level	0.76 A_{eff} per 1000 m			
Peak current	18.9 A_{eff}			
Nominal switching frequency	5 kHz			
Possible switching frequencies [14]	5 / 10 / 20 kHz			
Electrical stress of connected motor per IEC TS 60034-25 [15]	Limit value curve A			
Protective measures				
Overload protection	Yes			
Short circuit and ground fault protection	Yes			
Max. output frequency	598 Hz [16]			
Variant				
U, V, W, PE	Male connector			
Shield connection	Yes			
Terminal connection cross section				
Flexible and fine-stranded wires				
With wire end sleeves	0.25 to 4 mm²			
Approbation data				
UL/C-UL-US	30 to 10			
CSA	28 to 10			
Terminal cable cross section dimension of shield connection	12 to 22 mm			
Max. motor cable length depending on switching frequency				
Switching frequency 5 kHz	25 m			
Switching frequency 10 kHz	25 m			
Switching frequency 20 kHz	10 m			
Motor holding brake connection				
Quantity	1			
Output voltage [17]	24 VDC +5.8% / -0% [18]			
Continuous current	1.1 A			
Max. internal resistance	0.5 Ω			
Extinction potential	Approx. 30 V			
Max. extinction energy per switching operation	1.5 Ws			
Max. switching frequency	0.5 Hz			
Protective measures				
Overload and short-circuit protection	Yes			
Open circuit monitoring	Yes			
Undervoltage monitoring	Yes			

Table 23: 8BVI0055HCSS.000-1, 8BVI0055HWSS.000-1, 8BVI0055HCSA.000-1, 8BVI0055HWSA.000-1 - Technical data

Model number	8BVI0055HCSS.000-1	8BVI0055HWSS.000-1	8BVI0055HCSA.000-1	8BVI0055HWSA.000-1
Response threshold for open circuit monitoring	Approx. 0.25 A			
Response threshold for undervoltage monitoring	24 VDC -2% / -4%			
Encoder interfaces [19]				
Quantity	1			
Type	EnDat 2.2 [20]		SinCos	
Connections	9-pin female DSUB connector		15-pin female DSUB connector	
Status indicators	UP/DN LEDs			
Electrical isolation				
Encoder - ACOPOSmulti	No			
Encoder monitoring	Yes			
Max. encoder cable length	100 m Depends on the cross section of the pow-er supply wires of the encoder cable [21]		50 m [22]	
Encoder power supply				
Output voltage	Typ. 12.5 V		5 V ±5% [23]	
Load capacity	350 mA		300 mA [24]	
Sense lines	-		2, compensation of max. 2 x 0.7 V	
Protective measures				
Short-circuit proof	Yes			
Overload-proof	Yes			
Synchronous serial interface				
Signal transmission	RS485			
Data transfer rate	6.25 Mbit/s		781.25 kbit/s	
Sine/Cosine inputs				
Signal transmission	-		Differential signals, symmetrical	
Differential voltage				
In motion	-		0.5 to 1.35 V [25]	
At standstill	-		0.8 to 1.35 V [26]	
Differential voltage deviation per signal period	-		±10% [27]	
Common-mode voltage	-		Max. ±7 V	
Terminating resistor	-		120 Ω	
Max. input frequency	-		200 kHz	
Signal frequency (-5 dB)	-		<300 kHz	
Signal frequency (-3 dB)	-		DC up to 200 kHz	
ADC resolution	-		12-bit	
Reference input				
Signal transmission	-		Differential signal, symmetrical	
Differential voltage for low	-		≤-0.2 V	
Differential voltage for high	-		≥0.2 V	
Common-mode voltage	-		Max. -5 V to +9 V	
Terminating resistor	-		120 Ω	
Position				
Resolution @ 1 V_{SS} [28]	-		Number of encoder lines * 5700	
Accuracy [29]	-		---	
Noise [29]	-		---	
Max. power consumption per encoder interface	P_{SMC}[W] = 19 V * $I_{Encoder}$[A] [30]		P_{SMC}[W] = 25 V * (0.376 A + 0.35 * $I_{Encoder}$[A]) [30]	
Trigger inputs				
Quantity	2			
Circuit	Sink			
Electrical isolation				
Input - Inverter module	Yes			
Input - Input	Yes			
Input voltage				
Nominal	24 VDC			
Maximum	30 VDC			
Switching threshold				
Low	<5 V			
High	>15 V			
Input current at nominal voltage	Approx. 10 mA			
Switching delay				
Rising edge	52 µs ±0.5 µs (digitally filtered)			
Falling edge	53 µs ±0.5 µs (digitally filtered)			
Modulation compared to ground po-tential	Max. ±38 V			
Electrical properties				
Discharge capacitance	0.14 µF			

Table 23: 8BVI0055HCSS.000-1, 8BVI0055HWSS.000-1, 8BVI0055HCSA.000-1, 8BVI0055HWSA.000-1 - Technical data

Model number	8BVI0055HCSS.000-1	8BVI0055HWSS.000-1	8BVI0055HCSA.000-1	8BVI0055HWSA.000-1
Operating conditions				
Permissible mounting orientations				
Hanging vertically	Yes			
Horizontal, face up	Yes			
Standing horizontally	No			
Installation elevation above sea level				
Nominal	0 to 500 m			
Maximum [31]	4000 m			
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)			
Overvoltage category per EN 61800-5-1	III			
Degree of protection per EN 60529	IP20 [32]			
Ambient conditions				
Temperature				
Operation				
Nominal	5 to 40°C			
Maximum [33]	55°C			
Storage	-25 to 55°C			
Transport	-25 to 70°C			
Relative humidity				
Operation	5 to 85%			
Storage	5 to 95%			
Transport	Max. 95% at 40°C			
Mechanical properties				
Dimensions [34]				
Width	53 mm			
Height	317 mm			
Depth				
Wall mounting	-	263 mm	-	263 mm
Cold plate	212 mm	-	212 mm	-
Feed-through mounting	209 mm	-	209 mm	-
Weight	Approx. 2.2 kg	Approx. 2.7 kg	Approx. 2.2 kg	Approx. 2.7 kg
Module width	1			

Table 23: 8BVI0055HCSS.000-1, 8BVI0055HWSS.000-1, 8BVI0055HCSA.000-1, 8BVI0055HWSA.000-1 - Technical data

1) SLOT 2 is available. SLOT 1 of the ACOPOSmulti module is occupied by the SafeMOTION module.
2) Achievable safety classifications (safety integrity level, safety category, performance level) are documented in the user's manual (section "Safety technology").
3) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
4) I_M ... Current on motor connection X5A [A_{eff}]
5) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
$P_{24\,V\,Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
6) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
$P_{24\,V\,Out}$ ... Power [W] that is output to the connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
7) Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.
8) Valid in the following conditions: 750 VDC DC bus voltage. The temperature specifications refer to the ambient temperature.
9) Value for the nominal switching frequency.
10) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
11) Valid for the following conditions: 750 VDC DC bus voltage, minimum permissible coolant flow volume (3 l/min).
12) The temperature specifications refer to the return temperature of the cold plate mounting plate.
13) The module cannot supply the full continuous current at this switching frequency. This unusual value for the return temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
Caution! Condensation can occur at low flow temperatures and return temperatures.
14) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
15) If necessary, the stress of the motor isolation system can be reduced by an additional externally wired dv/dt choke. For example, the RWK 305 three-phase du/dt choke from Schaffner (www.schaffner.com) can be used. Important: Even when using a dv/dt choke, it is necessary to ensure that an EMC-compatible, low inductance shield connection is used!
16) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
17) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
18) The specified value is only valid under the following conditions:
- The 24 VDC supply for the module is provided by an 8B0C auxiliary supply module installed on the same mounting plate.
If the 24 VDC supply for the module is applied to the mounting plate using an 8BVE expansion module, then the output voltage is reduced because of voltage drops on the expansion cable. In this case, undervoltage monitoring must be disabled.
19) Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.
20) An EnDat 2.2 functional safety encoder is required when using ACOPOSmulti SafeMOTION inverter modules! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!

21) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 100 m is not permitted to be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A]
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)

22) The maximum permissible cable length is 50 m.
23) During the power-on procedure for the encoder power supply voltage (2 seconds), the monitoring limit for the supply voltage is increased from 5.25 V to 6 V. In this phase, overvoltages up to 6 V are not detected.
A short-term overvoltage of maximum 6 V is not permitted to damage the encoder electronics in any way.
An undervoltage on the encoder power supply will result in a sine or cosine signal outside the specification.
24) An actual reserve of 12 mA exists for the terminating resistor.
25) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length z = 2 √((Sin - nSin)² + (Cos - nCos)²) is monitored according to the specified limits.
26) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length z = 2 √((Sin - nSin)² + (Cos - nCos)²) is also monitored according to the specified limits from the time the evaluation circuit is switched on until a signal period has passed.
27) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length z = 2 √((Sin - nSin)² + (Cos - nCos)²) is permitted to deviate by a maximum of ±10% per signal period.
28) This value does not correspond to the encoder resolution that must be configured in Automation Studio (16384 * number of encoder lines).
29) Limited by the encoder in practice.
30) $I_{Encoder}$ ... Max. power consumption of the connected encoder [A].
31) Continuous operation at elevations ranging from 500 m to 4,000 m above sea level is possible (taking the specified continuous current reductions into consideration).
32) This value only applies in its delivered state (SLOT2 of the module is sealed by a slot cover / shield plate). If SLOT2 on the module is not sealed, then the level of protection is reduced to IP10. It is important to note that a 8SCS005.0000-00 shield set (slot cover / shield plate) or plug-in module must always be inserted!
33) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous current reductions into consideration), but this will result in a shorter service life.
34) These dimensions refer to the actual device dimensions including the respective mounting plate. Make sure to leave additional space above and below the devices for mounting, connections and air circulation.

2.3.2.3.4 Wiring

For details, see section 2.3.2.5 "Wiring: Safe single-width inverter modules (1-axis modules)" on page 58.

For general information, see section 2.6 "Wiring" on page 150.

2.3.2.4 8BVI0110HCSS.000-1, 8BVI0110HWSS.000-1, 8BVI0110HCSA.000-1, 8BVI0110HWSA.000-1

2.3.2.4.1 General information

- Clearly structured, straightforward implementation via network-based safety technology
- Modular expandability through virtual wiring
- Immediate triggering of safety function due to short cycle times
- Easy implementation with transparent control and status information, even in the standard application
- Compact design

2.3.2.4.2 Order data

Model number	Short description	Figure
	Cold plate or feed-through mounting	
8BVI0110HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 15.1 A, HV, cold plate or feed-through mounting	
8BVI0110HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 15.1 A, HV, cold plate or feed-through mounting	
	Wall mounting	
8BVI0110HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 15.1 A, HV, wall mounting	
8BVI0110HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 15.1 A, HV, wall mounting	
	Required accessories	
	Terminal block sets	
8BZVI0110SS.000-1A	Screw clamp set for ACOPOSmulti 8BVI0110HxSS and 8BVI0110HxSA modules: 1x 8TB3104.204G-11, 1x 8TB2104.203L-00, 1x 8TB2108.2010-00	
	Optional accessories	
	Accessory sets	
8BXB000.0000-00	ACOPOSmulti accessory set for encoder buffering consists of the following: 1 lithium battery AA 3.6 V, 1 cover for battery compartment	
	Fan modules	

Table 24: 8BVI0110HCSS.000-1, 8BVI0110HCSA.000-1, 8BVI0110HWSS.000-1, 8BVI0110HWSA.000-1 - Order data

Model number	Short description	Figure
8BXF001.0000-00	ACOPOSmulti fan module, replacement fan for ACOPOSmulti modules (8BxP/8B0C/8BVI/8BVE/8B0K)	
	POWERLINK/Ethernet cables	
X20CA0E61.00020	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.2 m	
X20CA0E61.00025	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.25 m	
X20CA0E61.00030	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.3 m	
X20CA0E61.00035	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.35 m	
X20CA0E61.00050	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.5 m	
X20CA0E61.00100	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 1 m	
	Plug-in modules	
8BAC0120.000-1	ACOPOSmulti plug-in module, EnDat 2.1 interface	
8BAC0120.001-2	ACOPOSmulti plug-in module, EnDat 2.2 interface	
8BAC0121.000-1	ACOPOSmulti plug-in module, HIPERFACE interface	
8BAC0122.000-1	ACOPOSmulti plug-in module, resolver interface 10 kHz	
8BAC0123.000-1	ACOPOSmulti plug-in module, incremental encoder and SSI absolute encoder interface for RS422 signals	
8BAC0123.001-1	ACOPOSmulti plug-in module, incremental encoder interface for 5 V single-ended and 5 V differential signals	
8BAC0123.002-1	ACOPOSmulti plug-in module, incremental encoder interface for 24 V single-ended and 24 V differential signals	
8BAC0124.000-1	ACOPOSmulti plug-in module, SinCos interface	
8BAC0125.000-1	ACOPOSmulti plug-in module, SinCos EnDat 2.1/SSI/BiSS interface	
8BAC0130.000-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 2 digital outputs, 500 mA, max. 1.25 kHz, 2 digital inputs 24 VDC	
8BAC0130.001-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 4 digital outputs, 500 mA, max. 1.25 kHz	
8BAC0132.000-1	ACOPOSmulti plug-in module, 4 analog inputs ±10 V	
8BAC0133.000-1	ACOPOSmulti plug-in module, 3 RS422 outputs for ABR encoder emulation, 1 MHz	
	Shield component sets	
8SCS000.0000-00	ACOPOSmulti shield component set: 1 shield plate 1x type 0, 1 hose clamp, B 9 mm, D 12-22 mm	
8SCS002.0000-00	ACOPOSmulti shield component set: 1x clamping plate; 2x clamps D 4-13.5 mm; 4x screws	
8SCS009.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK8-14, 1x shield connection clamp SK14	
	Terminal blocks	
8TB2104.203L-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, L keying: 1010	
8TB2108.2010-00	8-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	
8TB3104.204G-11	4-pin screw clamp, single row, spacing: 7.62 mm, label 4: PE W V U, G keying: 0110	

Table 24: 8BVI0110HCSS.000-1, 8BVI0110HCSA.000-1, 8BVI0110HWSS.000-1, 8BVI0110HWSA.000-1 - Order data

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

ACOPOSmulti SafeMOTION SinCos

Information:

Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.

Information:

Only 8BCS encoder cables from B&R are permitted to be connected to the encoder interfaces on B&R standard motors.

For details, see 6.1.2 "Safe power transmission system " on page 283.

2.3.2.4.3 Technical data

Model number	8BVI0110HCSS.000-1	8BVI0110HWSS.000-1	8BVI0110HCSA.000-1	8BVI0110HWSA.000-1
General information				
B&R ID code	0xAA18	0xAA1A	0xDD1F	0xE0BC
Cooling and mounting type	Cold plate or feed-through mounting	Wall mounting	Cold plate or feed-through mounting	Wall mounting
Slots for plug-in modules	2 [1]			
Certifications				
CE	Yes			
Functional safety[2]	Yes (openSAFETY)			
UL	cULus E225616 Power conversion equipment			
EAC	Yes			
KC	Yes		-	
DC bus connection				
Voltage				
Nominal	750 VDC			
Continuous power consumption [3]	11.2 kW			
Power dissipation depending on switching frequency [4]				
Switching frequency 5 kHz	[0.16 * I_M^2 + 5.6 * I_M + 55] W			
Switching frequency 10 kHz	[0.49 * I_M^2 + 4.7 * I_M + 95] W			
Switching frequency 20 kHz	[0.87 * I_M^2 + 10 * I_M + 200] W			
DC bus capacitance	330 µF			
Variant	ACOPOSmulti backplane			
24 VDC power supply				
Input voltage	25 VDC ±1.6%			
Input capacitance	23.5 µF			
Max. power consumption	18 W + P_{SMC1} + P_{SLOT2} + $P_{24\,V\,Out}$ + $P_{HoldingBrake}$ [5]		25 W + P_{SMC1} + P_{SLOT2} + $P_{24\,V\,Out}$ + $P_{HoldingBrake}$ [6]	
Variant	ACOPOSmulti backplane			
24 VDC output				
Quantity	2			
Output voltage				
DC bus voltage (U_{DC}): 260 to 315 VDC	25 VDC * (U_{DC}/315)			
DC bus voltage (U_{DC}): 315 to 800 VDC	24 VDC ±6%			
Fuse protection	250 mA (slow-blow) electronic, automatic reset			
Motor connection [7]				
Quantity	1			
Continuous power per motor connection [3]	11 kW			
Continuous current per motor connection [3]	15.1 A_{eff}			
Reduction of continuous current depending on switching frequency [8]				
Switching frequency 5 kHz	-	No reduction [9]	-	No reduction [9]
Switching frequency 10 kHz	-	0.26 A/K (starting at 33°C) [10]	-	0.26 A/K (starting at 33°C) [10]
Switching frequency 20 kHz	-	0.15 A/K (starting at -28°C) [10]	-	0.15 A/K (starting at -28°C) [10]
Reduction of continuous current depending on switching frequency and mounting type [11]				
Switching frequency 5 kHz				
Cold plate mounting [12]	0.73 A/K (starting at 55°C) [9]	-	0.73 A/K (starting at 55°C) [9]	-
Feed-through mounting	0.29 A/K (starting at 49°C) [9]	-	0.29 A/K (starting at 49°C) [9]	-
Switching frequency 10 kHz				
Cold plate mounting [12]	0.32 A/K (starting at 35°C) [13]	-	0.32 A/K (starting at 35°C) [13]	-
Feed-through mounting	0.17 A/K (starting at 11°C) [10]	-	0.17 A/K (starting at 11°C) [10]	-
Switching frequency 20 kHz				
Cold plate mounting [12]	0.18 A/K (starting at -13°C) [13]	-	0.18 A/K (starting at -13°C) [13]	-
Feed-through mounting	0.11 A/K (starting at -73°C) [10]	-	0.11 A/K (starting at -73°C) [10]	-
Reduction of continuous current depending on installation elevation				
Starting at 500 m above sea level	1.51 A_{eff} per 1000 m			
Peak current	37.7 A_{eff}			
Nominal switching frequency	5 kHz			
Possible switching frequencies [14]	5 / 10 / 20 kHz			
Electrical stress of connected motor per IEC TS 60034-25 [15]	Limit value curve A			

Table 25: 8BVI0110HCSS.000-1, 8BVI0110HWSS.000-1, 8BVI0110HCSA.000-1, 8BVI0110HWSA.000-1 - Technical data

Model number	8BVI0110HCSS.000-1	8BVI0110HWSS.000-1	8BVI0110HCSA.000-1	8BVI0110HWSA.000-1
Protective measures				
Overload protection	Yes			
Short circuit and ground fault protection	Yes			
Max. output frequency	598 Hz [16]			
Variant				
U, V, W, PE	Male connector			
Shield connection	Yes			
Terminal connection cross section				
Flexible and fine-stranded wires				
With wire end sleeves	0.25 to 4 mm²			
Approbation data				
UL/C-UL-US	30 to 10			
CSA	28 to 10			
Terminal cable cross section dimension of shield connection	12 to 22 mm			
Max. motor cable length depending on switching frequency				
Switching frequency 5 kHz	25 m			
Switching frequency 10 kHz	25 m			
Switching frequency 20 kHz	10 m			
Motor holding brake connection				
Quantity	1			
Output voltage [17]	24 VDC +5.8% / -0% [18]			
Continuous current	2.1 A			
Max. internal resistance	0.3 Ω			
Extinction potential	Approx. 30 V			
Max. extinction energy per switching operation	3 Ws			
Max. switching frequency	0.5 Hz			
Protective measures				
Overload and short-circuit protection	Yes			
Open circuit monitoring	Yes			
Undervoltage monitoring	Yes			
Response threshold for open circuit monitoring	Approx. 0.5 A			
Response threshold for undervoltage monitoring	24 VDC -2% / -4%			
Encoder interfaces [19]				
Quantity	1			
Type	EnDat 2.2 [20]		SinCos	
Connections	9-pin female DSUB connector		15-pin female DSUB connector	
Status indicators	UP/DN LEDs			
Electrical isolation				
Encoder - ACOPOSmulti	No			
Encoder monitoring	Yes			
Max. encoder cable length	100 m Depends on the cross section of the power supply wires of the encoder cable [21]		50 m [22]	
Encoder power supply				
Output voltage	Typ. 12.5 V		5 V ±5% [23]	
Load capacity	350 mA		300 mA [24]	
Sense lines	-		2, compensation of max. 2 x 0.7 V	
Protective measures				
Short-circuit proof	Yes			
Overload-proof	Yes			
Synchronous serial interface				
Signal transmission	RS485			
Data transfer rate	6.25 Mbit/s		781.25 kbit/s	
Sine/Cosine inputs				
Signal transmission	-		Differential signals, symmetrical	
Differential voltage				
In motion	-		0.5 to 1.35 V [25]	
At standstill	-		0.8 to 1.35 V [26]	
Differential voltage deviation per signal period	-		±10% [27]	
Common-mode voltage	-		Max. ±7 V	
Terminating resistor	-		120 Ω	
Max. input frequency	-		200 kHz	
Signal frequency (-5 dB)	-		<300 kHz	
Signal frequency (-3 dB)	-		DC up to 200 kHz	
ADC resolution	-		12-bit	

Table 25: 8BVI0110HCSS.000-1, 8BVI0110HWSS.000-1, 8BVI0110HCSA.000-1, 8BVI0110HWSA.000-1 - Technical data

Model number	8BVI0110HCSS.000-1	8BVI0110HWSS.000-1	8BVI0110HCSA.000-1	8BVI0110HWSA.000-1
Reference input				
Signal transmission	-		Differential signal, symmetrical	
Differential voltage for low	-		≤-0.2 V	
Differential voltage for high	-		≥0.2 V	
Common-mode voltage	-		Max. -5 V to +9 V	
Terminating resistor	-		120 Ω	
Position				
Resolution @ 1 V_{SS} [28)]	-		Number of encoder lines * 5700	
Accuracy [29)]	-		---	
Noise [29)]	-		---	
Max. power consumption per encoder interface	P_{SMC}[W] = 19 V * $I_{Encoder}$[A] [30)]		P_{SMC}[W] = 25 V * (0.376 A + 0.35 * $I_{Encoder}$[A]) [30)]	
Trigger inputs				
Quantity	2			
Circuit	Sink			
Electrical isolation				
Input - Inverter module	Yes			
Input - Input	Yes			
Input voltage				
Nominal	24 VDC			
Maximum	30 VDC			
Switching threshold				
Low	<5 V			
High	>15 V			
Input current at nominal voltage	Approx. 10 mA			
Switching delay				
Rising edge	52 µs ±0.5 µs (digitally filtered)			
Falling edge	53 µs ±0.5 µs (digitally filtered)			
Modulation compared to ground potential	Max. ±38 V			
Electrical properties				
Discharge capacitance	0.14 µF			
Operating conditions				
Permissible mounting orientations				
Hanging vertically	Yes			
Horizontal, face up	Yes			
Standing horizontally	No			
Installation elevation above sea level				
Nominal	0 to 500 m			
Maximum [31)]	4000 m			
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)			
Overvoltage category per EN 61800-5-1	III			
Degree of protection per EN 60529	IP20 [32)]			
Ambient conditions				
Temperature				
Operation				
Nominal	5 to 40°C			
Maximum [33)]	55°C			
Storage	-25 to 55°C			
Transport	-25 to 70°C			
Relative humidity				
Operation	5 to 85%			
Storage	5 to 95%			
Transport	Max. 95% at 40°C			
Mechanical properties				
Dimensions [34)]				
Width	53 mm			
Height	317 mm			
Depth				
Wall mounting	-	263 mm	-	263 mm
Cold plate	212 mm	-	212 mm	-
Feed-through mounting	209 mm	-	209 mm	-
Weight	Approx. 2.4 kg	Approx. 2.9 kg	Approx. 2.4 kg	Approx. 2.9 kg
Module width	1			

Table 25: 8BVI0110HCSS.000-1, 8BVI0110HWSS.000-1, 8BVI0110HCSA.000-1, 8BVI0110HWSA.000-1 - Technical data

1) SLOT 2 is available. SLOT 1 of the ACOPOSmulti module is occupied by the SafeMOTION module.
2) Achievable safety classifications (safety integrity level, safety category, performance level) are documented in the user's manual (section "Safety technology").
3) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
4) I_M ... Current on motor connection X5A [A_{eff}]
5) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
$P_{24\ V\ Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).

6) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
$P_{24\ V\ Out}$ ... Power [W] that is output to the connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
7) Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.
8) Valid in the following conditions: 750 VDC DC bus voltage. The temperature specifications refer to the ambient temperature.
9) Value for the nominal switching frequency.
10) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
11) Valid for the following conditions: 750 VDC DC bus voltage, minimum permissible coolant flow volume (3 l/min).
12) The temperature specifications refer to the return temperature of the cold plate mounting plate.
13) The module cannot supply the full continuous current at this switching frequency. This unusual value for the return temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
Caution! Condensation can occur at low flow temperatures and return temperatures.
14) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
15) If necessary, the stress of the motor isolation system can be reduced by an additional externally wired dv/dt choke. For example, the RWK 305 three-phase du/dt choke from Schaffner (www.schaffner.com) can be used. Important: Even when using a dv/dt choke, it is necessary to ensure that an EMC-compatible, low inductance shield connection is used!
16) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
17) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
18) The specified value is only valid under the following conditions:
- The 24 VDC supply for the module is provided by an 8B0C auxiliary supply module installed on the same mounting plate.
If the 24 VDC supply for the module is applied to the mounting plate using an 8BVE expansion module, then the output voltage is reduced because of voltage drops on the expansion cable. In this case, undervoltage monitoring must be disabled.
19) Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.
20) An EnDat 2.2 functional safety encoder is required when using ACOPOSmulti SafeMOTION inverter modules! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!
21) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 100 m is not permitted to be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A].
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
22) The maximum permissible cable length is 50 m.
23) During the power-on procedure for the encoder power supply voltage (2 seconds), the monitoring limit for the supply voltage is increased from 5.25 V to 6 V. In this phase, overvoltages up to 6 V are not detected.
A short-term overvoltage of maximum 6 V is not permitted to damage the encoder electronics in any way.
An undervoltage on the encoder power supply will result in a sine or cosine signal outside the specification.
24) An actual reserve of 12 mA exists for the terminating resistor.
25) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2 \sqrt{(Sin - nSin)^2 + (Cos - nCos)^2}$ is monitored according to the specified limits.
26) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2 \sqrt{(Sin - nSin)^2 + (Cos - nCos)^2}$ is also monitored according to the specified limits from the time the evaluation circuit is switched on until a signal period has passed.
27) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2 \sqrt{(Sin - nSin)^2 + (Cos - nCos)^2}$ is permitted to deviate by a maximum of ±10% per signal period.
28) This value does not correspond to the encoder resolution that must be configured in Automation Studio (16384 * number of encoder lines).
29) Limited by the encoder in practice.
30) $I_{Encoder}$ ... Max. power consumption of the connected encoder [A].
31) Continuous operation at elevations ranging from 500 m to 4,000 m above sea level is possible (taking the specified continuous current reductions into consideration).
32) This value only applies in its delivered state (SLOT2 of the module is sealed by a slot cover / shield plate). If SLOT2 on the module is not sealed, then the level of protection is reduced to IP10. It is important to note that a 8SCS005.0000-00 shield set (slot cover / shield plate) or plug-in module must always be inserted!
33) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous current reductions into consideration), but this will result in a shorter service life.
34) These dimensions refer to the actual device dimensions including the respective mounting plate. Make sure to leave additional space above and below the devices for mounting, connections and air circulation.

2.3.2.4.4 Wiring

For details, see section 2.3.2.5 "Wiring: Safe single-width inverter modules (1-axis modules)" on page 58.

For general information, see section 2.6 "Wiring" on page 150.

2.3.2.5 Wiring: Safe single-width inverter modules (1-axis modules)

2.3.2.5.1 ACOPOSmulti SafeMOTION EnDat 2.2 - Pinout overview

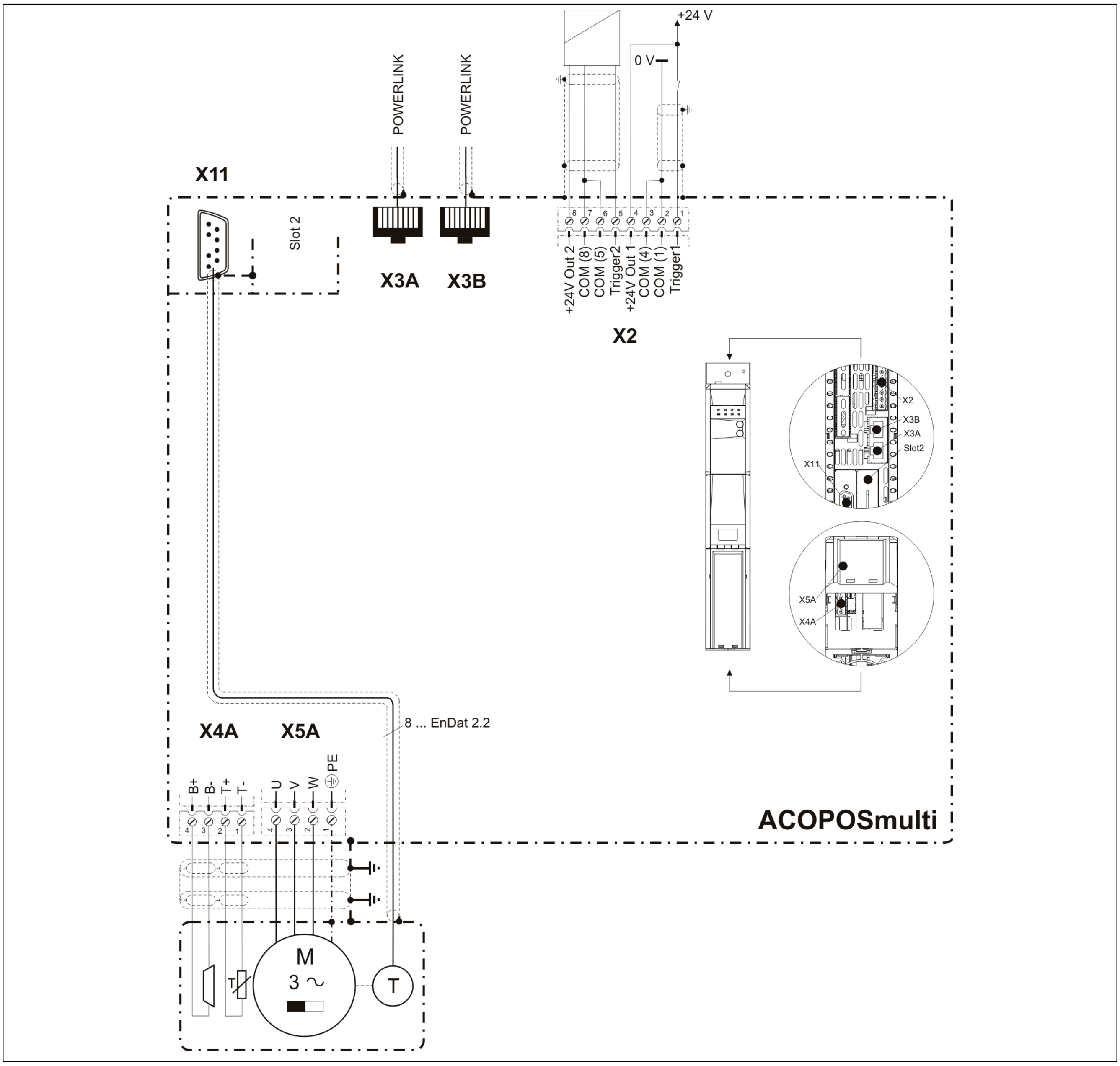


Figure 6: Pinout overview

2.3.2.5.2 ACOPOSmulti SafeMOTION SinCos - Pinout overview

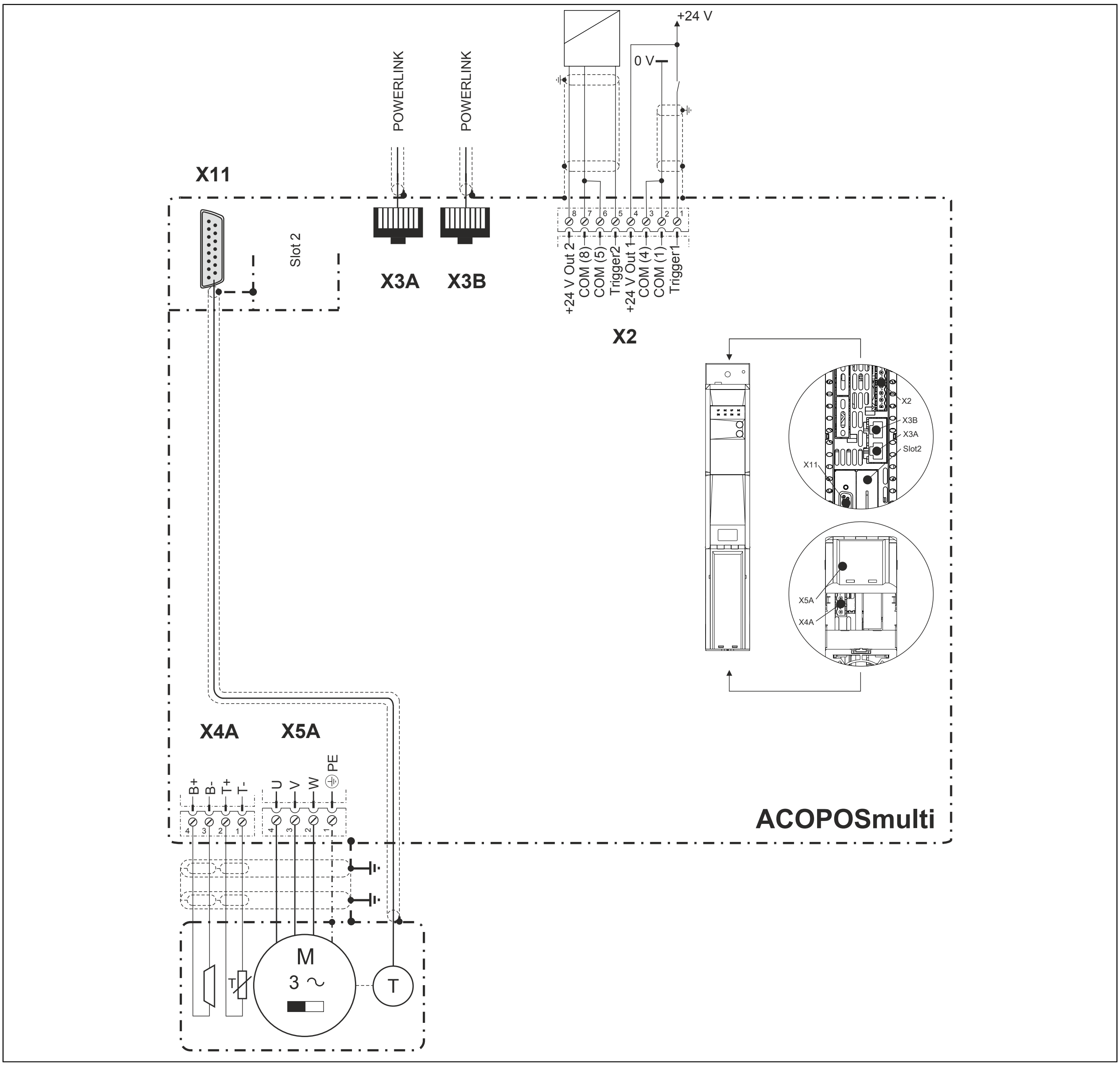


Figure 7: Pinout overview

2.3.2.5.3 Connector X2 - Pinout

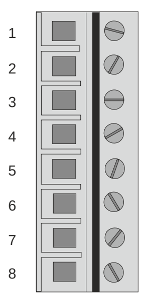
X2	Pin	Description	Function
	1	Trigger 1	Trigger 1
	2	COM (1)	Trigger 1 0 V
	3	COM (2)	+24 V output 1 0 V
	4	+24 V Out 1	+24 V output 1
	5	Trigger 2	Trigger 2
	6	COM (5)	Trigger 2 0 V
	7	COM (8)	+24 V output 2 0 V
	8	+24 V Out 2	+24 V output 2

Table 26: Connector X2 - Pinout

2.3.2.5.4 Connectors X3A, X3B - Pinout

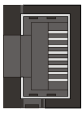
X3A, X3B	Pin	Description	Function
	1	RXD	Receive signal
	2	RXD\	Receive signal inverted
	3	TXD	Transmit signal
	4	Shield	Shield
	5	Shield	Shield
	6	TXD\	Transmit signal inverted
	7	Shield	Shield
	8	Shield	Shield

Table 27: X3A, X3B connectors - Pinout

2.3.2.5.5 X4A connector - Pinout

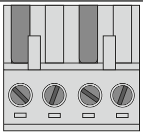
X4A	Description	Function
	T-	Axis 1: Temperature sensor -
	T+	Axis 1: Temperature sensor +
	B-	Axis 1: Brake -
	B+	Axis 1: Brake +

Table 28: Connector X4A - Pinout

Danger!

A short circuit of SBC output B+ against 24 V results in state FUNCTIONAL FAIL SAFE being enabled. This means that safe pulse disabling is enabled. The brake always remains switched on / released, however, due to the short circuit to 24 V!
This can lead to dangerous situations since the motor holding brake cannot brake, prevent the spin-out movement or prevent the unbraked lowering movement when loads are suspended!
A short circuit of SBC output B+ against 24 V must be prevented by suitable wiring measures!

Danger!

The following applies to the SBC output:

- **It is not permitted to be wired across modules!**
- **It is not permitted to be wired as an open emitter!**
- **It is not permitted to be wired as an open collector!**

Danger!

Only an output voltage of ≤ 5 V can be ensured for the safe motor holding brake output when switched off. When selecting the motor holding brake, the user must ensure that the required braking torque is achieved with a voltage of 5 V applied.

Information:

The transistors of the SBC output stage are tested cyclically. When the output channels are active, this test emits low pulses on the output with a maximum length of 600 µs.

This must be taken into consideration when choosing the motor holding brake!

Danger!

The connections for the motor temperature sensors and the motor holding brake are safely isolated circuits. These connections are therefore only permitted to be connected to devices or components that have sufficient isolation per IEC 60364-4-41 or EN 61800-5-1.

Caution!

If B+ and B- are swapped when connecting the permanent magnet holding brakes, then the brakes cannot be opened! ACOPOSmulti inverter modules cannot determine if a holding brake is connected with reverse polarity!

Warning!

Temperature sensors are only permitted to be connected to the X4A/T+ and X4A/T- connectors on an ACOPOSmulti module under the following conditions:

- **SLOT1 of the ACOPOSmulti module does not contain an ACOPOSmulti plug-in module to which a temperature sensor is connected on the T+ and T- connections.**

Otherwise, the temperature monitoring functions on the ACOPOSmulti module may become ineffective, which in extreme cases can cause the hardware (e.g. motors) connected to the ACOPOSmulti module to be destroyed!

2.3.2.5.6 X5A connector - Pinout

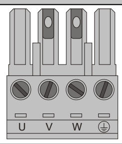
X5A	Description	Function
	⏚	Axis 1: Protective ground conductor
	W	Axis 1: Motor connection W
	V	Axis 1: Motor connection V
	U	Axis 1: Motor connection U

Table 29: Connector X5A - Pinout

Information:

An additional PE wire does not have to be connected to the threaded bolt beside the X5A connector. The PE connection on the male X5A connector is required and sufficient.

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

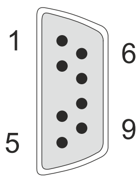
Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

ACOPOSmulti SafeMOTION SinCos

Information:

Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.

2.3.2.5.7 SafeMOTION EnDat 2.2 module - Pinout

Figure	X11 (X12)	Pin	Description	Function
		1	U+	Encoder power supply +12.5 V
		2	---	---
		3	---	---
		4	D	Data input
		5	T	Clock output
		6	COM (1)	Encoder power supply 0 V
		7	---	---
		8	D\	Data input inverted
		9	T\	Clock output inverted

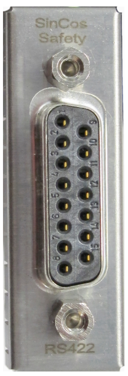
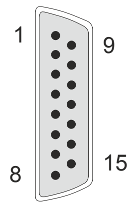
Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

Information:

The SafeMOTION module cannot be replaced! The SafeMOTION module and the ACOPOSmulti SafeMOTION inverter module together form a single unit. In the event of an error, the entire module must be replaced.

2.3.2.5.8 SafeMOTION SinCos module - Pinout

<table>
<tr><th>Figure</th><th>X11</th><th>Pin</th><th>Name</th><th>Function</th></tr>
<tr><td rowspan="15">
</td><td rowspan="15">
</td><td>1</td><td>A</td><td>Channel A/Sin</td></tr>
<tr><td>2</td><td>COM</td><td>Ground</td></tr>
<tr><td>3</td><td>B</td><td>Channel B/COS</td></tr>
<tr><td>4</td><td>+5 V</td><td>Encoder power supply +</td></tr>
<tr><td>5</td><td>D</td><td>Data</td></tr>
<tr><td>6</td><td>---</td><td>---</td></tr>
<tr><td>7</td><td>R\</td><td>Reference pulse inverted/nREF</td></tr>
<tr><td>8</td><td>T</td><td>Clock</td></tr>
<tr><td>9</td><td>A\</td><td>Channel A inverted/nSIN</td></tr>
<tr><td>10</td><td>Sense COM</td><td>Sense ground</td></tr>
<tr><td>11</td><td>B\</td><td>Channel B inverted/nCOS</td></tr>
<tr><td>12</td><td>Sense +5V</td><td>Sense input +5 V</td></tr>
<tr><td>13</td><td>D\</td><td>Data inverted</td></tr>
<tr><td>14</td><td>R</td><td>Reference pulse/REF</td></tr>
<tr><td>15</td><td>T\</td><td>Clock cycle inverted</td></tr>
</table>

Information:

The SafeMOTION module cannot be replaced! The SafeMOTION module and the ACOPOSmulti SafeMOTION inverter module together form a single unit. In the event of an error, the entire module must be replaced.

2.3.3 Safe double-width inverter modules (1-axis modules)

2.3.3.1 8BVI0220HCSS.000-1, 8BVI0220HWSS.000-1, 8BVI0220HCSA.000-1, 8BVI0220HWSA.000-1

2.3.3.1.1 General information

- Clearly structured, straightforward implementation via network-based safety technology
- Modular expandability through virtual wiring
- Immediate triggering of safety function due to short cycle times
- Easy implementation with transparent control and status information, even in the standard application
- Compact design

2.3.3.1.2 Order data

Model number	Short description	Figure
	Cold plate or feed-through mounting	
8BVI0220HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 22 A, HV, cold plate or feed-through mounting	
8BVI0220HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 22 A, HV, cold plate or feed-through mounting	
	Wall mounting	
8BVI0220HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 22 A, HV, wall mounting	
8BVI0220HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 22 A, HV, wall mounting	
	Required accessories	
	Terminal block sets	
8BZVI0220SS.000-1A	Screw clamp terminal block set for ACOPOSmulti 8BVI0220HxSS and 8BVI0220HxSA modules: 1x 8TB2108.2010-00, 1x 8TB2104.203L-00, 1x 8TB4104.204G-00	
	Optional accessories	
	Accessory sets	
8BXB000.0000-00	ACOPOSmulti accessory set for encoder buffering consists of the following: 1 lithium battery AA 3.6 V, 1 cover for battery compartment	
	Fan modules	
8BXF001.0000-00	ACOPOSmulti fan module, replacement fan for ACOPOSmulti modules (8BxP/8B0C/8BVI/8BVE/8B0K)	
	POWERLINK/Ethernet cables	
X20CA0E61.00020	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.2 m	
X20CA0E61.00025	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.25 m	
X20CA0E61.00030	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.3 m	
X20CA0E61.00035	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.35 m	
X20CA0E61.00050	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.5 m	
X20CA0E61.00100	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 1 m	
	Plug-in modules	
8BAC0120.000-1	ACOPOSmulti plug-in module, EnDat 2.1 interface	
8BAC0120.001-2	ACOPOSmulti plug-in module, EnDat 2.2 interface	
8BAC0121.000-1	ACOPOSmulti plug-in module, HIPERFACE interface	
8BAC0122.000-1	ACOPOSmulti plug-in module, resolver interface 10 kHz	
8BAC0123.000-1	ACOPOSmulti plug-in module, incremental encoder and SSI absolute encoder interface for RS422 signals	
8BAC0123.001-1	ACOPOSmulti plug-in module, incremental encoder interface for 5 V single-ended and 5 V differential signals	
8BAC0123.002-1	ACOPOSmulti plug-in module, incremental encoder interface for 24 V single-ended and 24 V differential signals	
8BAC0124.000-1	ACOPOSmulti plug-in module, SinCos interface	
8BAC0125.000-1	ACOPOSmulti plug-in module, SinCos EnDat 2.1/SSI/BiSS interface	
8BAC0130.000-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 2 digital outputs, 500 mA, max. 1.25 kHz, 2 digital inputs 24 VDC	
8BAC0130.001-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 4 digital outputs, 500 mA, max. 1.25 kHz	
8BAC0132.000-1	ACOPOSmulti plug-in module, 4 analog inputs ±10 V	
8BAC0133.000-1	ACOPOSmulti plug-in module, 3 RS422 outputs for ABR encoder emulation, 1 MHz	
	Shield component sets	
8SCS000.0000-00	ACOPOSmulti shield component set: 1 shield plate 1x type 0, 1 hose clamp, B 9 mm, D 12-22 mm	
8SCS002.0000-00	ACOPOSmulti shield component set: 1x clamping plate; 2x clamps D 4-13.5 mm; 4x screws	

Table 30: 8BVI0220HCSS.000-1, 8BVI0220HCSA.000-1, 8BVI0220HWSS.000-1, 8BVI0220HWSA.000-1 - Order data

Model number	Short description	Figure
8SCS009.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK8-14, 1x shield connection clamp SK14	
8SCS010.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK14-20, 1x shield connection clamp SK20	
	Terminal blocks	
8TB2104.203L-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, L keying: 1010	
8TB2108.2010-00	8-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	
8TB4104.204G-00	4-pin screw clamp, single row, spacing: 10.16 mm, label 4: PE W V U, G keying: 0110	

Table 30: 8BVI0220HCSS.000-1, 8BVI0220HCSA.000-1, 8BVI0220HWSS.000-1, 8BVI0220HWSA.000-1 - Order data

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

ACOPOSmulti SafeMOTION SinCos

Information:

Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.

Information:

Only 8BCS encoder cables from B&R are permitted to be connected to the encoder interfaces on B&R standard motors.

For details, see 6.1.2 "Safe power transmission system " on page 283.

2.3.3.1.3 Technical data

Model number	8BVI0220HCSS.000-1	8BVI0220HWSS.000-1	8BVI0220HCSA.000-1	8BVI0220HWSA.000-1
General information				
B&R ID code	0xAA1C	0xAA1E	0xE0B4	0xE0B5
Cooling and mounting type	Cold plate or feed-through mounting	Wall mounting	Cold plate or feed-through mounting	Wall mounting
Slots for plug-in modules	2 [1]	2 [2]	2 [1]	
Certifications				
CE	Yes			
Functional safety [3]	Yes (openSAFETY)			
UL	cULus E225616 Power conversion equipment			
EAC	Yes			
KC	Yes		-	
DC bus connection				
Voltage				
Nominal	750 VDC			
Continuous power consumption [4]	16.2 kW			
Power dissipation depending on switching frequency [5]				
Switching frequency 5 kHz	$[0.13 * I_M^2 + 5.5 * I_M + 40]$ W			
Switching frequency 10 kHz	$[0.43 * I_M^2 + 3.7 * I_M + 110]$ W			
Switching frequency 20 kHz	$[1.4 * I_M^2 + 1.97 * I_M + 230]$ W			
DC bus capacitance	495 µF			
Variant	ACOPOSmulti backplane			
24 VDC power supply				
Input voltage	25 VDC ±1.6%			
Input capacitance	32.9 µF			
Max. power consumption	26 W + P_{SMC1} + P_{SLOT2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake}$ [6]	26 W + P_{SMC1} + P_{SLOT2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake}$ [7]	25 W + P_{SMC1} + P_{SLOT2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake}$ [7]	
Variant	ACOPOSmulti backplane			

Table 31: 8BVI0220HCSS.000-1, 8BVI0220HWSS.000-1, 8BVI0220HCSA.000-1, 8BVI0220HWSA.000-1 - Technical data

Model number	8BVI0220HCSS.000-1	8BVI0220HWSS.000-1	8BVI0220HCSA.000-1	8BVI0220HWSA.000-1
24 VDC output				
Quantity	2			
Output voltage				
DC bus voltage (U_{DC}): 260 to 315 VDC	25 VDC * (U_{DC}/315)			
DC bus voltage (U_{DC}): 315 to 800 VDC	24 VDC ±6%			
Fuse protection	250 mA (slow-blow) electronic, automatic reset			
Motor connection [8]				
Quantity	1			
Continuous power per motor connection [4]	16 kW			
Continuous current per motor connection [4]	22 A_{eff}	22 A_{Eff}	22 A_{eff}	
Reduction of continuous current depending on switching frequency [9]				
Switching frequency 5 kHz	-	No reduction [10]	-	No reduction [10]
Switching frequency 10 kHz	-	0.4 A/K (from 31°C) [11]	-	0.4 A/K (starting at 31°C) [11]
Switching frequency 20 kHz	-	0.31 A/K (from -16°C) [11]	-	0.31 A/K (starting at -16°C) [11]
Reduction of continuous current depending on switching frequency and mounting type [12]				
Switching frequency 5 kHz				
Cold plate mounting [13]	No reduction [10]	-	No reduction [10]	-
Feed-through mounting	No reduction [10]	-	No reduction [10]	-
Switching frequency 10 kHz				
Cold plate mounting [13]	0.36 A/K (starting at 5°C) [14]	-	0.36 A/K (starting at 5°C) [14]	-
Feed-through mounting	0.39 A/K (starting at 26°C) [11]	-	0.39 A/K (starting at 26°C) [11]	-
Switching frequency 20 kHz				
Cold plate mounting [13]	0.5 A/K (starting at 49°C)	-	0.5 A/K (starting at 49°C)	-
Feed-through mounting	0.15 A/K (starting at -59°C) [11]	-	0.15 A/K (starting at -59°C) [11]	-
Reduction of continuous current depending on installation elevation				
Starting at 500 m above sea level	2.2 A_{eff} per 1000 m	2.2 A_{Eff} per 1000 m	2.2 A_{eff} per 1000 m	
Peak current	55 A_{eff}	55 A_{Eff}	55 A_{eff}	
Nominal switching frequency	5 kHz			
Possible switching frequencies [15]	5 / 10 / 20 kHz	5/10/20 kHz	5 / 10 / 20 kHz	
Electrical stress of connected motor per IEC TS 60034-25 [16]	Limit value curve A			
Protective measures				
Overload protection	Yes			
Short circuit and ground fault protection	Yes			
Max. output frequency	598 Hz [17]	598 Hz [18]	598 Hz [17]	
Variant				
U, V, W, PE	Male connector			
Shield connection	Yes			
Terminal connection cross section				
Flexible and fine-stranded wires				
With wire end sleeves	0.5 to 6 mm²		0.5 to 16 mm²	
Approbation data				
UL/C-UL-US	20 to 8			
CSA	20 to 8			
Terminal cable cross section dimension of shield connection	12 to 22 mm			
Max. motor cable length depending on switching frequency				
Switching frequency 5 kHz	25 m			
Switching frequency 10 kHz	25 m			
Switching frequency 20 kHz	25 m			
Motor holding brake connection				
Quantity	1			
Output voltage [19]	24 VDC +5.8% / -0.5% [20]			
Continuous current	4.2 A			
Max. internal resistance	0.15 Ω			
Extinction potential	Approx. 30 V			
Max. extinction energy per switching operation	3 Ws			
Max. switching frequency	0.5 Hz			

Table 31: 8BVI0220HCSS.000-1, 8BVI0220HWSS.000-1, 8BVI0220HCSA.000-1, 8BVI0220HWSA.000-1 - Technical data

Model number	8BVI0220HCSS.000-1	8BVI0220HWSS.000-1	8BVI0220HCSA.000-1	8BVI0220HWSA.000-1
Protective measures				
Overload and short-circuit protection	Yes			
Open circuit monitoring	Yes			
Undervoltage monitoring	Yes			
Response threshold for open circuit monitoring	Approx. 0.5 A			
Response threshold for undervoltage monitoring	24 VDC -2% / -4%			
Encoder interfaces [21]				
Quantity	1			
Type	EnDat 2.2 [22]		SinCos	
Connections	9-pin female DSUB connector		15-pin female DSUB connector	
Status indicators	UP/DN LEDs			
Electrical isolation				
Encoder - ACOPOSmulti	No			
Encoder monitoring	Yes			
Max. encoder cable length	100 m Depends on the cross section of the power supply wires of the encoder cable [23]	100 m Depends on the cross section of the power supply wires in the encoder cable [24]	50 m [25]	
Encoder power supply				
Output voltage	Typ. 12.5 V		5 V ±5% [26]	
Load capacity	350 mA		300 mA [27]	
Sense lines	-		2, compensation of max. 2 x 0.7 V	
Protective measures				
Short-circuit proof	Yes			
Overload-proof	Yes			
Synchronous serial interface				
Signal transmission	RS485			
Data transfer rate	6.25 Mbit/s		781.25 kbit/s	
Sine/Cosine inputs				
Signal transmission	-		Differential signals, symmetrical	
Differential voltage				
In motion	-		0.5 to 1.35 V [28]	
At standstill	-		0.8 to 1.35 V [29]	
Differential voltage deviation per signal period	-		±10% [30]	
Common-mode voltage	-		Max. ±7 V	
Terminating resistor	-		120 Ω	
Max. input frequency	-		200 kHz	
Signal frequency (-5 dB)	-		<300 kHz	
Signal frequency (-3 dB)	-		DC up to 200 kHz	
ADC resolution	-		12-bit	
Reference input				
Signal transmission	-		Differential signal, symmetrical	
Differential voltage for low	-		≤-0.2 V	
Differential voltage for high	-		≥0.2 V	
Common-mode voltage	-		Max. -5 V to +9 V	
Terminating resistor	-		120 Ω	
Position				
Resolution @ 1 V_{SS} [31]	-		Number of encoder lines * 5700	
Accuracy [32]	-		---	
Noise [32]	-		---	
Max. power consumption per encoder interface	P_{SMC}[W] = 19 V * $I_{Encoder}$[A] [33]		P_{SMC}[W] = 25 V * (0.376 A + 0.35 * $I_{Encoder}$[A]) [33]	
Trigger inputs				
Quantity	2			
Circuit	Sink			
Electrical isolation				
Input - Inverter module	Yes			
Input - Input	Yes			
Input voltage				
Nominal	24 VDC			
Maximum	30 VDC			
Switching threshold				
Low	<5 V			
High	>15 V			
Input current at nominal voltage	Approx. 10 mA			
Switching delay				
Rising edge	52 µs ±0.5 µs (digitally filtered)			
Falling edge	53 µs ±0.5 µs (digitally filtered)			

Table 31: 8BVI0220HCSS.000-1, 8BVI0220HWSS.000-1, 8BVI0220HCSA.000-1, 8BVI0220HWSA.000-1 - Technical data

Model number	8BVI0220HCSS.000-1	8BVI0220HWSS.000-1	8BVI0220HCSA.000-1	8BVI0220HWSA.000-1
Modulation compared to ground potential	Max. ±38 V			
Electrical properties				
Discharge capacitance	0.22 µF			
Operating conditions				
Permissible mounting orientations				
Hanging vertically	Yes			
Horizontal, face up	Yes			
Standing horizontally	No			
Installation elevation above sea level				
Nominal	0 to 500 m			
Maximum [34]	4000 m			
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)			
Overvoltage category per EN 61800-5-1	III			
Degree of protection per EN 60529	IP20 [35]			
Ambient conditions				
Temperature				
Operation				
Nominal	5 to 40°C			
Maximum [36]	55°C			
Storage	-25 to 55°C			
Transport	-25 to 70°C			
Relative humidity				
Operation	5 to 85%			
Storage	5 to 95%			
Transport	Max. 95% at 40°C			
Mechanical properties				
Dimensions [37]				
Width	106.5 mm			
Height	317 mm			
Depth				
Wall mounting	-	263 mm	-	263 mm
Cold plate	212 mm	-	212 mm	-
Feed-through mounting	209 mm	-	209 mm	-
Weight	Approx. 3.9 kg	Approx. 5.2 kg	Approx. 3.9 kg	Approx. 5.2 kg
Module width	2			

Table 31: 8BVI0220HCSS.000-1, 8BVI0220HWSS.000-1, 8BVI0220HCSA.000-1, 8BVI0220HWSA.000-1 - Technical data

1) SLOT 2 is available. SLOT 1 of the ACOPOSmulti module is occupied by the SafeMOTION module.
2) SLOT 2 is not occupied. SLOT 1 of the ACOPOSmulti module is occupied by the SafeMOTION module.
3) Achievable safety classifications (safety integrity level, safety category, performance level) are documented in the user's manual (section "Safety technology").
4) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
5) I_M ... Current on motor connection X5A [A_{eff}]
6) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
   P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
   $P_{24\ V\ Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
7) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
   P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
   $P_{24\ V\ Out}$ ... Power [W] that is output to the connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
8) Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.
9) Valid in the following conditions: 750 VDC DC bus voltage. The temperature specifications refer to the ambient temperature.
10) Value for the nominal switching frequency.
11) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
12) Valid for the following conditions: 750 VDC DC bus voltage, minimum permissible coolant flow volume (3 l/min).
13) The temperature specifications refer to the return temperature of the cold plate mounting plate.
14) The module cannot supply the full continuous current at this switching frequency. This unusual value for the return temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
   Caution! Condensation can occur at low flow temperatures and return temperatures.
15) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
16) If necessary, the stress of the motor isolation system can be reduced by an additional externally wired dv/dt choke. For example, the RWK 305 three-phase du/dt choke from Schaffner (www.schaffner.com) can be used. Important: Even when using a dv/dt choke, it is necessary to ensure that an EMC-compatible, low inductance shield connection is used!
17) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
18) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output (power unit: limit speed exceeded).
19) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.

20) The specified value is only valid under the following conditions:
- The 24 VDC supply for the module is provided by an 8B0C auxiliary supply module installed on the same mounting plate.
If the 24 VDC supply for the module is applied to the mounting plate using an 8BVE expansion module, then the output voltage is reduced because of voltage drops on the expansion cable. In this case, undervoltage monitoring must be disabled.
21) Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.
22) An EnDat 2.2 functional safety encoder is required when using ACOPOSmulti SafeMOTION inverter modules! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!
23) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 100 m is not permitted to be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A]
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
24) The maximum encoder cable length l_{Max} can be calculated as follows (the maximum permissible encoder cable length of 100 m must not be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A].
A ... Cross section of the power supply wires [mm²].
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178).
25) The maximum permissible cable length is 50 m.
26) During the power-on procedure for the encoder power supply voltage (2 seconds), the monitoring limit for the supply voltage is increased from 5.25 V to 6 V. In this phase, overvoltages up to 6 V are not detected.
A short-term overvoltage of maximum 6 V is not permitted to damage the encoder electronics in any way.
An undervoltage on the encoder power supply will result in a sine or cosine signal outside the specification.
27) An actual reserve of 12 mA exists for the terminating resistor.
28) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length z = 2 √((Sin - nSin)² + (Cos - nCos)²) is monitored according to the specified limits.
29) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length z = 2 √((Sin - nSin)² + (Cos - nCos)²) is also monitored according to the specified limits from the time the evaluation circuit is switched on until a signal period has passed.
30) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length z = 2 √((Sin - nSin)² + (Cos - nCos)²) is permitted to deviate by a maximum of ±10% per signal period.
31) This value does not correspond to the encoder resolution that must be configured in Automation Studio (16384 * number of encoder lines).
32) Limited by the encoder in practice.
33) $I_{Encoder}$ ... Max. power consumption of the connected encoder [A].
34) Continuous operation at elevations ranging from 500 m to 4,000 m above sea level is possible (taking the specified continuous current reductions into consideration).
35) This value only applies in its delivered state (SLOT2 of the module is sealed by a slot cover / shield plate). If SLOT2 on the module is not sealed, then the level of protection is reduced to IP10. It is important to note that a 8SCS005.0000-00 shield set (slot cover / shield plate) or plug-in module must always be inserted!
36) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous current reductions into consideration), but this will result in a shorter service life.
37) These dimensions refer to the actual device dimensions including the respective mounting plate. Make sure to leave additional space above and below the devices for mounting, connections and air circulation.

2.3.3.1.4 Wiring

For details, see section 2.3.3.4 "Wiring: Safe double-width inverter modules (1-axis modules)" on page 81.

For general information, see section 2.6 "Wiring" on page 150.

2.3.3.2 8BVI0330HCSS.000-1, 8BVI0330HWSS.000-1, 8BVI0330HCSA.000-1, 8BVI0330HWSA.000-1

2.3.3.2.1 General information

- Clearly structured, straightforward implementation via network-based safety technology
- Modular expandability through virtual wiring
- Immediate triggering of safety function due to short cycle times
- Easy implementation with transparent control and status information, even in the standard application
- Compact design

2.3.3.2.2 Order data

Model number	Short description	Figure
	Cold plate or feed-through mounting	
8BVI0330HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 33 A, HV, cold plate or feed-through mounting	
8BVI0330HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 33 A, HV, cold plate or feed-through mounting	
	Wall mounting	
8BVI0330HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 33 A, HV, wall mounting	
8BVI0330HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 33 A, HV, wall mounting	
	Required accessories	
	Terminal block sets	
8BZVI0440SS.000-1A	Screw clamp set for ACOPOSmulti 8BVI0440HxSS, 8BVI0440HxSA modules: 1x 8TB2108.2010-00, 1x 8TB2104.203L-00, 1x 8TB4104.204G-10	
	Optional accessories	
	Accessory sets	
8BXB000.0000-00	ACOPOSmulti accessory set for encoder buffering consists of the following: 1 lithium battery AA 3.6 V, 1 cover for battery compartment	
	Fan modules	
8BXF001.0000-00	ACOPOSmulti fan module, replacement fan for ACOPOSmulti modules (8BxP/8B0C/8BVI/8BVE/8B0K)	
	POWERLINK/Ethernet cables	
X20CA0E61.00020	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.2 m	
X20CA0E61.00025	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.25 m	
X20CA0E61.00030	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.3 m	
X20CA0E61.00035	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.35 m	
X20CA0E61.00050	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.5 m	
X20CA0E61.00100	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 1 m	
	Plug-in modules	
8BAC0120.000-1	ACOPOSmulti plug-in module, EnDat 2.1 interface	
8BAC0120.001-2	ACOPOSmulti plug-in module, EnDat 2.2 interface	
8BAC0121.000-1	ACOPOSmulti plug-in module, HIPERFACE interface	
8BAC0122.000-1	ACOPOSmulti plug-in module, resolver interface 10 kHz	
8BAC0123.000-1	ACOPOSmulti plug-in module, incremental encoder and SSI absolute encoder interface for RS422 signals	
8BAC0123.001-1	ACOPOSmulti plug-in module, incremental encoder interface for 5 V single-ended and 5 V differential signals	
8BAC0123.002-1	ACOPOSmulti plug-in module, incremental encoder interface for 24 V single-ended and 24 V differential signals	
8BAC0124.000-1	ACOPOSmulti plug-in module, SinCos interface	
8BAC0125.000-1	ACOPOSmulti plug-in module, SinCos EnDat 2.1/SSI/BiSS interface	
8BAC0130.000-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 2 digital outputs, 500 mA, max. 1.25 kHz, 2 digital inputs 24 VDC	
8BAC0130.001-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 4 digital outputs, 500 mA, max. 1.25 kHz	
8BAC0132.000-1	ACOPOSmulti plug-in module, 4 analog inputs ±10 V	
8BAC0133.000-1	ACOPOSmulti plug-in module, 3 RS422 outputs for ABR encoder emulation, 1 MHz	
	Shield component sets	
8SCS002.0000-00	ACOPOSmulti shield component set: 1x clamping plate; 2x clamps D 4-13.5 mm; 4x screws	
8SCS007.0000-00	ACOPOSmulti shield component set: 1x shield mounting plate 2x 45°, 4x screws	
8SCS008.0000-00	ACOPOSmulti shield component set: 1x shield plate 2x type 0, 1x hose clamp, B 9 mm, D 23-35 mm	
8SCS010.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK14-20, 1x shield connection clamp SK20	
	Terminal blocks	
8TB2104.203L-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, L keying: 1010	
8TB2108.2010-00	8-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	
8TB4104.204G-10	4-pin screw clamp terminal block, 1-row, spacing: 10.16 mm, label 4: PE W V U, coding G: 0110	

Table 32: 8BVI0330HCSS.000-1, 8BVI0330HCSA.000-1, 8BVI0330HWSS.000-1, 8BVI0330HWSA.000-1 - Order data

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

ACOPOSmulti SafeMOTION SinCos

Information:

Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.

Information:

Only 8BCS encoder cables from B&R are permitted to be connected to the encoder interfaces on B&R standard motors.

For details, see 6.1.2 "Safe power transmission system " on page 283.

2.3.3.2.3 Technical data

Model number	8BVI0330HCSS.000-1	8BVI0330HWSS.000-1	8BVI0330HCSA.000-1	8BVI0330HWSA.000-1
General information				
B&R ID code	0xADC3	0xADC4	0xE0B6	0xE0B7
Cooling and mounting type	Cold plate or feed-through mounting	Wall mounting	Cold plate or feed-through mounting	Wall mounting
Slots for plug-in modules	2 [1]	2 [2]	2 [1]	
Certifications				
CE	Yes			
Functional safety[3]	Yes (openSAFETY)			
UL	cULus E225616 Power conversion equipment			
EAC	Yes			
KC	Yes		-	
DC bus connection				
Voltage				
Nominal	750 VDC			
Continuous power consumption [4]	24.4 kW			
Power dissipation depending on switching frequency [5]				
Switching frequency 5 kHz	$[0.07 * I_M^2 + 7.3 * I_M + 40]$ W			
Switching frequency 10 kHz	$[0.2 * I_M^2 + 11.1 * I_M + 130]$ W			
Switching frequency 20 kHz	$[1.85 * I_M^2 + 3.8 * I_M + 300]$ W			
DC bus capacitance	990 µF			
Variant	ACOPOSmulti backplane			
24 VDC power supply				
Input voltage	25 VDC ±1.6%			
Input capacitance	32.9 µF			
Max. power consumption	31 W + P_{SMC1} + P_{SLOT2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake}$[6]	31 W + P_{SMC1} + P_{SLOT2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake}$[7]	25 W + P_{SMC1} + P_{SLOT2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake}$[7]	
Variant	ACOPOSmulti backplane			
24 VDC output				
Quantity	2			
Output voltage				
DC bus voltage (U_{DC}): 260 to 315 VDC	25 VDC * (U_{DC}/315)			
DC bus voltage (U_{DC}): 315 to 800 VDC	24 VDC ±6%			
Fuse protection	250 mA (slow-blow) electronic, automatic reset			
Motor connection [8]				
Quantity	1			
Continuous power per motor connection [4]	24 kW			
Continuous current per motor connection [4]	33 A_{eff}	33 A_{Eff}	33 A_{eff}	

Table 33: 8BVI0330HCSS.000-1, 8BVI0330HWSS.000-1, 8BVI0330HCSA.000-1, 8BVI0330HWSA.000-1 - Technical data

Model number	8BVI0330HCSS.000-1	8BVI0330HWSS.000-1	8BVI0330HCSA.000-1	8BVI0330HWSA.000-1
Reduction of continuous current depending on switching frequency [9]				
Switching frequency 5 kHz	-	1.57 A/K (from 40°C) [10]	-	1.57 A/K (starting at 40°C) [10]
Switching frequency 10 kHz	-	0.5 A/K (from -10°C) [11]	-	0.5 A/K (starting at -10°C) [11]
Switching frequency 20 kHz	-	0.36 A/K (from -77°C) [11]	-	0.36 A/K (starting at -77°C) [11]
Reduction of continuous current depending on switching frequency and mounting type [12]				
Switching frequency 5 kHz				
Cold plate mounting [13]	0.8 A/K (starting at 45°C) [10]	-	0.8 A/K (starting at 45°C) [10]	-
Feed-through mounting	1.26 A/K (starting at 40°C) [10]	-	1.26 A/K (starting at 40°C) [10]	-
Switching frequency 10 kHz				
Cold plate mounting [13]	0.62 A/K (starting at 6°C) [14]	-	0.62 A/K (starting at 6°C) [14]	-
Feed-through mounting	0.37 A/K (starting at -36°C) [11]	-	0.37 A/K (starting at -36°C) [11]	-
Switching frequency 20 kHz				
Cold plate mounting [13]	0.32 A/K (starting at -82°C) [14]	-	0.32 A/K (starting at -82°C) [14]	-
Feed-through mounting	0.24 A/K (starting at -137°C) [11]	-	0.24 A/K (starting at -137°C) [11]	-
Reduction of continuous current depending on installation elevation				
Starting at 500 m above sea level	3.3 A_{eff} per 1000 m	3.3 A_{Eff} per 1000 m	3.3 A_{eff} per 1000 m	
Peak current	83 A_{eff}	83 A_{Eff}	83 A_{eff}	
Nominal switching frequency	5 kHz			
Possible switching frequencies [15]	5 / 10 / 20 kHz	5/10/20 kHz	5 / 10 / 20 kHz	
Electrical stress of connected motor per IEC TS 60034-25 [16]	Limit value curve A			
Protective measures				
Overload protection	Yes			
Short circuit and ground fault protection	Yes			
Max. output frequency	598 Hz [17]	598 Hz [18]	598 Hz [17]	
Variant				
U, V, W, PE	Male connector			
Shield connection	Yes			
Terminal connection cross section				
Flexible and fine-stranded wires				
With wire end sleeves	0.5 to 16 mm²			
Approbation data				
UL/C-UL-US	20 to 6			
CSA	20 to 6			
Terminal cable cross section dimension of shield connection	23 to 35 mm			
Max. motor cable length depending on switching frequency				
Switching frequency 5 kHz	25 m			
Switching frequency 10 kHz	25 m			
Switching frequency 20 kHz	25 m			
Motor holding brake connection				
Quantity	1			
Output voltage [19]	24 VDC +5.8% / -0.5% [20]			
Continuous current	4.2 A			
Max. internal resistance	0.15 Ω			
Extinction potential	Approx. 30 V			
Max. extinction energy per switching operation	3 Ws			
Max. switching frequency	0.5 Hz			
Protective measures				
Overload and short-circuit protection	Yes			
Open circuit monitoring	Yes			
Undervoltage monitoring	Yes			
Response threshold for open circuit monitoring	Approx. 0.5 A			
Response threshold for undervoltage monitoring	24 VDC -2% / -4%			
Encoder interfaces [21]				
Quantity	1			
Type	EnDat 2.2 [22]		SinCos	
Connections	9-pin female DSUB connector		15-pin female DSUB connector	
Status indicators	UP/DN LEDs			

Table 33: 8BVI0330HCSS.000-1, 8BVI0330HWSS.000-1, 8BVI0330HCSA.000-1, 8BVI0330HWSA.000-1 - Technical data

Model number	8BVI0330HCSS.000-1	8BVI0330HWSS.000-1	8BVI0330HCSA.000-1	8BVI0330HWSA.000-1
Electrical isolation				
Encoder - ACOPOSmulti	No			
Encoder monitoring	Yes			
Max. encoder cable length	100 m Depends on the cross section of the power supply wires of the encoder cable [23]	100 m Depends on the cross section of the power supply wires in the encoder cable [24]	50 m [25]	
Encoder power supply				
Output voltage	Typ. 12.5 V		5 V ±5% [26]	
Load capacity	350 mA		300 mA [27]	
Sense lines	-		2, compensation of max. 2 x 0.7 V	
Protective measures				
Short-circuit proof	Yes			
Overload-proof	Yes			
Synchronous serial interface				
Signal transmission	RS485			
Data transfer rate	6.25 Mbit/s		781.25 kbit/s	
Sine/Cosine inputs				
Signal transmission	-		Differential signals, symmetrical	
Differential voltage				
In motion	-		0.5 to 1.35 V [28]	
At standstill	-		0.8 to 1.35 V [29]	
Differential voltage deviation per signal period	-		±10% [30]	
Common-mode voltage	-		Max. ±7 V	
Terminating resistor	-		120 Ω	
Max. input frequency	-		200 kHz	
Signal frequency (-5 dB)	-		<300 kHz	
Signal frequency (-3 dB)	-		DC up to 200 kHz	
ADC resolution	-		12-bit	
Reference input				
Signal transmission	-		Differential signal, symmetrical	
Differential voltage for low	-		≤-0.2 V	
Differential voltage for high	-		≥0.2 V	
Common-mode voltage	-		Max. -5 V to +9 V	
Terminating resistor	-		120 Ω	
Position				
Resolution @ 1 V_{SS} [31]	-		Number of encoder lines * 5700	
Accuracy [32]	-		---	
Noise [32]	-		---	
Max. power consumption per encoder interface	P_{SMC}[W] = 19 V * $I_{Encoder}$[A] [33]		P_{SMC}[W] = 25 V * (0.376 A + 0.35 * $I_{Encoder}$[A]) [33]	
Trigger inputs				
Quantity	2			
Circuit	Sink			
Electrical isolation				
Input - Inverter module	Yes			
Input - Input	Yes			
Input voltage				
Nominal	24 VDC			
Maximum	30 VDC			
Switching threshold				
Low	<5 V			
High	>15 V			
Input current at nominal voltage	Approx. 10 mA			
Switching delay				
Rising edge	52 µs ±0.5 µs (digitally filtered)			
Falling edge	53 µs ±0.5 µs (digitally filtered)			
Modulation compared to ground potential	Max. ±38 V			
Electrical properties				
Discharge capacitance	0.22 µF			
Operating conditions				
Permissible mounting orientations				
Hanging vertically	Yes			
Horizontal, face up	Yes			
Standing horizontally	No			
Installation elevation above sea level				
Nominal	0 to 500 m			
Maximum [34]	4000 m			
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)			
Overvoltage category per EN 61800-5-1	III			

Table 33: 8BVI0330HCSS.000-1, 8BVI0330HWSS.000-1, 8BVI0330HCSA.000-1, 8BVI0330HWSA.000-1 - Technical data

Model number	8BVI0330HCSS.000-1	8BVI0330HWSS.000-1	8BVI0330HCSA.000-1	8BVI0330HWSA.000-1
Degree of protection per EN 60529	IP20 [35]			
Ambient conditions				
Temperature				
Operation				
Nominal	5 to 40°C			
Maximum [36]	55°C			
Storage	-25 to 55°C			
Transport	-25 to 70°C			
Relative humidity				
Operation	5 to 85%			
Storage	5 to 95%			
Transport	Max. 95% at 40°C			
Mechanical properties				
Dimensions [37]				
Width	106.5 mm			
Height	317 mm			
Depth				
Wall mounting	-	263 mm	-	263 mm
Cold plate	212 mm	-	212 mm	-
Feed-through mounting	209 mm	-	209 mm	-
Weight	Approx. 4.3 kg	Approx. 5.4 kg	Approx. 4.3 kg	Approx. 5.4 kg
Module width	2			

Table 33: 8BVI0330HCSS.000-1, 8BVI0330HWSS.000-1, 8BVI0330HCSA.000-1, 8BVI0330HWSA.000-1 - Technical data

1) SLOT 2 is available. SLOT 1 of the ACOPOSmulti module is occupied by the SafeMOTION module.
2) SLOT 2 is not occupied. SLOT 1 of the ACOPOSmulti module is occupied by the SafeMOTION module.
3) Achievable safety classifications (safety integrity level, safety category, performance level) are documented in the user's manual (section "Safety technology").
4) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
5) I_M ... Current on motor connection X5A [A_{eff}]
6) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
$P_{24\,V\,Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
7) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
$P_{24\,V\,Out}$ ... Power [W] that is output to the connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
8) Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.
9) Valid in the following conditions: 750 VDC DC bus voltage. The temperature specifications refer to the ambient temperature.
10) Value for the nominal switching frequency.
11) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
12) Valid for the following conditions: 750 VDC DC bus voltage, minimum permissible coolant flow volume (3 l/min).
13) The temperature specifications refer to the return temperature of the cold plate mounting plate.
14) The module cannot supply the full continuous current at this switching frequency. This unusual value for the return temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
Caution! Condensation can occur at low flow temperatures and return temperatures.
15) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
16) If necessary, the stress of the motor isolation system can be reduced by an additional externally wired dv/dt choke. For example, the RWK 305 three-phase du/dt choke from Schaffner (www.schaffner.com) can be used. Important: Even when using a dv/dt choke, it is necessary to ensure that an EMC-compatible, low inductance shield connection is used!
17) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
18) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output (power unit: limit speed exceeded).
19) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
20) The specified value is only valid under the following conditions:
- The 24 VDC supply for the module is provided by an 8B0C auxiliary supply module installed on the same mounting plate.
If the 24 VDC supply for the module is applied to the mounting plate using an 8BVE expansion module, then the output voltage is reduced because of voltage drops on the expansion cable. In this case, undervoltage monitoring must be disabled.
21) Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.
22) An EnDat 2.2 functional safety encoder is required when using ACOPOSmulti SafeMOTION inverter modules! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!
23) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 100 m is not permitted to be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A].
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)

24) The maximum encoder cable length l_{Max} can be calculated as follows (the maximum permissible encoder cable length of 100 m must not be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A].
A ... Cross section of the power supply wires [mm²].
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178).

25) The maximum permissible cable length is 50 m.

26) During the power-on procedure for the encoder power supply voltage (2 seconds), the monitoring limit for the supply voltage is increased from 5.25 V to 6 V. In this phase, overvoltages up to 6 V are not detected.
A short-term overvoltage of maximum 6 V is not permitted to damage the encoder electronics in any way.
An undervoltage on the encoder power supply will result in a sine or cosine signal outside the specification.

27) An actual reserve of 12 mA exists for the terminating resistor.

28) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2\sqrt{(Sin - nSin)^2 + (Cos - nCos)^2}$ is monitored according to the specified limits.

29) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2\sqrt{(Sin - nSin)^2 + (Cos - nCos)^2}$ is also monitored according to the specified limits from the time the evaluation circuit is switched on until a signal period has passed.

30) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2\sqrt{(Sin - nSin)^2 + (Cos - nCos)^2}$ is permitted to deviate by a maximum of ±10% per signal period.

31) This value does not correspond to the encoder resolution that must be configured in Automation Studio (16384 * number of encoder lines).

32) Limited by the encoder in practice.

33) $I_{Encoder}$ ... Max. power consumption of the connected encoder [A].

34) Continuous operation at elevations ranging from 500 m to 4,000 m above sea level is possible (taking the specified continuous current reductions into consideration).

35) This value only applies in its delivered state (SLOT2 of the module is sealed by a slot cover / shield plate). If SLOT2 on the module is not sealed, then the level of protection is reduced to IP10. It is important to note that a 8SCS005.0000-00 shield set (slot cover / shield plate) or plug-in module must always be inserted!

36) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous current reductions into consideration), but this will result in a shorter service life.

37) These dimensions refer to the actual device dimensions including the respective mounting plate. Make sure to leave additional space above and below the devices for mounting, connections and air circulation.

2.3.3.2.4 Wiring

For details, see section 2.3.3.4 "Wiring: Safe double-width inverter modules (1-axis modules)" on page 81.

For general information, see section 2.6 "Wiring" on page 150.

2.3.3.3 8BVI0440HCSS.000-1, 8BVI0440HWSS.000-1, 8BVI0440HCSA.000-1, 8BVI0440HWSA.000-1

2.3.3.3.1 General information

- Clearly structured, straightforward implementation via network-based safety technology
- Modular expandability through virtual wiring
- Immediate triggering of safety function due to short cycle times
- Easy implementation with transparent control and status information, even in the standard application
- Compact design

2.3.3.3.2 Order data

Model number	Short description	Figure
	Cold plate or feed-through mounting	
8BVI0440HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 44 A, HV, cold plate or feed-through mounting	
8BVI0440HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 44 A, HV, cold plate or feed-through mounting	
	Wall mounting	
8BVI0440HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 44 A, HV, wall mounting	
8BVI0440HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 44 A, HV, wall mounting	
	Required accessories	
	Terminal block sets	
8BZVI0440SS.000-1A	Screw clamp set for ACOPOSmulti 8BVI0440HxSS, 8BVI0440HxSA modules: 1x 8TB2108.2010-00, 1x 8TB2104.203L-00, 1x 8TB4104.204G-10	
	Optional accessories	
	Accessory sets	
8BXB000.0000-00	ACOPOSmulti accessory set for encoder buffering consists of the following: 1 lithium battery AA 3.6 V, 1 cover for battery compartment	
	Fan modules	
8BXF001.0000-00	ACOPOSmulti fan module, replacement fan for ACOPOSmulti modules (8BxP/8B0C/8BVI/8BVE/8B0K)	

Table 34: 8BVI0440HCSS.000-1, 8BVI0440HCSA.000-1, 8BVI0440HWSS.000-1, 8BVI0440HWSA.000-1 - Order data

Model number	Short description	Figure
	POWERLINK/Ethernet cables	
X20CA0E61.00020	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.2 m	
X20CA0E61.00025	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.25 m	
X20CA0E61.00030	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.3 m	
X20CA0E61.00035	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.35 m	
X20CA0E61.00050	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.5 m	
X20CA0E61.00100	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 1 m	
	Plug-in modules	
8BAC0120.000-1	ACOPOSmulti plug-in module, EnDat 2.1 interface	
8BAC0120.001-2	ACOPOSmulti plug-in module, EnDat 2.2 interface	
8BAC0121.000-1	ACOPOSmulti plug-in module, HIPERFACE interface	
8BAC0122.000-1	ACOPOSmulti plug-in module, resolver interface 10 kHz	
8BAC0123.000-1	ACOPOSmulti plug-in module, incremental encoder and SSI absolute encoder interface for RS422 signals	
8BAC0123.001-1	ACOPOSmulti plug-in module, incremental encoder interface for 5 V single-ended and 5 V differential signals	
8BAC0123.002-1	ACOPOSmulti plug-in module, incremental encoder interface for 24 V single-ended and 24 V differential signals	
8BAC0124.000-1	ACOPOSmulti plug-in module, SinCos interface	
8BAC0125.000-1	ACOPOSmulti plug-in module, SinCos EnDat 2.1/SSI/BiSS interface	
8BAC0130.000-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 2 digital outputs, 500 mA, max. 1.25 kHz, 2 digital inputs 24 VDC	
8BAC0130.001-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 4 digital outputs, 500 mA, max. 1.25 kHz	
8BAC0132.000-1	ACOPOSmulti plug-in module, 4 analog inputs ±10 V	
8BAC0133.000-1	ACOPOSmulti plug-in module, 3 RS422 outputs for ABR encoder emulation, 1 MHz	
	Shield component sets	
8SCS002.0000-00	ACOPOSmulti shield component set: 1x clamping plate; 2x clamps D 4-13.5 mm; 4x screws	
8SCS007.0000-00	ACOPOSmulti shield component set: 1x shield mounting plate 2x 45°, 4x screws	
8SCS008.0000-00	ACOPOSmulti shield component set: 1x shield plate 2x type 0, 1x hose clamp, B 9 mm, D 23-35 mm	
8SCS010.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK14-20, 1x shield connection clamp SK20	
	Terminal blocks	
8TB2104.203L-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, L keying: 1010	
8TB2108.2010-00	8-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	
8TB4104.204G-10	4-pin screw clamp terminal block, 1-row, spacing: 10.16 mm, label 4: PE W V U, coding G: 0110	

Table 34: 8BVI0440HCSS.000-1, 8BVI0440HCSA.000-1, 8BVI0440HWSS.000-1, 8BVI0440HWSA.000-1 - Order data

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

ACOPOSmulti SafeMOTION SinCos

Information:

Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.

Information:

Only 8BCS encoder cables from B&R are permitted to be connected to the encoder interfaces on B&R standard motors.

For details, see 6.1.2 "Safe power transmission system " on page 283.

2.3.3.3.3 Technical data

Model number	8BVI0440HCSS.000-1	8BVI0440HWSS.000-1	8BVI0440HCSA.000-1	8BVI0440HWSA.000-1
General information				
B&R ID code	0xAA1F	0xAA20	0xD5CB	0xC5FE
Cooling and mounting type	Cold plate or feed-through mounting	Wall mounting	Cold plate or feed-through mounting	Wall mounting
Slots for plug-in modules	2 [1]	2 [2]	2 [1]	
Certifications				
CE	Yes			
Functional safety[3]	Yes (openSAFETY)			
UL	cULus E225616 Power conversion equipment			
EAC	Yes			
KC	Yes		-	Yes
DC bus connection				
Voltage				
Nominal	750 VDC			
Continuous power consumption [4]	32.5 kW			
Power dissipation depending on switching frequency [5]				
Switching frequency 5 kHz	[0.07 * I_M^2 + 7.3 * I_M + 40] W			
Switching frequency 10 kHz	[0.2 * I_M^2 + 11.1 * I_M + 130] W			
Switching frequency 20 kHz	[1.85 * I_M^2 + 3.8 * I_M + 300] W			
DC bus capacitance	990 µF			
Variant	ACOPOSmulti backplane			
24 VDC power supply				
Input voltage	25 VDC ±1.6%			
Input capacitance	32.9 µF			
Max. power consumption	31 W + P_{SMC1} + P_{SLOT2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake}$[6]	31 W + P_{SMC1} + P_{SLOT2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake}$[7]	25 W + P_{SMC1} + P_{SLOT2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake}$[7]	
Variant	ACOPOSmulti backplane			
24 VDC output				
Quantity	2			
Output voltage				
DC bus voltage (U_{DC}): 260 to 315 VDC	25 VDC * (U_{DC}/315)			
DC bus voltage (U_{DC}): 315 to 800 VDC	24 VDC ±6%			
Fuse protection	250 mA (slow-blow) electronic, automatic reset			
Motor connection [8]				
Quantity	1			
Continuous power per motor connection [4]	32 kW			
Continuous current per motor connection [4]	44 A_{eff}	44 A_{Eff}	44 A_{eff}	
Reduction of continuous current depending on switching frequency [9]				
Switching frequency 5 kHz	-	1.57 A/K (from 40°C) [10]	-	1.57 A/K (starting at 40°C) [10]
Switching frequency 10 kHz	-	0.5 A/K (from -10°C) [11]	-	0.5 A/K (starting at -10°C) [11]
Switching frequency 20 kHz	-	0.36 A/K (from -77°C) [11]	-	0.36 A/K (starting at -77°C) [11]
Reduction of continuous current depending on switching frequency and mounting type [12]				
Switching frequency 5 kHz				
Cold plate mounting [13]	0.8 A/K (starting at 45°C) [10]	-	0.8 A/K (starting at 45°C) [10]	-
Feed-through mounting	1.26 A/K (starting at 40°C) [10]	-	1.26 A/K (starting at 40°C) [10]	-
Switching frequency 10 kHz				
Cold plate mounting [13]	0.62 A/K (starting at 6°C) [14]	-	0.62 A/K (starting at 6°C) [14]	-
Feed-through mounting	0.37 A/K (starting at -36°C) [11]	-	0.37 A/K (starting at -36°C) [11]	-
Switching frequency 20 kHz				
Cold plate mounting [13]	0.32 A/K (starting at -82°C) [14]	-	0.32 A/K (starting at -82°C) [14]	-
Feed-through mounting	0.24 A/K (starting at -137°C) [11]	-	0.24 A/K (starting at -137°C) [11]	-
Reduction of continuous current depending on installation elevation				
Starting at 500 m above sea level	4.4 A_{eff} per 1000 m	4.4 A_{Eff} per 1000 m	4.4 A_{eff} per 1000 m	
Peak current	88 A_{eff}	88 A_{Eff}	88 A_{eff}	
Nominal switching frequency	5 kHz			
Possible switching frequencies [15]	5 / 10 / 20 kHz	5/10/20 kHz	5 / 10 / 20 kHz	

Table 35: 8BVI0440HCSS.000-1, 8BVI0440HWSS.000-1, 8BVI0440HCSA.000-1, 8BVI0440HWSA.000-1 - Technical data

Model number	8BVI0440HCSS.000-1	8BVI0440HWSS.000-1	8BVI0440HCSA.000-1	8BVI0440HWSA.000-1
Electrical stress of connected motor per IEC TS 60034-25 [16]	Limit value curve A			
Protective measures				
Overload protection	Yes			
Short circuit and ground fault protection	Yes			
Max. output frequency	598 Hz [17]	598 Hz [18]	598 Hz [17]	
Variant				
U, V, W, PE	Male connector			
Shield connection	Yes			
Terminal connection cross section				
Flexible and fine-stranded wires				
With wire end sleeves	0.5 to 16 mm²			
Approbation data				
UL/C-UL-US	20 to 6			
CSA	20 to 6			
Terminal cable cross section dimension of shield connection	23 to 35 mm			
Max. motor cable length depending on switching frequency				
Switching frequency 5 kHz	25 m			
Switching frequency 10 kHz	25 m			
Switching frequency 20 kHz	25 m			
Motor holding brake connection				
Quantity	1			
Output voltage [19]	24 VDC +5.8% / -0.5% [20]			
Continuous current	4.2 A			
Max. internal resistance	0.15 Ω			
Extinction potential	Approx. 30 V			
Max. extinction energy per switching operation	3 Ws			
Max. switching frequency	0.5 Hz			
Protective measures				
Overload and short-circuit protection	Yes			
Open circuit monitoring	Yes			
Undervoltage monitoring	Yes			
Response threshold for open circuit monitoring	Approx. 0.5 A			
Response threshold for undervoltage monitoring	24 VDC -2% / -4%			
Encoder interfaces [21]				
Quantity	1			
Type	EnDat 2.2 [22]		SinCos	
Connections	9-pin female DSUB connector		15-pin female DSUB connector	
Status indicators	UP/DN LEDs			
Electrical isolation				
Encoder - ACOPOSmulti	No			
Encoder monitoring	Yes			
Max. encoder cable length	100 m Depends on the cross section of the power supply wires of the encoder cable [23]	100 m Depends on the cross section of the power supply wires in the encoder cable [24]	50 m [25]	
Encoder power supply				
Output voltage	Typ. 12.5 V		5 V ±5% [26]	
Load capacity	350 mA		300 mA [27]	
Sense lines	-		2, compensation of max. 2 x 0.7 V	
Protective measures				
Short-circuit proof	Yes			
Overload-proof	Yes			
Synchronous serial interface				
Signal transmission	RS485			
Data transfer rate	6.25 Mbit/s		781.25 kbit/s	

Table 35: 8BVI0440HCSS.000-1, 8BVI0440HWSS.000-1, 8BVI0440HCSA.000-1, 8BVI0440HWSA.000-1 - Technical data

Model number	8BVI0440HCSS.000-1	8BVI0440HWSS.000-1	8BVI0440HCSA.000-1	8BVI0440HWSA.000-1
Sine/Cosine inputs				
Signal transmission	-		Differential signals, symmetrical	
Differential voltage				
In motion	-		0.5 to 1.35 V [28]	
At standstill	-		0.8 to 1.35 V [29]	
Differential voltage deviation per signal period	-		±10% [30]	
Common-mode voltage	-		Max. ±7 V	
Terminating resistor	-		120 Ω	
Max. input frequency	-		200 kHz	
Signal frequency (-5 dB)	-		<300 kHz	
Signal frequency (-3 dB)	-		DC up to 200 kHz	
ADC resolution	-		12-bit	
Reference input				
Signal transmission	-		Differential signal, symmetrical	
Differential voltage for low	-		≤-0.2 V	
Differential voltage for high	-		≥0.2 V	
Common-mode voltage	-		Max. -5 V to +9 V	
Terminating resistor	-		120 Ω	
Position				
Resolution @ 1 V_{SS} [31]	-		Number of encoder lines * 5700	
Accuracy [32]	-		---	
Noise [32]	-		---	
Max. power consumption per encoder interface	P_{SMC}[W] = 19 V * $I_{Encoder}$[A] [33]		P_{SMC}[W] = 25 V * (0.376 A + 0.35 * $I_{Encoder}$[A]) [33]	
Trigger inputs				
Quantity	2			
Circuit	Sink			
Electrical isolation				
Input - Inverter module	Yes			
Input - Input	Yes			
Input voltage				
Nominal	24 VDC			
Maximum	30 VDC			
Switching threshold				
Low	<5 V			
High	>15 V			
Input current at nominal voltage	Approx. 10 mA			
Switching delay				
Rising edge	52 µs ±0.5 µs (digitally filtered)			
Falling edge	53 µs ±0.5 µs (digitally filtered)			
Modulation compared to ground potential	Max. ±38 V			
Electrical properties				
Discharge capacitance	0.22 µF			
Operating conditions				
Permissible mounting orientations				
Hanging vertically	Yes			
Horizontal, face up	Yes			
Standing horizontally	No			
Installation elevation above sea level				
Nominal	0 to 500 m			
Maximum [34]	4000 m			
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)			
Overvoltage category per EN 61800-5-1	III			
Degree of protection per EN 60529	IP20 [35]			
Ambient conditions				
Temperature				
Operation				
Nominal	5 to 40°C			
Maximum [36]	55°C			
Storage	-25 to 55°C			
Transport	-25 to 70°C			
Relative humidity				
Operation	5 to 85%			
Storage	5 to 95%			
Transport	Max. 95% at 40°C			

Table 35: 8BVI0440HCSS.000-1, 8BVI0440HWSS.000-1, 8BVI0440HCSA.000-1, 8BVI0440HWSA.000-1 - Technical data

Model number	8BVI0440HCSS.000-1	8BVI0440HWSS.000-1	8BVI0440HCSA.000-1	8BVI0440HWSA.000-1
Mechanical properties				
Dimensions [37]				
Width	106.5 mm			
Height	317 mm			
Depth				
Wall mounting	-	263 mm	-	263 mm
Cold plate	212 mm	-	212 mm	-
Feed-through mounting	209 mm	-	209 mm	-
Weight	Approx. 4.3 kg	Approx. 5.4 kg	Approx. 4.3 kg	Approx. 5.4 kg
Module width	2			

Table 35: 8BVI0440HCSS.000-1, 8BVI0440HWSS.000-1, 8BVI0440HCSA.000-1, 8BVI0440HWSA.000-1 - Technical data

1) SLOT 2 is available. SLOT 1 of the ACOPOSmulti module is occupied by the SafeMOTION module.
2) SLOT 2 is not occupied. SLOT 1 of the ACOPOSmulti module is occupied by the SafeMOTION module.
3) Achievable safety classifications (safety integrity level, safety category, performance level) are documented in the user's manual (section "Safety technology").
4) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
5) I_M ... Current on motor connection X5A [A_{eff}]
6) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
   P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
   $P_{24\,V\,Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
7) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
   P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
   $P_{24\,V\,Out}$ ... Power [W] that is output to the connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
8) Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.
9) Valid in the following conditions: 750 VDC DC bus voltage. The temperature specifications refer to the ambient temperature.
10) Value for the nominal switching frequency.
11) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
12) Valid for the following conditions: 750 VDC DC bus voltage, minimum permissible coolant flow volume (3 l/min).
13) The temperature specifications refer to the return temperature of the cold plate mounting plate.
14) The module cannot supply the full continuous current at this switching frequency. This unusual value for the return temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
    Caution! Condensation can occur at low flow temperatures and return temperatures.
15) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
16) If necessary, the stress of the motor isolation system can be reduced by an additional externally wired dv/dt choke. For example, the RWK 305 three-phase du/dt choke from Schaffner (www.schaffner.com) can be used. Important: Even when using a dv/dt choke, it is necessary to ensure that an EMC-compatible, low inductance shield connection is used!
17) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
18) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output (power unit: limit speed exceeded).
19) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
20) The specified value is only valid under the following conditions:
    - The 24 VDC supply for the module is provided by an 8B0C auxiliary supply module installed on the same mounting plate.
    If the 24 VDC supply for the module is applied to the mounting plate using an 8BVE expansion module, then the output voltage is reduced because of voltage drops on the expansion cable. In this case, undervoltage monitoring must be disabled.
21) Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.
22) An EnDat 2.2 functional safety encoder is required when using ACOPOSmulti SafeMOTION inverter modules! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!
23) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 100 m is not permitted to be exceeded):

    $l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

    I_G ... Max. current consumption of the encoder [A].
    A ... Cross section of the power supply wires [mm²]
    ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
24) The maximum encoder cable length l_{Max} can be calculated as follows (the maximum permissible encoder cable length of 100 m must not be exceeded):

    $l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

    I_G ... Max. current consumption of the encoder [A].
    A ... Cross section of the power supply wires [mm²].
    ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178).
25) The maximum permissible cable length is 50 m.
26) During the power-on procedure for the encoder power supply voltage (2 seconds), the monitoring limit for the supply voltage is increased from 5.25 V to 6 V. In this phase, overvoltages up to 6 V are not detected.
    A short-term overvoltage of maximum 6 V is not permitted to damage the encoder electronics in any way.
    An undervoltage on the encoder power supply will result in a sine or cosine signal outside the specification.
27) An actual reserve of 12 mA exists for the terminating resistor.
28) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
    The pointer length $z = 2\sqrt{(Sin - nSin)^2 + (Cos - nCos)^2}$ is monitored according to the specified limits.

29) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2\sqrt{(Sin - nSin)^2 + (Cos - nCos)^2}$ is also monitored according to the specified limits from the time the evaluation circuit is switched on until a signal period has passed.
30) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2\sqrt{(Sin - nSin)^2 + (Cos - nCos)^2}$ is permitted to deviate by a maximum of ±10% per signal period.
31) This value does not correspond to the encoder resolution that must be configured in Automation Studio (16384 * number of encoder lines).
32) Limited by the encoder in practice.
33) $I_{Encoder}$ ... Max. power consumption of the connected encoder [A].
34) Continuous operation at elevations ranging from 500 m to 4,000 m above sea level is possible (taking the specified continuous current reductions into consideration).
35) This value only applies in its delivered state (SLOT2 of the module is sealed by a slot cover / shield plate). If SLOT2 on the module is not sealed, then the level of protection is reduced to IP10. It is important to note that a 8SCS005.0000-00 shield set (slot cover / shield plate) or plug-in module must always be inserted!
36) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous current reductions into consideration), but this will result in a shorter service life.
37) These dimensions refer to the actual device dimensions including the respective mounting plate. Make sure to leave additional space above and below the devices for mounting, connections and air circulation.

2.3.3.3.4 Wiring

For details, see section 2.3.3.4 "Wiring: Safe double-width inverter modules (1-axis modules)" on page 81.

For general information, see section 2.6 "Wiring" on page 150.

2.3.3.4 Wiring: Safe double-width inverter modules (1-axis modules)

2.3.3.4.1 ACOPOSmulti SafeMOTION EnDat 2.2 - Pinout overview

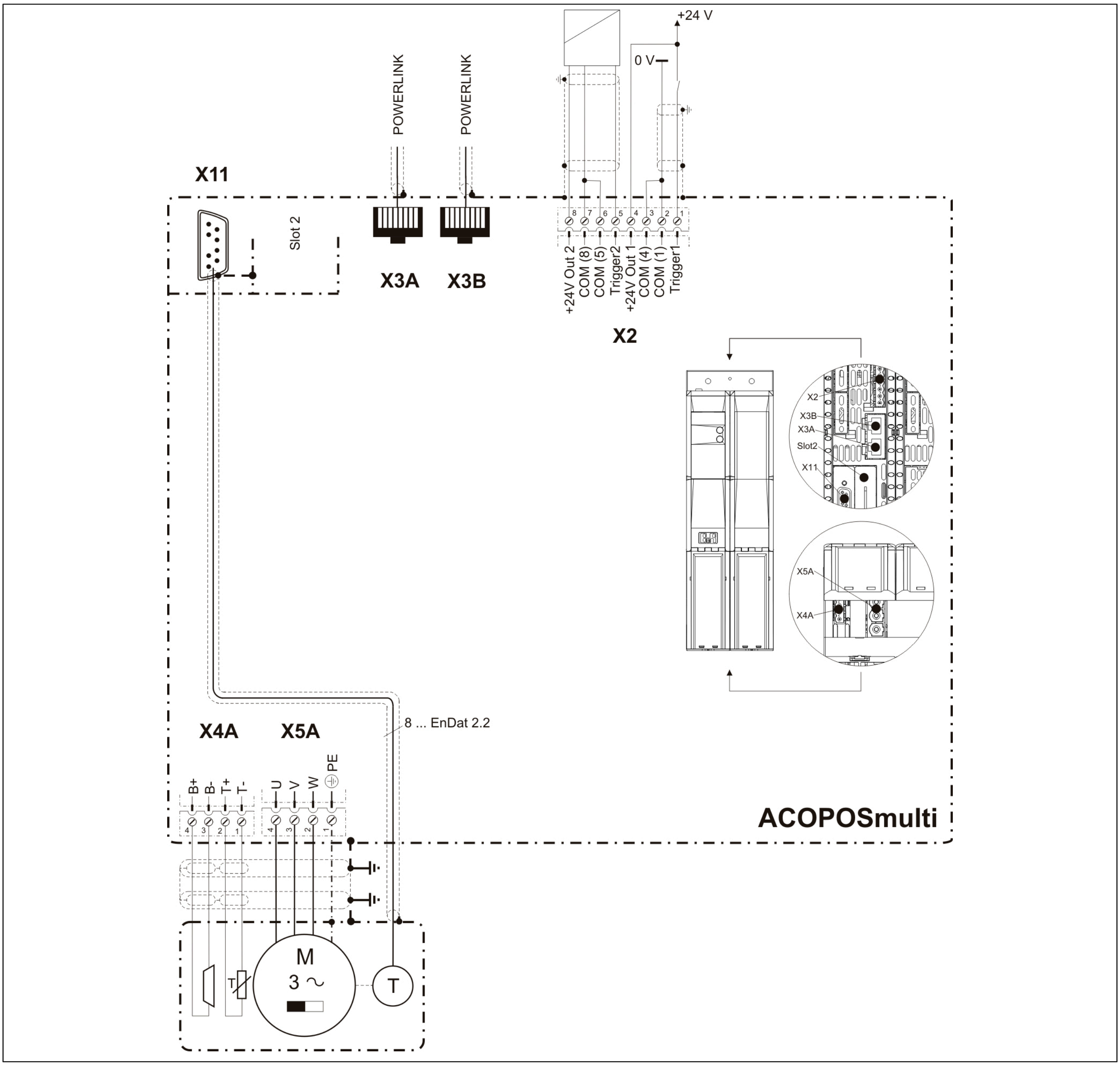


Figure 8: Pinout overview

2.3.3.4.2 ACOPOSmulti SafeMOTION SinCos - Pinout overview

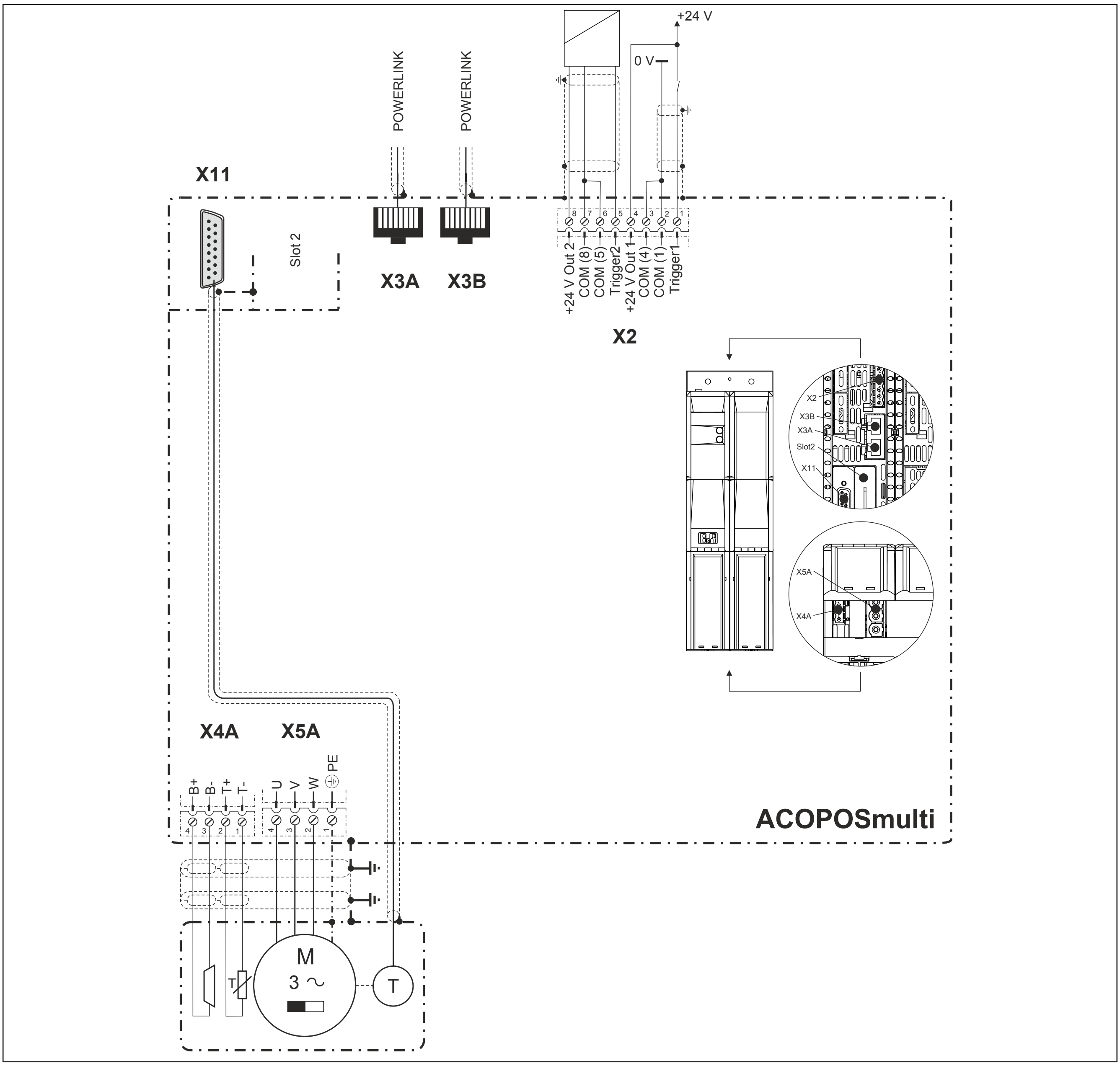


Figure 9: Pinout overview

2.3.3.4.3 Connector X2 - Pinout

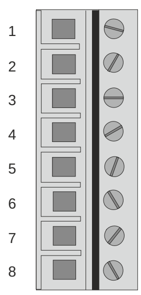
X2	Pin	Description	Function
	1	Trigger 1	Trigger 1
	2	COM (1)	Trigger 1 0 V
	3	COM (2)	+24 V output 1 0 V
	4	+24 V Out 1	+24 V output 1
	5	Trigger 2	Trigger 2
	6	COM (5)	Trigger 2 0 V
	7	COM (8)	+24 V output 2 0 V
	8	+24 V Out 2	+24 V output 2

Table 36: Connector X2 - Pinout

2.3.3.4.4 Connectors X3A, X3B - Pinout

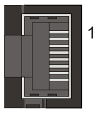
X3A, X3B	Pin	Description	Function
	1	RXD	Receive signal
	2	RXD\	Receive signal inverted
	3	TXD	Transmit signal
	4	Shield	Shield
	5	Shield	Shield
	6	TXD\	Transmit signal inverted
	7	Shield	Shield
	8	Shield	Shield

Table 37: X3A, X3B connectors - Pinout

2.3.3.4.5 X4A connector - Pinout

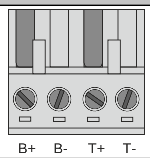
X4A	Description	Function
	T-	Axis 1: Temperature sensor -
	T+	Axis 1: Temperature sensor +
	B-	Axis 1: Brake -
	B+	Axis 1: Brake +

Table 38: Connector X4A - Pinout

Danger!

A short circuit of SBC output B+ against 24 V results in state FUNCTIONAL FAIL SAFE being enabled. This means that safe pulse disabling is enabled. The brake always remains switched on / released, however, due to the short circuit to 24 V!
This can lead to dangerous situations since the motor holding brake cannot brake, prevent the spin-out movement or prevent the unbraked lowering movement when loads are suspended!
A short circuit of SBC output B+ against 24 V must be prevented by suitable wiring measures!

Danger!

The following applies to the SBC output:

- **It is not permitted to be wired across modules!**
- **It is not permitted to be wired as an open emitter!**
- **It is not permitted to be wired as an open collector!**

Danger!

Only an output voltage of ≤ 5 V can be ensured for the safe motor holding brake output when switched off. When selecting the motor holding brake, the user must ensure that the required braking torque is achieved with a voltage of 5 V applied.

Information:

The transistors of the SBC output stage are tested cyclically. When the output channels are active, this test emits low pulses on the output with a maximum length of 600 µs.

This must be taken into consideration when choosing the motor holding brake!

Danger!

The connections for the motor temperature sensors and the motor holding brake are safely isolated circuits. These connections are therefore only permitted to be connected to devices or components that have sufficient isolation per IEC 60364-4-41 or EN 61800-5-1.

Caution!

If B+ and B- are swapped when connecting the permanent magnet holding brakes, then the brakes cannot be opened! ACOPOSmulti inverter modules cannot determine if a holding brake is connected with reverse polarity!

Warning!

Temperature sensors are only permitted to be connected to the X4A/T+ and X4A/T- connectors on an ACOPOSmulti module under the following conditions:

- **SLOT1 of the ACOPOSmulti module does not contain an ACOPOSmulti plug-in module to which a temperature sensor is connected on the T+ and T- connections.**

Otherwise, the temperature monitoring functions on the ACOPOSmulti module may become ineffective, which in extreme cases can cause the hardware (e.g. motors) connected to the ACOPOSmulti module to be destroyed!

2.3.3.4.6 X5A connector - Pinout

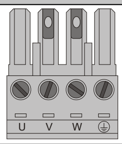
X5A	Description	Function
	⏚	Axis 1: Protective ground conductor
	W	Axis 1: Motor connection W
	V	Axis 1: Motor connection V
	U	Axis 1: Motor connection U

Table 39: Connector X5A - Pinout

Information:

An additional PE wire does not have to be connected to the threaded bolt beside the X5A connector. The PE connection on the male X5A connector is required and sufficient.

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

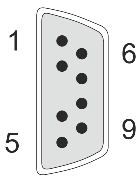
Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

ACOPOSmulti SafeMOTION SinCos

Information:

Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.

2.3.3.4.7 SafeMOTION EnDat 2.2 module - Pinout

Figure	X11 (X12)	Pin	Description	Function
		1	U+	Encoder power supply +12.5 V
		2	---	---
		3	---	---
		4	D	Data input
		5	T	Clock output
		6	COM (1)	Encoder power supply 0 V
		7	---	---
		8	D\	Data input inverted
		9	T\	Clock output inverted

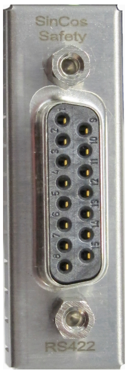
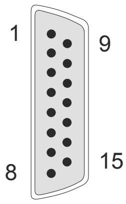
Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

Information:

The SafeMOTION module cannot be replaced! The SafeMOTION module and the ACOPOSmulti SafeMOTION inverter module together form a single unit. In the event of an error, the entire module must be replaced.

2.3.3.4.8 SafeMOTION SinCos module - Pinout

Figure	X11	Pin	Name	Function
		1	A	Channel A/Sin
		2	COM	Ground
		3	B	Channel B/COS
		4	+5 V	Encoder power supply +
		5	D	Data
		6	---	---
		7	R\	Reference pulse inverted/nREF
		8	T	Clock
		9	A\	Channel A inverted/nSIN
		10	Sense COM	Sense ground
		11	B\	Channel B inverted/nCOS
		12	Sense +5V	Sense input +5 V
		13	D\	Data inverted
		14	R	Reference pulse/REF
		15	T\	Clock cycle inverted

Information:

The SafeMOTION module cannot be replaced! The SafeMOTION module and the ACOPOSmulti SafeMOTION inverter module together form a single unit. In the event of an error, the entire module must be replaced.

2.3.4 Safe single-width inverter modules (2-axis modules)

2.3.4.1 8BVI0014HCDS.000-1, 8BVI0014HWDS.000-1

2.3.4.1.1 General information

- Clearly structured, straightforward implementation via network-based safety technology
- Modular expandability through virtual wiring
- Immediate triggering of safety function due to short cycle times
- Easy implementation with transparent control and status information, even in the standard application
- Compact design
- Complete safety functionality, even in 2-axis modules

2.3.4.1.2 Order data

Model number	Short description	Figure
	Cold plate or feed-through mounting	
8BVI0014HCDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 1.9 A, HV, cold plate or feed-through mounting, 2 axes	
	Wall mounting	
8BVI0014HWDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 1.9 A, HV, wall mounting, 2 axes	
	Required accessories	
	Terminal block sets	
8BZVI0055DS.000-1A	Screw clamp set for ACOPOSmulti 8BVI00xxHxDS modules: 1x 8TB2108.2010-00, 1x 8TB2104.203L-00, 1x 8TB2104.203F-00, 1x 8TB3104.204G-11, 1x 8TB3104.204K-11	
	Optional accessories	
	Accessory sets	
8BXB000.0000-00	ACOPOSmulti accessory set for encoder buffering consists of the following: 1 lithium battery AA 3.6 V, 1 cover for battery compartment	
	Fan modules	
8BXF001.0000-00	ACOPOSmulti fan module, replacement fan for ACOPOSmulti modules (8BxP/8B0C/8BVI/8BVE/8B0K)	
	POWERLINK/Ethernet cables	
X20CA0E61.00020	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.2 m	
X20CA0E61.00025	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.25 m	
X20CA0E61.00030	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.3 m	
X20CA0E61.00035	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.35 m	
X20CA0E61.00050	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.5 m	
X20CA0E61.00100	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 1 m	
	Shield component sets	
8SCS000.0000-00	ACOPOSmulti shield component set: 1 shield plate 1x type 0, 1 hose clamp, B 9 mm, D 12-22 mm	
8SCS002.0000-00	ACOPOSmulti shield component set: 1x clamping plate; 2x clamps D 4-13.5 mm; 4x screws	
8SCS009.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK8-14, 1x shield connection clamp SK14	
	Terminal blocks	
8TB2104.203F-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, F keying: 0101	
8TB2104.203L-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, L keying: 1010	
8TB2108.2010-00	8-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	
8TB3104.204G-11	4-pin screw clamp, single row, spacing: 7.62 mm, label 4: PE W V U, G keying: 0110	
8TB3104.204K-11	4-pin screw clamp, single row, spacing: 7.62 mm, label 4: PE W V U, K keying: 1001	

Table 40: 8BVI0014HCDS.000-1, 8BVI0014HWDS.000-1 - Order data

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

For details, see 6.1.2 "Safe power transmission system " on page 283.

2.3.4.1.3 Technical data

Model number	8BVI0014HCDS.000-1	8BVI0014HWDS.000-1
General information		
B&R ID code	0xAA0B	0xAA0D
Cooling and mounting type	Cold plate or feed-through mounting	Wall mounting
Slots for plug-in modules	2 [1)]	
Certifications		
CE	Yes	
Functional safety [2)]	Yes (openSAFETY)	
UL	cULus E225616 Power conversion equipment	
EAC	Yes	
KC	Yes	
DC bus connection		
Voltage		
Nominal	750 VDC	
Continuous power consumption [3)]	2.91 kW	
Power dissipation depending on switching frequency [4)]		
Switching frequency 5 kHz	[1.2 * I_M^2 + 2.62 * I_M + 100] W	
Switching frequency 10 kHz	[2.56 * I_M^2 + 2.8 * I_M + 200] W	
Switching frequency 20 kHz	[6 * I_M^2 - 9.4 * I_M + 430] W	
DC bus capacitance	165 µF	
Variant	ACOPOSmulti backplane	
24 VDC power supply		
Input voltage	25 VDC ±1.6%	
Input capacitance	23.5 µF	
Max. power consumption	28 W + P_{SMC1} + P_{SMC2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake(s)}$ [5)]	28 W + P_{SMC1} + P_{SMC2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake(s)}$ [6)]
Variant	ACOPOSmulti backplane	
24 VDC output		
Quantity	2	
Output voltage		
DC bus voltage (U_{DC}): 260 to 315 VDC	25 VDC * (U_{DC}/315)	
DC bus voltage (U_{DC}): 315 to 800 VDC	24 VDC ±6%	
Fuse protection	250 mA (slow-blow) electronic, automatic reset	
Motor connection [7)]		
Quantity	2	
Continuous power per motor connection [3)]	1.4 kW	
Continuous current per motor connection [3)]	1.9 A_{eff}	
Reduction of continuous current depending on switching frequency [8)]		
Switching frequency 5 kHz	-	No reduction [9)]
Switching frequency 10 kHz	-	No reduction
Switching frequency 20 kHz	-	0.11 A/K (starting at 15 °C) [10)]
Reduction of continuous current depending on switching frequency and mounting type [11)]		
Switching frequency 5 kHz		
Cold plate mounting [12)]	No reduction [9)]	-
Feed-through mounting	No reduction [9)]	-
Switching frequency 10 kHz		
Cold plate mounting [12)]	No reduction	-
Feed-through mounting	No reduction	-
Switching frequency 20 kHz		
Cold plate mounting [12)]	0.13 A/K (from 45°C)	-
Feed-through mounting	0.14 A/K (from 32°C) [10)]	-
Reduction of continuous current depending on installation elevation		
Starting at 500 m above sea level	0.19 A_{eff} per 1000 m	
Peak current per motor connection	4.7 A_{eff}	
Nominal switching frequency	5 kHz	
Possible switching frequencies [13)]	5/10/20 kHz	5 / 10 / 20 kHz
Electrical stress of connected motor per IEC TS 60034-25 [14)]	Limit value curve A	

Table 41: 8BVI0014HCDS.000-1, 8BVI0014HWDS.000-1 - Technical data

Model number	8BVI0014HCDS.000-1	8BVI0014HWDS.000-1
Protective measures		
Overload protection	Yes	
Short circuit and ground fault protection	Yes	
Max. output frequency	598 Hz [15)]	598 Hz [16)]
Variant		
U, V, W, PE	Male connector	
Shield connection	Yes	
Terminal connection cross section		
Flexible and fine-stranded wires		
With wire end sleeves	0.25 to 4 mm²	
Approbation data		
UL/C-UL-US	30 to 10	
CSA	28 to 10	
Terminal cable cross section dimension of shield connection	12 to 22 mm	
Max. motor cable length depending on switching frequency		
Switching frequency 5 kHz	25 m	
Switching frequency 10 kHz	25 m	
Switching frequency 20 kHz	10 m	
Motor holding brake connection		
Quantity	2	
Output voltage [17)]	24 VDC +5.8% / -0% [18)]	
Continuous current	1.1 A	
Max. internal resistance	0.5 Ω	
Extinction potential	Approx. 30 V	
Max. extinction energy per switching operation	1.5 Ws	
Max. switching frequency	0.5 Hz	
Protective measures		
Overload and short-circuit protection	Yes	
Open circuit monitoring	Yes	
Undervoltage monitoring	Yes	
Response threshold for open circuit monitoring	Approx. 0.25 A	
Response threshold for undervoltage monitoring	24 VDC -2% / -4%	
Encoder interfaces [19)]		
Quantity	2	
Type	EnDat 2.2 [20)]	
Connections	9-pin female DSUB connector	
Status indicators	UP/DN LEDs	
Electrical isolation		
Encoder - ACOPOSmulti	No	
Encoder monitoring	Yes	
Max. encoder cable length	100 m Depends on the cross section of the power supply wires in the encoder cable [21)]	100 m Depends on the cross section of the power supply wires of the encoder cable [22)]
Encoder power supply		
Output voltage	Typ. 12.5 V	
Load capacity	350 mA	
Protective measures		
Short-circuit proof	Yes	
Overload-proof	Yes	
Synchronous serial interface		
Signal transmission	RS485	
Data transfer rate	6.25 Mbit/s	
Max. power consumption per encoder interface	P_{SMC}[W] = 19 V * $I_{Encoder}$[A] [23)]	
Trigger inputs		
Quantity	2	
Circuit	Sink	
Electrical isolation		
Input - Inverter module	Yes	
Input - Input	Yes	
Input voltage		
Nominal	24 VDC	
Maximum	30 VDC	
Switching threshold		
Low	<5 V	
High	>15 V	
Input current at nominal voltage	Approx. 10 mA	
Switching delay		
Rising edge	52 µs ±0.5 µs (digitally filtered)	
Falling edge	53 µs ±0.5 µs (digitally filtered)	
Modulation compared to ground potential	Max. ±38 V	

Table 41: 8BVI0014HCDS.000-1, 8BVI0014HWDS.000-1 - Technical data

Model number	8BVI0014HCDS.000-1	8BVI0014HWDS.000-1
Electrical properties		
Discharge capacitance	0.2 µF	
Operating conditions		
Permissible mounting orientations		
Hanging vertically	Yes	
Horizontal, face up	Yes	
Standing horizontally	No	
Installation elevation above sea level		
Nominal	0 to 500 m	
Maximum [24)]	4000 m	
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)	
Overvoltage category per EN 61800-5-1	III	
Degree of protection per EN 60529	IP20	
Ambient conditions		
Temperature		
Operation		
Nominal	5 to 40°C	
Maximum [25)]	55°C	
Storage	-25 to 55°C	
Transport	-25 to 70°C	
Relative humidity		
Operation	5 to 85%	
Storage	5 to 95%	
Transport	Max. 95% at 40°C	
Mechanical properties		
Dimensions [26)]		
Width	53 mm	
Height	317 mm	
Depth		
Wall mounting	-	263 mm
Cold plate	212 mm	-
Feed-through mounting	209 mm	-
Weight	Approx. 2.3 kg	Approx. 2.8 kg
Module width	1	

Table 41: 8BVI0014HCDS.000-1, 8BVI0014HWDS.000-1 - Technical data

1) SLOT 1 and SLOT 2 of the ACOPOSmulti module are occupied by the encoder interfaces.
2) Achievable safety classifications (safety integrity level, safety category, performance level) are documented in the user's manual (section "Safety technology").
3) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
4) $I_M = 0.5 * (I_{X5A} + I_{X5B})$
I_{X5A} ... Current on X5A motor connection [A_{Eff}]
I_{X5B} ... Current on X5B motor connection [A_{Eff}]
5) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SMC2} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT2 (see the "Encoder interfaces" section).
$P_{24\ V\ Out}$ ... Power [W] that is output to the connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
6) P_{SMC1} ... Max. power consumption P_{SMC}[W] of the SafeMOTION module in SLOT1 (see section "Encoder interfaces").
P_{SMC2} ... Max. power consumption P_{SMC}[W] of the SafeMOTION module in SLOT2 (see section "Encoder interfaces").
$P_{24\ V\ Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
7) Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.
8) Valid in the following conditions: 750 VDC DC bus voltage. The temperature specifications refer to the ambient temperature.
9) Value for the nominal switching frequency.
10) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
11) Valid in the following conditions: 750 VDC DC bus voltage, minimum permissible coolant flow volume (3 l/min).
12) The temperature specifications refer to the return temperature of the cold plate mounting plate.
13) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load. When using 2-axis modules, the increased CPU load reduces the functionality of the drive; if this is not taken into consideration, the computing time can be exceeded in extreme cases.
14) If necessary, the stress of the motor isolation system can be reduced by an additional externally wired dv/dt choke. For example, the RWK 305 three-phase du/dt choke from Schaffner (www.schaffner.com) can be used. Important: Even when using a dv/dt choke, it is necessary to ensure that an EMC-compatible, low inductance shield connection is used!
15) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output (Power unit: Limit speed exceeded).
16) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use per Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
17) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified wiring. The operating voltage range of the holding brake can be found in the user's manual for the respective motor.
18) The specified value is only valid under the following conditions:
- The 24 VDC supply for the module is provided by an 8B0C auxiliary supply module installed on the same mounting plate.
If the 24 VDC supply for the module is applied to the mounting plate using an 8BVE expansion module, then the output voltage is reduced because of voltage drops on the expansion cable. In this case, undervoltage monitoring must be disabled.
19) Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.

20) An EnDat 2.2 functional safety encoder is required when using ACOPOSmulti SafeMOTION inverter modules! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!

21) The maximum encoder cable length l_{Max} can be calculated as follows (the maximum permissible encoder cable length of 100 m must not be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A].
A ... Cross section of the power supply wires [mm²].
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178).

22) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 100 m is not permitted to be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A].
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)

23) $I_{Encoder}$ ... Max. power consumption of the connected encoder [A].

24) Continuous operation at elevations ranging from 500 m to 4000 m above sea level is possible (taking the specified continuous current reductions into consideration).

25) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous current reductions into consideration), but this will result in a shorter service life.

26) These dimensions refer to the actual device dimensions including the respective mounting plate. Make sure to leave additional space above and below the devices for mounting, connections and air circulation.

2.3.4.1.4 Wiring

For details, see section 2.3.4.4 "Wiring: Safe single-width inverter modules (2-axis modules)" on page 99.

For general information, see section 2.6 "Wiring" on page 150.

2.3.4.2 8BVI0028HCDS.000-1, 8BVI0028HWDS.000-1

2.3.4.2.1 General information

- Clearly structured, straightforward implementation via network-based safety technology
- Modular expandability through virtual wiring
- Immediate triggering of safety function due to short cycle times
- Easy implementation with transparent control and status information, even in the standard application
- Compact design
- Complete safety functionality, even in 2-axis modules

2.3.4.2.2 Order data

Model number	Short description	Figure
	Cold plate or feed-through mounting	
8BVI0028HCDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 3.8 A, HV, cold plate or feed-through mounting, 2 axes	
	Wall mounting	
8BVI0028HWDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 3.8 A, HV, wall mounting, 2 axes	
	Required accessories	
	Terminal block sets	
8BZVI0055DS.000-1A	Screw clamp set for ACOPOSmulti 8BVI00xxHxDS modules: 1x 8TB2108.2010-00, 1x 8TB2104.203L-00, 1x 8TB2104.203F-00, 1x 8TB3104.204G-11, 1x 8TB3104.204K-11	
	Optional accessories	
	Accessory sets	
8BXB000.0000-00	ACOPOSmulti accessory set for encoder buffering consists of the following: 1 lithium battery AA 3.6 V, 1 cover for battery compartment	
	Fan modules	
8BXF001.0000-00	ACOPOSmulti fan module, replacement fan for ACOPOSmulti modules (8BxP/8B0C/8BVI/8BVE/8B0K)	
	POWERLINK/Ethernet cables	
X20CA0E61.00020	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.2 m	
X20CA0E61.00025	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.25 m	
X20CA0E61.00030	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.3 m	
X20CA0E61.00035	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.35 m	
X20CA0E61.00050	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.5 m	
X20CA0E61.00100	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 1 m	
	Shield component sets	

Table 42: 8BVI0028HCDS.000-1, 8BVI0028HWDS.000-1 - Order data

Model number	Short description	Figure
8SCS000.0000-00	ACOPOSmulti shield component set: 1 shield plate 1x type 0, 1 hose clamp, B 9 mm, D 12-22 mm	
8SCS002.0000-00	ACOPOSmulti shield component set: 1x clamping plate; 2x clamps D 4-13.5 mm; 4x screws	
8SCS009.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK8-14, 1x shield connection clamp SK14	
	Terminal blocks	
8TB2104.203F-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, F keying: 0101	
8TB2104.203L-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, L keying: 1010	
8TB2108.2010-00	8-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	
8TB3104.204G-11	4-pin screw clamp, single row, spacing: 7.62 mm, label 4: PE W V U, G keying: 0110	
8TB3104.204K-11	4-pin screw clamp, single row, spacing: 7.62 mm, label 4: PE W V U, K keying: 1001	

Table 42: 8BVI0028HCDS.000-1, 8BVI0028HWDS.000-1 - Order data

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

For details, see 6.1.2 "Safe power transmission system " on page 283.

2.3.4.2.3 Technical data

Model number	8BVI0028HCDS.000-1	8BVI0028HWDS.000-1
General information		
B&R ID code	0xAA0F	0xAA11
Cooling and mounting type	Cold plate or feed-through mounting	Wall mounting
Slots for plug-in modules	2 1)	
Certifications		
CE	Yes	
Functional safety 2)	Yes (openSAFETY)	
UL	cULus E225616 Power conversion equipment	
EAC	Yes	
KC	Yes	
DC bus connection		
Voltage		
Nominal	750 VDC	
Continuous power consumption 3)	5.73 kW	
Power dissipation depending on switching frequency 4)		
Switching frequency 5 kHz	$[1.2 * I_M^2 + 2.62 * I_M + 100]$ W	
Switching frequency 10 kHz	$[2.56 * I_M^2 + 2.8 * I_M + 200]$ W	
Switching frequency 20 kHz	$[6 * I_M^2 - 9.4 * I_M + 430]$ W	
DC bus capacitance	165 µF	
Variant	ACOPOSmulti backplane	
24 VDC power supply		
Input voltage	25 VDC ±1.6%	
Input capacitance	23.5 µF	
Max. power consumption	28 W + $P_{SMC1} + P_{SMC2} + P_{24\,V\,Out} + P_{HoldingBrake(s)}$ 5)	28 W + $P_{SMC1} + P_{SMC2} + P_{24\,V\,Out} + P_{HoldingBrake(s)}$ 6)
Variant	ACOPOSmulti backplane	
24 VDC output		
Quantity	2	
Output voltage		
DC bus voltage (U_{DC}): 260 to 315 VDC	25 VDC * (U_{DC}/315)	
DC bus voltage (U_{DC}): 315 to 800 VDC	24 VDC ±6%	
Fuse protection	250 mA (slow-blow) electronic, automatic reset	
Motor connection 7)		
Quantity	2	

Table 43: 8BVI0028HCDS.000-1, 8BVI0028HWDS.000-1 - Technical data

Model number	8BVI0028HCDS.000-1	8BVI0028HWDS.000-1
Continuous power per motor connection [3]	2.8 kW	
Continuous current per motor connection [3]	3.8 A_{eff}	
Reduction of continuous current depending on switching frequency [8]		
Switching frequency 5 kHz	-	No reduction [9]
Switching frequency 10 kHz	-	No reduction
Switching frequency 20 kHz	-	0.12 A/K (starting at 13 °C) [10]
Reduction of continuous current depending on switching frequency and mounting type [11]		
Switching frequency 5 kHz		
Cold plate mounting [12]	No reduction [9]	-
Feed-through mounting	No reduction [9]	-
Switching frequency 10 kHz		
Cold plate mounting [12]	0.6 A/K (starting at 57°C)	-
Feed-through mounting	No reduction	-
Switching frequency 20 kHz		
Cold plate mounting [12]	0.12 A/K (starting at 34°C) [13]	-
Feed-through mounting	0.09 A/K (starting at 6°C) [10]	-
Reduction of continuous current depending on installation elevation		
Starting at 500 m above sea level	0.38 A_{eff} per 1000 m	
Peak current per motor connection	9.5 A_{eff}	
Nominal switching frequency	5 kHz	
Possible switching frequencies [14]	5 / 10 / 20 kHz	
Electrical stress of connected motor per IEC TS 60034-25 [15]	Limit value curve A	
Protective measures		
Overload protection	Yes	
Short circuit and ground fault protection	Yes	
Max. output frequency	598 Hz [16]	598 Hz [17]
Variant		
U, V, W, PE	Male connector	
Shield connection	Yes	
Terminal connection cross section		
Flexible and fine-stranded wires		
With wire end sleeves	0.25 to 4 mm²	
Approbation data		
UL/C-UL-US	30 to 10	
CSA	28 to 10	
Terminal cable cross section dimension of shield connection	12 to 22 mm	
Max. motor cable length depending on switching frequency		
Switching frequency 5 kHz	25 m	
Switching frequency 10 kHz	25 m	
Switching frequency 20 kHz	10 m	
Motor holding brake connection		
Quantity	2	
Output voltage [18]	24 VDC +5.8% / -0% [19]	
Continuous current	1.1 A	
Max. internal resistance	0.5 Ω	
Extinction potential	Approx. 30 V	
Max. extinction energy per switching operation	1.5 Ws	
Max. switching frequency	0.5 Hz	
Protective measures		
Overload and short-circuit protection	Yes	
Open circuit monitoring	Yes	
Undervoltage monitoring	Yes	
Response threshold for open circuit monitoring	Approx. 0.25 A	
Response threshold for undervoltage monitoring	24 VDC -2% / -4%	
Encoder interfaces [20]		
Quantity	2	
Type	EnDat 2.2 [21]	
Connections	9-pin female DSUB connector	
Status indicators	UP/DN LEDs	
Electrical isolation		
Encoder - ACOPOSmulti	No	
Encoder monitoring	Yes	
Max. encoder cable length	100 m Depends on the cross section of the power supply wires of the encoder cable [22]	

Table 43: 8BVI0028HCDS.000-1, 8BVI0028HWDS.000-1 - Technical data

Model number	8BVI0028HCDS.000-1	8BVI0028HWDS.000-1
Encoder power supply		
Output voltage	Typ. 12.5 V	
Load capacity	350 mA	
Protective measures		
Short-circuit proof	Yes	
Overload-proof	Yes	
Synchronous serial interface		
Signal transmission	RS485	
Data transfer rate	6.25 Mbit/s	
Max. power consumption per encoder interface	$P_{SMC}[W] = 19\ V * I_{Encoder}[A]$ [23]	
Trigger inputs		
Quantity	2	
Circuit	Sink	
Electrical isolation		
Input - Inverter module	Yes	
Input - Input	Yes	
Input voltage		
Nominal	24 VDC	
Maximum	30 VDC	
Switching threshold		
Low	<5 V	
High	>15 V	
Input current at nominal voltage	Approx. 10 mA	
Switching delay		
Rising edge	52 µs ±0.5 µs (digitally filtered)	
Falling edge	53 µs ±0.5 µs (digitally filtered)	
Modulation compared to ground potential	Max. ±38 V	
Electrical properties		
Discharge capacitance	0.14 µF	0.2 µF
Operating conditions		
Permissible mounting orientations		
Hanging vertically	Yes	
Horizontal, face up	Yes	
Standing horizontally	No	
Installation elevation above sea level		
Nominal	0 to 500 m	
Maximum [24]	4000 m	
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)	
Overvoltage category per EN 61800-5-1	III	
Degree of protection per EN 60529	IP20	
Ambient conditions		
Temperature		
Operation		
Nominal	5 to 40°C	
Maximum [25]	55°C	
Storage	-25 to 55°C	
Transport	-25 to 70°C	
Relative humidity		
Operation	5 to 85%	
Storage	5 to 95%	
Transport	Max. 95% at 40°C	
Mechanical properties		
Dimensions [26]		
Width	53 mm	
Height	317 mm	
Depth		
Wall mounting	-	263 mm
Cold plate	212 mm	-
Feed-through mounting	209 mm	-
Weight	Approx. 2.3 kg	Approx. 2.8 kg
Module width	1	

Table 43: 8BVI0028HCDS.000-1, 8BVI0028HWDS.000-1 - Technical data

1) SLOT 1 and SLOT 2 of the ACOPOSmulti module are occupied by the encoder interfaces.
2) Achievable safety classifications (safety integrity level, safety category, performance level) are documented in the user's manual (section "Safety technology").
3) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
4) $I_M = 0.5 * (I_{X5A} + I_{X5B})$
I_{X5A} ... Current on motor connection X5A [A_{eff}]
I_{X5B} ... Current on motor connection X5B [A_{eff}]
5) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SMC2} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT2 (see the "Encoder interfaces" section).
$P_{24\ V\ Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).

6) P_{SMC1} ... Max. power consumption P_{SMC}[W] of the SafeMOTION module in SLOT1 (see section "Encoder interfaces").
P_{SMC2} ... Max. power consumption P_{SMC}[W] of the SafeMOTION module in SLOT2 (see section "Encoder interfaces").
$P_{24\ V\ Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
7) Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.
8) Valid in the following conditions: 750 VDC DC bus voltage. The temperature specifications refer to the ambient temperature.
9) Value for the nominal switching frequency.
10) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
11) Valid for the following conditions: 750 VDC DC bus voltage, minimum permissible coolant flow volume (3 l/min).
12) The temperature specifications refer to the return temperature of the cold plate mounting plate.
13) The module cannot supply the full continuous current at this switching frequency. This unusual value for the return temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
Caution! Condensation can occur at low flow temperatures and return temperatures.
14) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load. When using 2-axis modules, the increased CPU load reduces the functionality of the drive; if this is not taken into consideration, the computing time can be exceeded in extreme cases.
15) If necessary, the stress of the motor isolation system can be reduced by an additional externally wired dv/dt choke. For example, the RWK 305 three-phase du/dt choke from Schaffner (www.schaffner.com) can be used. Important: Even when using a dv/dt choke, it is necessary to ensure that an EMC-compatible, low inductance shield connection is used!
16) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
17) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use per Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
18) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
19) The specified value is only valid under the following conditions:
- The 24 VDC supply for the module is provided by an 8B0C auxiliary supply module installed on the same mounting plate.
If the 24 VDC supply for the module is applied to the mounting plate using an 8BVE expansion module, then the output voltage is reduced because of voltage drops on the expansion cable. In this case, undervoltage monitoring must be disabled.
20) Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.
21) An EnDat 2.2 functional safety encoder is required when using ACOPOSmulti SafeMOTION inverter modules! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!
22) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 100 m is not permitted to be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A]
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
23) $I_{Encoder}$ ... Max. power consumption of the connected encoder [A].
24) Continuous operation at elevations ranging from 500 m to 4,000 m above sea level is possible (taking the specified continuous current reductions into consideration).
25) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous current reductions into consideration), but this will result in a shorter service life.
26) These dimensions refer to the actual device dimensions including the respective mounting plate. Make sure to leave additional space above and below the devices for mounting, connections and air circulation.

2.3.4.2.4 Wiring

For details, see section 2.3.4.4 "Wiring: Safe single-width inverter modules (2-axis modules)" on page 99.

For general information, see section 2.6 "Wiring" on page 150.

2.3.4.3 8BVI0055HCDS.000-1, 8BVI0055HWDS.000-1

2.3.4.3.1 General information

- Clearly structured, straightforward implementation via network-based safety technology
- Modular expandability through virtual wiring
- Immediate triggering of safety function due to short cycle times
- Easy implementation with transparent control and status information, even in the standard application
- Compact design
- Complete safety functionality, even in 2-axis modules

2.3.4.3.2 Order data

Model number	Short description	Figure
	Cold plate or feed-through mounting	
8BVI0055HCDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 7.6 A, HV, cold plate or feed-through mounting, 2 axes	
	Wall mounting	
8BVI0055HWDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 7.6 A, HV, wall mounting, 2 axes	
	Required accessories	
	Terminal block sets	
8BZVI0055DS.000-1A	Screw clamp set for ACOPOSmulti 8BVI00xxHxDS modules: 1x 8TB2108.2010-00, 1x 8TB2104.203L-00, 1x 8TB2104.203F-00, 1x 8TB3104.204G-11, 1x 8TB3104.204K-11	
	Optional accessories	
	Accessory sets	
8BXB000.0000-00	ACOPOSmulti accessory set for encoder buffering consists of the following: 1 lithium battery AA 3.6 V, 1 cover for battery compartment	
	Fan modules	
8BXF001.0000-00	ACOPOSmulti fan module, replacement fan for ACOPOSmulti modules (8BxP/8B0C/8BVI/8BVE/8B0K)	
	POWERLINK/Ethernet cables	
X20CA0E61.00020	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.2 m	
X20CA0E61.00025	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.25 m	
X20CA0E61.00030	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.3 m	
X20CA0E61.00035	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.35 m	
X20CA0E61.00050	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.5 m	
X20CA0E61.00100	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 1 m	
	Shield component sets	
8SCS000.0000-00	ACOPOSmulti shield component set: 1 shield plate 1x type 0, 1 hose clamp, B 9 mm, D 12-22 mm	
8SCS002.0000-00	ACOPOSmulti shield component set: 1x clamping plate; 2x clamps D 4-13.5 mm; 4x screws	
8SCS009.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK8-14, 1x shield connection clamp SK14	
	Terminal blocks	
8TB2104.203F-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, F keying: 0101	
8TB2104.203L-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, L keying: 1010	
8TB2108.2010-00	8-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	
8TB3104.204G-11	4-pin screw clamp, single row, spacing: 7.62 mm, label 4: PE W V U, G keying: 0110	
8TB3104.204K-11	4-pin screw clamp, single row, spacing: 7.62 mm, label 4: PE W V U, K keying: 1001	

Table 44: 8BVI0055HCDS.000-1, 8BVI0055HWDS.000-1 - Order data

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

For details, see 6.1.2 "Safe power transmission system " on page 283.

2.3.4.3.3 Technical data

Model number	8BVI0055HCDS.000-1	8BVI0055HWDS.000-1
General information		
B&R ID code	0xAA13	0xAA15
Cooling and mounting type	Cold plate or feed-through mounting	Wall mounting
Slots for plug-in modules	2 [1)]	

Table 45: 8BVI0055HCDS.000-1, 8BVI0055HWDS.000-1 - Technical data

Model number	8BVI0055HCDS.000-1	8BVI0055HWDS.000-1
Certifications		
CE	Yes	
Functional safety[2]	Yes (openSAFETY)	
UL	cULus E225616 Power conversion equipment	
EAC	Yes	
KC	Yes	
DC bus connection		
Voltage		
Nominal	750 VDC	
Continuous power consumption [3]	11.19 kW	
Power dissipation depending on switching frequency [4]		
Switching frequency 5 kHz	$[1.2 * I_M^2 + 2.62 * I_M + 100]$ W	
Switching frequency 10 kHz	$[2.56 * I_M^2 + 2.8 * I_M + 200]$ W	
Switching frequency 20 kHz	$[6 * I_M^2 - 9.4 * I_M + 430]$ W	
DC bus capacitance	330 µF	
Variant	ACOPOSmulti backplane	
24 VDC power supply		
Input voltage	25 VDC ±1.6%	
Input capacitance	23.5 µF	
Max. power consumption	28 W + P_{SMC1} + P_{SMC2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake(s)}$[5]	28 W + P_{SMC1} + P_{SMC2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake(s)}$[6]
Variant	ACOPOSmulti backplane	
24 VDC output		
Quantity	2	
Output voltage		
DC bus voltage (U_{DC}): 260 to 315 VDC	25 VDC * (U_{DC}/315)	
DC bus voltage (U_{DC}): 315 to 800 VDC	24 VDC ±6%	
Fuse protection	250 mA (slow-blow) electronic, automatic reset	
Motor connection [7]		
Quantity	2	
Continuous power per motor connection [3]	5.5 kW	
Continuous current per motor connection [3]	7.6 A_{eff}	
Reduction of continuous current depending on switching frequency [8]		
Switching frequency 5 kHz	-	No reduction [9]
Switching frequency 10 kHz	-	0.22 A/K (starting at 43 °C)
Switching frequency 20 kHz	-	0.15 A/K (starting at -14 °C) [10]
Reduction of continuous current depending on switching frequency and mounting type [11]		
Switching frequency 5 kHz		
Cold plate mounting [12]	0.72 A/K (from 56°C) [9]	-
Feed-through mounting	No reduction [9]	-
Switching frequency 10 kHz		
Cold plate mounting [12]	0.28 A/K (from 43°C)	-
Feed-through mounting	0.17 A/K (from 23°C) [10]	-
Switching frequency 20 kHz		
Cold plate mounting [12]	0.13 A/K (from 3°C) [13]	-
Feed-through mounting	0.12 A/K (from -21°C) [10]	-
Reduction of continuous current depending on installation elevation		
Starting at 500 m above sea level	0.76 A_{eff} per 1000 m	
Peak current per motor connection	18.9 A_{eff}	
Nominal switching frequency	5 kHz	
Possible switching frequencies [14]	5/10/20 kHz	5 / 10 / 20 kHz
Electrical stress of connected motor per IEC TS 60034-25 [15]	Limit value curve A	
Protective measures		
Overload protection	Yes	
Short circuit and ground fault protection	Yes	
Max. output frequency	598 Hz [16]	598 Hz [17]
Variant		
U, V, W, PE	Male connector	
Shield connection	Yes	
Terminal connection cross section		
Flexible and fine-stranded wires		
With wire end sleeves	0.25 to 4 mm²	
Approbation data		
UL/C-UL-US	30 to 10	
CSA	28 to 10	
Terminal cable cross section dimension of shield connection	12 to 22 mm	

Table 45: 8BVI0055HCDS.000-1, 8BVI0055HWDS.000-1 - Technical data

Model number	8BVI0055HCDS.000-1	8BVI0055HWDS.000-1
Max. motor cable length depending on switching frequency		
Switching frequency 5 kHz	25 m	
Switching frequency 10 kHz	25 m	
Switching frequency 20 kHz	10 m	
Motor holding brake connection		
Quantity	2	
Output voltage [18]	24 VDC +5.8% / -0% [19]	
Continuous current	1.1 A	
Max. internal resistance	0.5 Ω	
Extinction potential	Approx. 30 V	
Max. extinction energy per switching operation	1.5 Ws	
Max. switching frequency	0.5 Hz	
Protective measures		
Overload and short-circuit protection	Yes	
Open circuit monitoring	Yes	
Undervoltage monitoring	Yes	
Response threshold for open circuit monitoring	Approx. 0.25 A	
Response threshold for undervoltage monitoring	24 VDC -2% / -4%	
Encoder interfaces [20]		
Quantity	2	
Type	EnDat 2.2 [21]	
Connections	9-pin female DSUB connector	
Status indicators	UP/DN LEDs	
Electrical isolation		
Encoder - ACOPOSmulti	No	
Encoder monitoring	Yes	
Max. encoder cable length	100 m Depends on the cross section of the power supply wires in the encoder cable [22]	100 m Depends on the cross section of the power supply wires of the encoder cable [23]
Encoder power supply		
Output voltage	Typ. 12.5 V	
Load capacity	350 mA	
Protective measures		
Short-circuit proof	Yes	
Overload-proof	Yes	
Synchronous serial interface		
Signal transmission	RS485	
Data transfer rate	6.25 Mbit/s	
Max. power consumption per encoder interface	P_{SMC}[W] = 19 V * $I_{Encoder}$[A] [24]	
Trigger inputs		
Quantity	2	
Circuit	Sink	
Electrical isolation		
Input - Inverter module	Yes	
Input - Input	Yes	
Input voltage		
Nominal	24 VDC	
Maximum	30 VDC	
Switching threshold		
Low	<5 V	
High	>15 V	
Input current at nominal voltage	Approx. 10 mA	
Switching delay		
Rising edge	52 µs ±0.5 µs (digitally filtered)	
Falling edge	53 µs ±0.5 µs (digitally filtered)	
Modulation compared to ground potential	Max. ±38 V	
Electrical properties		
Discharge capacitance	0.2 µF	
Operating conditions		
Permissible mounting orientations		
Hanging vertically	Yes	
Horizontal, face up	Yes	
Standing horizontally	No	
Installation elevation above sea level		
Nominal	0 to 500 m	
Maximum [25]	4000 m	
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)	
Overvoltage category per EN 61800-5-1	III	
Degree of protection per EN 60529	IP20	

Table 45: 8BVI0055HCDS.000-1, 8BVI0055HWDS.000-1 - Technical data

Model number	8BVI0055HCDS.000-1	8BVI0055HWDS.000-1
Ambient conditions		
Temperature		
Operation		
Nominal	5 to 40°C	
Maximum 26)	55°C	
Storage	-25 to 55°C	
Transport	-25 to 70°C	
Relative humidity		
Operation	5 to 85%	
Storage	5 to 95%	
Transport	Max. 95% at 40°C	
Mechanical properties		
Dimensions 27)		
Width	53 mm	
Height	317 mm	
Depth		
Wall mounting	-	263 mm
Cold plate	212 mm	-
Feed-through mounting	209 mm	-
Weight	Approx. 2.3 kg	Approx. 2.9 kg
Module width	1	

Table 45: 8BVI0055HCDS.000-1, 8BVI0055HWDS.000-1 - Technical data

1) SLOT 1 and SLOT 2 of the ACOPOSmulti module are occupied by the encoder interfaces.
2) Achievable safety classifications (safety integrity level, safety category, performance level) are documented in the user's manual (section "Safety technology").
3) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
4) $I_M = 0.5 * (I_{X5A} + I_{X5B})$
I_{X5A} ... Current on X5A motor connection [A_{Eff}]
I_{X5B} ... Current on X5B motor connection [A_{Eff}]
5) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SMC2} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT2 (see the "Encoder interfaces" section).
$P_{24\ V\ Out}$ ... Power [W] that is output to the connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
6) P_{SMC1} ... Max. power consumption P_{SMC}[W] of the SafeMOTION module in SLOT1 (see section "Encoder interfaces").
P_{SMC2} ... Max. power consumption P_{SMC}[W] of the SafeMOTION module in SLOT2 (see section "Encoder interfaces").
$P_{24\ V\ Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
7) Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.
8) Valid in the following conditions: 750 VDC DC bus voltage. The temperature specifications refer to the ambient temperature.
9) Value for the nominal switching frequency.
10) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
11) Valid in the following conditions: 750 VDC DC bus voltage, minimum permissible coolant flow volume (3 l/min).
12) The temperature specifications refer to the return temperature of the cold plate mounting plate.
13) The module cannot supply the full continuous current at this switching frequency. This unusual value for the return temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
Caution! Condensation can occur at low flow temperatures and return temperatures.
14) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load. When using 2-axis modules, the increased CPU load reduces the functionality of the drive; if this is not taken into consideration, the computing time can be exceeded in extreme cases.
15) If necessary, the stress of the motor isolation system can be reduced by an additional externally wired dv/dt choke. For example, the RWK 305 three-phase du/dt choke from Schaffner (www.schaffner.com) can be used. Important: Even when using a dv/dt choke, it is necessary to ensure that an EMC-compatible, low inductance shield connection is used!
16) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output (Power unit: Limit speed exceeded).
17) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use per Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
18) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified wiring. The operating voltage range of the holding brake can be found in the user's manual for the respective motor.
19) The specified value is only valid under the following conditions:
- The 24 VDC supply for the module is provided by an 8B0C auxiliary supply module installed on the same mounting plate.
If the 24 VDC supply for the module is applied to the mounting plate using an 8BVE expansion module, then the output voltage is reduced because of voltage drops on the expansion cable. In this case, undervoltage monitoring must be disabled.
20) Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.
21) An EnDat 2.2 functional safety encoder is required when using ACOPOSmulti SafeMOTION inverter modules! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!
22) The maximum encoder cable length l_{Max} can be calculated as follows (the maximum permissible encoder cable length of 100 m must not be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A].
A ... Cross section of the power supply wires [mm²].
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178).

23) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 100 m is not permitted to be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A].
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)

24) $I_{Encoder}$ ... Max. power consumption of the connected encoder [A].

25) Continuous operation at elevations ranging from 500 m to 4000 m above sea level is possible (taking the specified continuous current reductions into consideration).

26) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous current reductions into consideration), but this will result in a shorter service life.

27) These dimensions refer to the actual device dimensions including the respective mounting plate. Make sure to leave additional space above and below the devices for mounting, connections and air circulation.

2.3.4.3.4 Wiring

For details, see section 2.3.4.4 "Wiring: Safe single-width inverter modules (2-axis modules)" on page 99.

For general information, see section 2.6 "Wiring" on page 150.

2.3.4.4 Wiring: Safe single-width inverter modules (2-axis modules)

2.3.4.4.1 Pinout overview

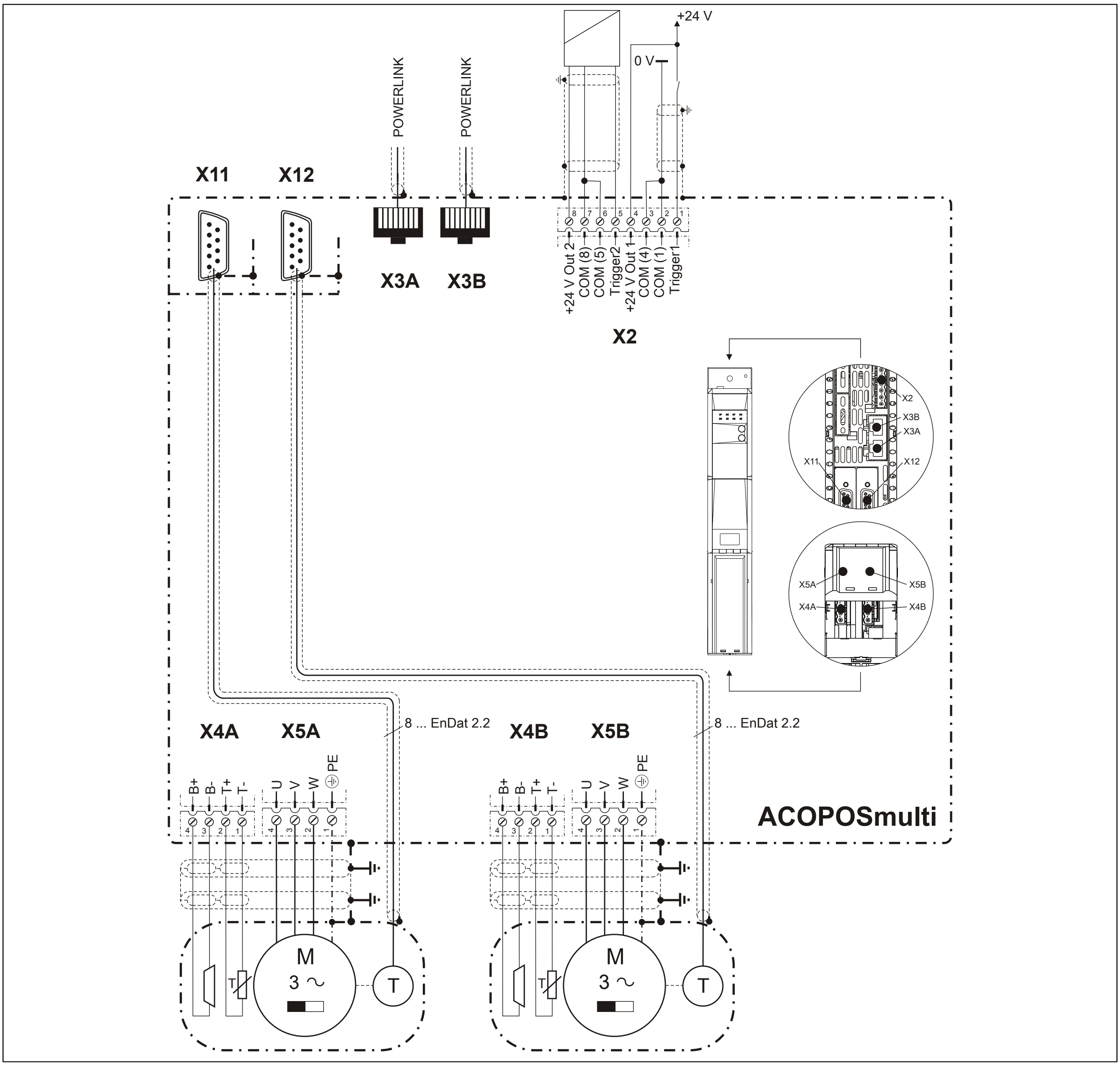


Figure 10: Pinout overview

2.3.4.4.2 Connector X2 - Pinout

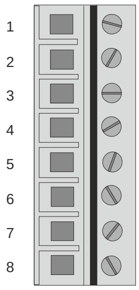
X2	Pin	Description	Function
	1	Trigger 1	Trigger 1
	2	COM (1)	Trigger 1 0 V
	3	COM (2)	+24 V output 1 0 V
	4	+24 V Out 1	+24 V output 1
	5	Trigger 2	Trigger 2
	6	COM (5)	Trigger 2 0 V
	7	COM (8)	+24 V output 2 0 V
	8	+24 V Out 2	+24 V output 2

Table 46: Connector X2 - Pinout

2.3.4.4.3 Connectors X3A, X3B - Pinout

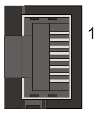
X3A, X3B	Pin	Description	Function
	1	RXD	Receive signal
	2	RXD\	Receive signal inverted
	3	TXD	Transmit signal
	4	Shield	Shield
	5	Shield	Shield
	6	TXD\	Transmit signal inverted
	7	Shield	Shield
	8	Shield	Shield

Table 47: X3A, X3B connectors - Pinout

2.3.4.4.4 Connector X4A - Pinout

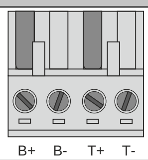
X4A	Description	Function
	T-	Axis 1: Temperature sensor -
	T+	Axis 1: Temperature sensor +
	B-	Axis 1: Brake -
	B+	Axis 1: Brake +

Table 48: Connector X4A - Pinout

Danger!

A short circuit of SBC output B+ against 24 V results in state FUNCTIONAL FAIL SAFE being enabled. This means that safe pulse disabling is enabled. The brake always remains switched on / released, however, due to the short circuit to 24 V!
This can lead to dangerous situations since the motor holding brake cannot brake, prevent the spin-out movement or prevent the unbraked lowering movement when loads are suspended!
A short circuit of SBC output B+ against 24 V must be prevented by suitable wiring measures!

For a 2-axis module, it is therefore especially important to prevent a cross fault between the two B+ connections of the two axes!

Danger!

The following applies to the SBC output:

- **It is not permitted to be wired across modules!**
- **It is not permitted to be wired as an open emitter!**
- **It is not permitted to be wired as an open collector!**

Danger!

Only an output voltage of ≤ 5 V can be ensured for the safe motor holding brake output when switched off. When selecting the motor holding brake, the user must ensure that the required braking torque is achieved with a voltage of 5 V applied.

Information:

The transistors of the SBC output stage are tested cyclically. When the output channels are active, this test emits low pulses on the output with a maximum length of 600 µs.

This must be taken into consideration when choosing the motor holding brake!

Danger!

The connections for the motor temperature sensors and the motor holding brake are safely isolated circuits. These connections are therefore only permitted to be connected to devices or components that have sufficient isolation per IEC 60364-4-41 or EN 61800-5-1.

Caution!

If B+ and B- are swapped when connecting the permanent magnet holding brakes, then the brakes cannot be opened! ACOPOSmulti inverter modules cannot determine if a holding brake is connected with reverse polarity!

Warning!

Temperature sensors are only permitted to be connected to the X4A/T+ and X4A/T- connectors on an ACOPOSmulti module under the following conditions:

- **SLOT1 of the ACOPOSmulti module does not contain an ACOPOSmulti plug-in module to which a temperature sensor is connected on the T+ and T- connections.**

Otherwise, the temperature monitoring functions on the ACOPOSmulti module may become ineffective, which in extreme cases can cause the hardware (e.g. motors) connected to the ACOPOSmulti module to be destroyed!

2.3.4.4.5 Connector X4B - Pinout

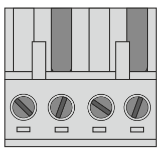
X4B	Description	Function
	T-	Axis 2: Temperature sensor -
	T+	Axis 2: Temperature sensor +
	B-	Axis 2: Brake -
	B+	Axis 2: Brake +

Table 49: Connector X4B - Pinout

Danger!

A short circuit of SBC output B+ against 24 V results in state FUNCTIONAL FAIL SAFE being enabled. This means that safe pulse disabling is enabled. The brake always remains switched on / released, however, due to the short circuit to 24 V!
This can lead to dangerous situations since the motor holding brake cannot brake, prevent the spin-out movement or prevent the unbraked lowering movement when loads are suspended!
A short circuit of SBC output B+ against 24 V must be prevented by suitable wiring measures!

For a 2-axis module, it is therefore especially important to prevent a cross fault between the two B+ connections of the two axes!

Danger!

The following applies to the SBC output:

- **It is not permitted to be wired across modules!**
- **It is not permitted to be wired as an open emitter!**
- **It is not permitted to be wired as an open collector!**

Danger!

Only an output voltage of ≤ 5 V can be ensured for the safe motor holding brake output when switched off. When selecting the motor holding brake, the user must ensure that the required braking torque is achieved with a voltage of 5 V applied.

Information:

The transistors of the SBC output stage are tested cyclically. When the output channels are active, this test emits low pulses on the output with a maximum length of 600 µs.

This must be taken into consideration when choosing the motor holding brake!

Danger!

The connections for the motor temperature sensors and the motor holding brake are safely isolated circuits. These connections are therefore only permitted to be connected to devices or components that have sufficient isolation per IEC 60364-4-41 or EN 61800-5-1.

Caution!

If B+ and B- are swapped when connecting the permanent magnet holding brakes, then the brakes cannot be opened! ACOPOSmulti inverter modules cannot determine if a holding brake is connected with reverse polarity!

Warning!

Temperature sensors are only permitted to be connected to the X4B/T+ and X4B/T- connectors on an ACOPOSmulti module under the following conditions:

- **SLOT2 of the ACOPOSmulti module does not contain an ACOPOSmulti plug-in module to which a temperature sensor is connected on the T+ and T- connections.**

Otherwise, the temperature monitoring functions on the ACOPOSmulti module may become ineffective, which in extreme cases can cause the hardware (e.g. motors) connected to the ACOPOSmulti module to be destroyed!

2.3.4.4.6 Connector X5A - Pinout

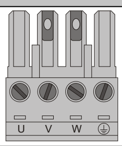
X5A	Description	Function
	⏚	Axis 1: Protective ground conductor
	W	Axis 1: Motor connection W
	V	Axis 1: Motor connection V
	U	Axis 1: Motor connection U

Table 50: Connector X5A - Pinout

Information:

An additional PE wire does not have to be connected to the threaded bolt beside the X5A connector. The PE connection on the male X5A connector is required and sufficient.

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

2.3.4.4.7 Connector X5B - Pinout

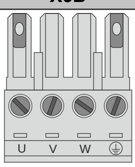
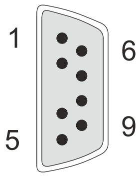
X5B	Description	Function
	⏚	Axis 2: Protective ground conductor
	W	Axis 2: Motor connection W
	V	Axis 2: Motor connection V
	U	Axis 2: Motor connection U

Table 51: Connector X5B - Pinout

Information:

Only B&R 8BCM motor cables are permitted to be used for wiring the motor connections!

2.3.4.4.8 SafeMOTION EnDat 2.2 module - Pinout

Figure	X11 (X12)	Pin	Description	Function
		1	U+	Encoder power supply +12.5 V
		2	---	---
		3	---	---
		4	D	Data input
		5	T	Clock output
		6	COM (1)	Encoder power supply 0 V
		7	---	---
		8	D\	Data input inverted
		9	T\	Clock output inverted

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

Information:

The SafeMOTION module cannot be replaced! The SafeMOTION module and the ACOPOSmulti SafeMOTION inverter module together form a single unit. In the event of an error, the entire module must be replaced.

2.3.5 Safe double-width inverter modules (2-axis modules)

2.3.5.1 8BVI0110HCDS.000-1, 8BVI0110HWDS.000-1

2.3.5.1.1 General information

- Clearly structured, straightforward implementation via network-based safety technology
- Modular expandability through virtual wiring
- Immediate triggering of safety function due to short cycle times
- Easy implementation with transparent control and status information, even in the standard application
- Compact design
- Complete safety functionality, even in 2-axis modules

2.3.5.1.2 Order data

Model number	Short description	Figure
	Cold plate or feed-through mounting	
8BVI0110HCDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 15.1 A, HV, cold plate or feed-through mounting, 2 axes	
	Wall mounting	
8BVI0110HWDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 15.1 A, HV, wall mounting, 2 axes	
	Required accessories	
	Terminal block sets	
8BZVI0110DS.000-1A	Screw clamp set for ACOPOSmulti 8BVI0110HxDS modules: 1x 8TB2108.2010-00, 1x 8TB2104.203L-00, 1x 8TB2104.203F-00, 1x 8TB3104.204G-11, 1x 8TB3104.204K-11	
	Optional accessories	
	Accessory sets	
8BXB000.0000-00	ACOPOSmulti accessory set for encoder buffering consists of the following: 1 lithium battery AA 3.6 V, 1 cover for battery compartment	
	Fan modules	
8BXF001.0000-00	ACOPOSmulti fan module, replacement fan for ACOPOSmulti modules (8BxP/8B0C/8BVI/8BVE/8B0K)	
	POWERLINK/Ethernet cables	
X20CA0E61.00020	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.2 m	
X20CA0E61.00025	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.25 m	
X20CA0E61.00030	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.3 m	
X20CA0E61.00035	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.35 m	
X20CA0E61.00050	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.5 m	
X20CA0E61.00100	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 1 m	
	Shield component sets	
8SCS000.0000-00	ACOPOSmulti shield component set: 1 shield plate 1x type 0, 1 hose clamp, B 9 mm, D 12-22 mm	
8SCS002.0000-00	ACOPOSmulti shield component set: 1x clamping plate; 2x clamps D 4-13.5 mm; 4x screws	
8SCS009.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK8-14, 1x shield connection clamp SK14	
	Terminal blocks	
8TB2104.203F-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, F keying: 0101	
8TB2104.203L-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, L keying: 1010	
8TB2108.2010-00	8-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	
8TB3104.204G-11	4-pin screw clamp, single row, spacing: 7.62 mm, label 4: PE W V U, G keying: 0110	
8TB3104.204K-11	4-pin screw clamp, single row, spacing: 7.62 mm, label 4: PE W V U, K keying: 1001	

Table 52: 8BVI0110HCDS.000-1, 8BVI0110HWDS.000-1 - Order data

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

For details, see 6.1.2 "Safe power transmission system " on page 283.

2.3.5.1.3 Technical data

Model number	8BVI0110HCDS.000-1	8BVI0110HWDS.000-1
General information		
B&R ID code	0xAA17	0xAA19
Cooling and mounting type	Cold plate or feed-through mounting	Wall mounting
Slots for plug-in modules	2 [1]	
Certifications		
CE	Yes	
Functional safety[2]	Yes (openSAFETY)	
UL	cULus E225616 Power conversion equipment	
EAC	Yes	
KC	Yes	
DC bus connection		
Voltage		
Nominal	750 VDC	
Continuous power consumption [3]	22.3 kW	
Power dissipation depending on switching frequency [4]		
Switching frequency 5 kHz	[0.33 * I_M^2 + 11 * I_M + 90] W	
Switching frequency 10 kHz	[0.97 * I_M^2 + 9.5 * I_M + 170] W	
Switching frequency 20 kHz	[1.66 * I_M^2 + 21 * I_M + 380] W	
DC bus capacitance	660 µF	
Variant	ACOPOSmulti backplane	
24 VDC power supply		
Input voltage	25 VDC ±1.6%	
Input capacitance	23.5 µF	
Max. power consumption	32 W + P_{SMC1} + P_{SMC2} + $P_{24 V Out}$ + $P_{HoldingBrake(s)}$[5]	32 W + P_{SMC1} + P_{SMC2} + $P_{24 V Out}$ + $P_{HoldingBrake(s)}$[6]
Variant	ACOPOSmulti backplane	
24 VDC output		
Quantity	2	
Output voltage		
DC bus voltage (U_{DC}): 260 to 315 VDC	25 VDC * (U_{DC}/315)	
DC bus voltage (U_{DC}): 315 to 800 VDC	24 VDC ±6%	
Fuse protection	250 mA (slow-blow) electronic, automatic reset	
Motor connection [7]		
Quantity	2	
Continuous power per motor connection [3]	11 kW	
Continuous current per motor connection [3]	15.1 A_{eff}	15.1 A_{Eff}
Reduction of continuous current depending on switching frequency [8]		
Switching frequency 5 kHz	-	No reduction [9]
Switching frequency 10 kHz	-	0.19 A/K (from 29°C) [10]
Switching frequency 20 kHz	-	0.15 A/K (from -38°C) [10]
Reduction of continuous current depending on switching frequency and mounting type [8]		
Switching frequency 5 kHz		
Cold plate mounting [11]	0.38 A/K (starting at 51°C) [9]	-
Feed-through mounting	0.27 A/K (starting at 46°C) [9]	-
Switching frequency 10 kHz		
Cold plate mounting [11]	0.25 A/K (starting at 24°C) [12]	-
Feed-through mounting	0.16 A/K (starting at 2°C) [10]	-
Switching frequency 20 kHz		
Cold plate mounting [11]	0.19 A/K (starting at -14°C) [12]	-
Feed-through mounting	0.14 A/K (starting at -74°C) [10]	-
Reduction of continuous current depending on installation elevation		
Starting at 500 m above sea level	1.51 A_{eff} per 1000 m	1.51 A_{Eff} per 1000 m
Peak current per motor connection	37.7 A_{eff}	37.7 A_{Eff}
Nominal switching frequency	5 kHz	
Possible switching frequencies [13]	5 / 10 / 20 kHz	5/10/20 kHz
Electrical stress of connected motor per IEC TS 60034-25 [14]	Limit value curve A	

Table 53: 8BVI0110HCDS.000-1, 8BVI0110HWDS.000-1 - Technical data

Model number	8BVI0110HCDS.000-1	8BVI0110HWDS.000-1
Protective measures		
Overload protection	Yes	
Short circuit and ground fault protection	Yes	
Max. output frequency	598 Hz [15)]	598 Hz [16)]
Variant		
U, V, W, PE	Male connector	
Shield connection	Yes	
Terminal connection cross section		
Flexible and fine-stranded wires		
With wire end sleeves	0.25 to 4 mm²	
Approbation data		
UL/C-UL-US	30 to 10	
CSA	28 to 10	
Terminal cable cross section dimension of shield connection	12 to 22 mm	
Max. motor cable length depending on switching frequency		
Switching frequency 5 kHz	25 m	
Switching frequency 10 kHz	25 m	
Switching frequency 20 kHz	10 m	
Motor holding brake connection		
Quantity	2	
Output voltage [17)]	24 VDC +5.8% / -0.5% [18)]	
Continuous current	2.1 A	
Max. internal resistance	0.3 Ω	
Extinction potential	Approx. 30 V	
Max. extinction energy per switching operation	3 Ws	
Max. switching frequency	0.5 Hz	
Protective measures		
Overload and short-circuit protection	Yes	
Open circuit monitoring	Yes	
Undervoltage monitoring	Yes	
Response threshold for open circuit monitoring	Approx. 0.5 A	
Response threshold for undervoltage monitoring	24 VDC -2% / -4%	
Encoder interfaces [19)]		
Quantity	2	
Type	EnDat 2.2 [20)]	
Connections	9-pin female DSUB connector	
Status indicators	UP/DN LEDs	
Electrical isolation		
Encoder - ACOPOSmulti	No	
Encoder monitoring	Yes	
Max. encoder cable length	100 m Depends on the cross section of the power supply wires of the encoder cable [21)]	100 m Depends on the cross section of the power supply wires in the encoder cable [22)]
Encoder power supply		
Output voltage	Typ. 12.5 V	
Load capacity	350 mA	
Protective measures		
Short-circuit proof	Yes	
Overload-proof	Yes	
Synchronous serial interface		
Signal transmission	RS485	
Data transfer rate	6.25 Mbit/s	
Max. power consumption per encoder interface	P_{SMC}[W] = 19 V * $I_{Encoder}$[A] [23)]	
Trigger inputs		
Quantity	2	
Circuit	Sink	
Electrical isolation		
Input - Inverter module	Yes	
Input - Input	No	Yes
Input voltage		
Nominal	24 VDC	
Maximum	30 VDC	
Switching threshold		
Low	<5 V	
High	>15 V	
Input current at nominal voltage	Approx. 10 mA	
Switching delay		
Rising edge	52 µs ±0.5 µs (digitally filtered)	
Falling edge	53 µs ±0.5 µs (digitally filtered)	
Modulation compared to ground potential	Max. ±38 V	

Table 53: 8BVI0110HCDS.000-1, 8BVI0110HWDS.000-1 - Technical data

Model number	8BVI0110HCDS.000-1	8BVI0110HWDS.000-1
Electrical properties		
Discharge capacitance	0.44 µF	
Operating conditions		
Permissible mounting orientations		
Hanging vertically	Yes	
Horizontal, face up	Yes	
Standing horizontally	No	
Installation elevation above sea level		
Nominal	0 to 500 m	
Maximum [24]	4000 m	
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)	
Overvoltage category per EN 61800-5-1	III	
Degree of protection per EN 60529	IP20	
Ambient conditions		
Temperature		
Operation		
Nominal	5 to 40°C	
Maximum [25]	55°C	
Storage	-25 to 55°C	
Transport	-25 to 70°C	
Relative humidity		
Operation	5 to 85%	
Storage	5 to 95%	
Transport	Max. 95% at 40°C	
Mechanical properties		
Dimensions [26]		
Width	106.5 mm	
Height	317 mm	
Depth		
Wall mounting	-	263 mm
Cold plate	212 mm	-
Feed-through mounting	209 mm	-
Weight	Approx. 4.1 kg	Approx. 5.3 kg
Module width	2	

Table 53: 8BVI0110HCDS.000-1, 8BVI0110HWDS.000-1 - Technical data

1) SLOT 1 and SLOT 2 of the ACOPOSmulti module are occupied by the encoder interfaces.
2) Achievable safety classifications (safety integrity level, safety category, performance level) are documented in the user's manual (section "Safety technology").
3) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
4) I_M = 0.5 * (I_{X5A} + I_{X5B})
I_{X5A} ... Current on motor connection X5A [A_{eff}]
I_{X5B} ... Current on motor connection X5B [A_{eff}]
5) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SMC2} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT2 (see the "Encoder interfaces" section).
$P_{24\ V\ Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
6) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SMC2} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT2 (see the "Encoder interfaces" section).
$P_{24\ V\ Out}$ ... Power [W] that is output to the connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
7) Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.
8) Valid for the following conditions: 750 VDC DC bus voltage, minimum permissible coolant flow volume (3 l/min). The temperature specifications refer to the return temperature of the cold plate mounting plate.
9) Value for the nominal switching frequency.
10) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
11) The temperature specifications refer to the return temperature of the cold plate mounting plate.
12) The module cannot supply the full continuous current at this switching frequency. This unusual value for the return temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
Caution! Condensation can occur at low flow temperatures and return temperatures.
13) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load. When using 2-axis modules, the increased CPU load reduces the functionality of the drive; if this is not taken into consideration, the computing time can be exceeded in extreme cases.
14) If necessary, the stress of the motor isolation system can be reduced by an additional externally wired dv/dt choke. For example, the RWK 305 three-phase du/dt choke from Schaffner (www.schaffner.com) can be used. Important: Even when using a dv/dt choke, it is necessary to ensure that an EMC-compatible, low inductance shield connection is used!
15) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
16) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output (power unit: limit speed exceeded).
17) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.

18) The specified value is only valid under the following conditions:
- The 24 VDC supply for the module is provided by an 8B0C auxiliary supply module installed on the same mounting plate.
If the 24 VDC supply for the module is applied to the mounting plate using an 8BVE expansion module, then the output voltage is reduced because of voltage drops on the expansion cable. In this case, undervoltage monitoring must be disabled.
19) Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.
20) An EnDat 2.2 functional safety encoder is required when using ACOPOSmulti SafeMOTION inverter modules! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!
21) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 100 m is not permitted to be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A]
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
22) The maximum encoder cable length l_{Max} can be calculated as follows (the maximum permissible encoder cable length of 100 m must not be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A].
A ... Cross section of the power supply wires [mm²].
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178).
23) $I_{Encoder}$ ... Max. power consumption of the connected encoder [A].
24) Continuous operation at elevations ranging from 500 m to 4,000 m above sea level is possible (taking the specified continuous current reductions into consideration).
25) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous current reductions into consideration), but this will result in a shorter service life.
26) These dimensions refer to the actual device dimensions including the respective mounting plate. Make sure to leave additional space above and below the devices for mounting, connections and air circulation.

2.3.5.1.4 Wiring

For details, see section 2.3.5.3 "Wiring: Safe double-width inverter modules (2-axis modules)" on page 113.

For general information, see section 2.6 "Wiring" on page 150.

2.3.5.2 8BVI0220HCDS.000-1, 8BVI0220HWDS.000-1

2.3.5.2.1 General information

- Clearly structured, straightforward implementation via network-based safety technology
- Modular expandability through virtual wiring
- Immediate triggering of safety function due to short cycle times
- Easy implementation with transparent control and status information, even in the standard application
- Compact design
- Complete safety functionality, even in 2-axis modules

2.3.5.2.2 Order data

Model number	Short description	Figure
	Cold plate or feed-through mounting	
8BVI0220HCDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 22 A, HV, cold plate or feed-through mounting, 2 axes	
	Wall mounting	
8BVI0220HWDS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 22 A, HV, wall mounting, 2 axes	
	Required accessories	
	Terminal block sets	
8BZVI0220DS.000-1A	Screw clamp terminal block set for ACOPOSmulti 8BVI0220HxDS modules: 1x 8TB2108.2010-00, 1x 8TB2104.203L-00, 1x 8TB2104.203F-00, 1x 8TB3104.204G-11, 1x 8TB3104.204K-11	
	Optional accessories	
	Accessory sets	
8BXB000.0000-00	ACOPOSmulti accessory set for encoder buffering consists of the following: 1 lithium battery AA 3.6 V, 1 cover for battery compartment	
	Fan modules	
8BXF001.0000-00	ACOPOSmulti fan module, replacement fan for ACOPOSmulti modules (8BxP/8B0C/8BVI/8BVE/8B0K)	
	POWERLINK/Ethernet cables	
X20CA0E61.00020	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.2 m	
X20CA0E61.00025	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.25 m	

Table 54: 8BVI0220HCDS.000-1, 8BVI0220HWDS.000-1 - Order data

Model number	Short description	Figure
X20CA0E61.00030	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.3 m	
X20CA0E61.00035	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.35 m	
X20CA0E61.00050	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.5 m	
X20CA0E61.00100	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 1 m	
	Shield component sets	
8SCS000.0000-00	ACOPOSmulti shield component set: 1 shield plate 1x type 0, 1 hose clamp, B 9 mm, D 12-22 mm	
8SCS002.0000-00	ACOPOSmulti shield component set: 1x clamping plate; 2x clamps D 4-13.5 mm; 4x screws	
8SCS009.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK8-14, 1x shield connection clamp SK14	
	Terminal blocks	
8TB2104.203F-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, F keying: 0101	
8TB2104.203L-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, L keying: 1010	
8TB2108.2010-00	8-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	
8TB3104.204G-11	4-pin screw clamp, single row, spacing: 7.62 mm, label 4: PE W V U, G keying: 0110	
8TB3104.204K-11	4-pin screw clamp, single row, spacing: 7.62 mm, label 4: PE W V U, K keying: 1001	

Table 54: 8BVI0220HCDS.000-1, 8BVI0220HWDS.000-1 - Order data

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

For details, see 6.1.2 "Safe power transmission system " on page 283.

2.3.5.2.3 Technical data

Model number	8BVI0220HCDS.000-1	8BVI0220HWDS.000-1
General information		
B&R ID code	0xAA1B	0xAA1D
Cooling and mounting type	Cold plate or feed-through mounting	Wall mounting
Slots for plug-in modules	2 1)	
Certifications		
CE	Yes	
Functional safety2)	Yes (openSAFETY)	
UL	cULus E225616 Power conversion equipment	
EAC	Yes	
KC	Yes	
DC bus connection		
Voltage		
Nominal	750 VDC	
Continuous power consumption 3)	32.37 kW	
Power dissipation depending on switching frequency 4)		
Switching frequency 5 kHz	[0.65 * I_M^2 - 0.35 * I_M+ 64] W	
Switching frequency 10 kHz	[2.16 * I_M^2 - 10.912 * I_M+ 190] W	
DC bus capacitance	1320 µF	
Variant	ACOPOSmulti backplane	
24 VDC power supply		
Input voltage	25 VDC ±1.6%	
Input capacitance	23.5 µF	
Max. power consumption	32 W + P_{SMC1} + P_{SMC2} + $P_{24\,V\,Out}$ + $P_{HoldingBrake(s)}$5)	
Variant	ACOPOSmulti backplane	
24 VDC output		
Quantity	2	

Table 55: 8BVI0220HCDS.000-1, 8BVI0220HWDS.000-1 - Technical data

Model number	8BVI0220HCDS.000-1	8BVI0220HWDS.000-1
Output voltage		
DC bus voltage (U_{DC}): 260 to 315 VDC	25 VDC * (U_{DC}/315)	
DC bus voltage (U_{DC}): 315 to 800 VDC	24 VDC ±6%	
Fuse protection	250 mA (slow-blow) electronic, automatic reset	
Motor connection [6]		
Quantity	2	
Continuous power per motor connection [3]	16 kW	
Continuous current per motor connection [3]	22 A_{eff}	
Reduction of continuous current depending on switching frequency [7]		
Switching frequency 5 kHz	-	0.33 A/K (starting at 40°C) [8]
Switching frequency 10 kHz	-	0.17 A/K (starting at -25°C) [9]
Reduction of continuous current depending on switching frequency and mounting type [7]		
Switching frequency 5 kHz		
Cold plate mounting [10]	0.99 A/K (starting at 40°C) [8]	-
Feed-through mounting	0.52 A/K (starting at 40°C) [8]	-
Switching frequency 10 kHz		
Cold plate mounting [10]	0.29 A/K (starting at 10°C) [11]	-
Feed-through mounting	0.23 A/K (starting at 0°C) [9]	-
Reduction of continuous current depending on installation elevation		
Starting at 500 m above sea level	2.2 A_{eff} per 1000 m	
Peak current per motor connection	55 A_{eff} [12]	
Nominal switching frequency	5 kHz	
Possible switching frequencies [13]	5/10 kHz	
Electrical stress of connected motor per IEC TS 60034-25 [14]	Limit value curve A	
Protective measures		
Overload protection	Yes	
Short circuit and ground fault protection	Yes	
Max. output frequency	598 Hz [15]	
Variant		
U, V, W, PE	Male connector	
Shield connection	Yes	
Terminal connection cross section		
Flexible and fine-stranded wires		
With wire end sleeves	0.25 to 4 mm²	
Approbation data		
UL/C-UL-US	30 to 10	
CSA	28 to 10	
Terminal cable cross section dimension of shield connection	12 to 22 mm	
Max. motor cable length depending on switching frequency		
Switching frequency 5 kHz	25 m	
Switching frequency 10 kHz	25 m	
Motor holding brake connection		
Quantity	2	
Output voltage [16]	24 VDC +5.8% / -0.5% [17]	
Continuous current	2.1 A	
Max. internal resistance	0.3 Ω	
Extinction potential	Approx. 30 V	
Max. extinction energy per switching operation	3 Ws	
Max. switching frequency	0.5 Hz	
Protective measures		
Overload and short-circuit protection	Yes	
Open circuit monitoring	Yes	
Undervoltage monitoring	Yes	
Response threshold for open circuit monitoring	Approx. 0.5 A	
Response threshold for undervoltage monitoring	24 VDC -2% / -4%	
Encoder interfaces [18]		
Quantity	2	
Type	EnDat 2.2 [19]	
Connections	9-pin female DSUB connector	
Status indicators	UP/DN LEDs	
Electrical isolation		
Encoder - ACOPOSmulti	No	
Encoder monitoring	Yes	
Max. encoder cable length	100 m Depends on the cross section of the power supply wires of the encoder cable [20]	

Table 55: 8BVI0220HCDS.000-1, 8BVI0220HWDS.000-1 - Technical data

Model number	8BVI0220HCDS.000-1	8BVI0220HWDS.000-1
Encoder power supply		
Output voltage	Typ. 12.5 V	
Load capacity	350 mA	
Protective measures		
Short-circuit proof	Yes	
Overload-proof	Yes	
Synchronous serial interface		
Signal transmission	RS485	
Data transfer rate	6.25 Mbit/s	
Max. power consumption per encoder interface	P_{SMC}[W] = 19 V * $I_{Encoder}$[A] 21)	
Trigger inputs		
Quantity	2	
Circuit	Sink	
Electrical isolation		
Input - Inverter module	Yes	
Input - Input	Yes	
Input voltage		
Nominal	24 VDC	
Maximum	30 VDC	
Switching threshold		
Low	<5 V	
High	>15 V	
Input current at nominal voltage	Approx. 10 mA	
Switching delay		
Rising edge	52 µs ±0.5 µs (digitally filtered)	
Falling edge	53 µs ±0.5 µs (digitally filtered)	
Modulation compared to ground potential	Max. ±38 V	
Electrical properties		
Discharge capacitance	0.44 µF	
Operating conditions		
Permissible mounting orientations		
Hanging vertically	Yes	
Horizontal, face up	Yes	
Standing horizontally	No	
Installation elevation above sea level		
Nominal	0 to 500 m	
Maximum 22)	4000 m	
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)	
Overvoltage category per EN 61800-5-1	III	
Degree of protection per EN 60529	IP20	
Ambient conditions		
Temperature		
Operation		
Nominal	5 to 40°C	
Maximum 23)	55°C	
Storage	-25 to 55°C	
Transport	-25 to 70°C	
Relative humidity		
Operation	5 to 85%	
Storage	5 to 95%	
Transport	Max. 95% at 40°C	
Mechanical properties		
Dimensions 24)		
Width	106.5 mm	
Height	317 mm	
Depth		
Wall mounting	-	263 mm
Cold plate	212 mm	-
Feed-through mounting	209 mm	-
Weight	Approx. 4.4 kg	Approx. 5.7 kg
Module width	2	

Table 55: 8BVI0220HCDS.000-1, 8BVI0220HWDS.000-1 - Technical data

1) SLOT 1 and SLOT 2 of the ACOPOSmulti module are occupied by the encoder interfaces.
2) Achievable safety classifications (safety integrity level, safety category, performance level) are documented in the user's manual (section "Safety technology").
3) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
4) $I_M = 0.5 * (I_{X5A} + I_{X5B})$
I_{X5A} ... Current on motor connection X5A [A_{eff}]
I_{X5B} ... Current on motor connection X5B [A_{eff}]
5) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SMC2} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT2 (see the "Encoder interfaces" section).
$P_{24\ V\ Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
6) Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.

7) Valid for the following conditions: 750 VDC DC bus voltage, minimum permissible coolant flow volume (3 l/min). The temperature specifications refer to the return temperature of the cold plate mounting plate.
8) Value for the nominal switching frequency.
9) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
10) The temperature specifications refer to the return temperature of the cold plate mounting plate.
11) The module cannot supply the full continuous current at this switching frequency. This unusual value for the return temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
Caution! Condensation can occur at low flow temperatures and return temperatures.
12) The thermal pulse load capacity is lower than for the 8BVI0220HxS0.000-1 1-axis module. It is therefore not possible to simply replace two 8BVI0220HxS0.000-1 1-axis modules with one 8BVI0220HxD0.000-1 2-axis module. If this is required, the load cycle must be examined in detail.
13) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load. When using 2-axis modules, the increased CPU load reduces the functionality of the drive; if this is not taken into consideration, the computing time can be exceeded in extreme cases.
14) If necessary, the stress of the motor isolation system can be reduced by an additional externally wired dv/dt choke. For example, the RWK 305 three-phase du/dt choke from Schaffner (www.schaffner.com) can be used. Important: Even when using a dv/dt choke, it is necessary to ensure that an EMC-compatible, low inductance shield connection is used!
15) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
16) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
17) The specified value is only valid under the following conditions:
- The 24 VDC supply for the module is provided by an 8B0C auxiliary supply module installed on the same mounting plate.
If the 24 VDC supply for the module is applied to the mounting plate using an 8BVE expansion module, then the output voltage is reduced because of voltage drops on the expansion cable. In this case, undervoltage monitoring must be disabled.
18) Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.
19) An EnDat 2.2 functional safety encoder is required when using ACOPOSmulti SafeMOTION inverter modules! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!
20) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 100 m is not permitted to be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A].
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
21) $I_{Encoder}$ ... Max. power consumption of the connected encoder [A].
22) Continuous operation at elevations ranging from 500 m to 4,000 m above sea level is possible (taking the specified continuous current reductions into consideration).
23) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous current reductions into consideration), but this will result in a shorter service life.
24) These dimensions refer to the actual device dimensions including the respective mounting plate. Make sure to leave additional space above and below the devices for mounting, connections and air circulation.

2.3.5.2.4 Wiring

For details, see section 2.3.5.3 "Wiring: Safe double-width inverter modules (2-axis modules)" on page 113.

For general information, see section 2.6 "Wiring" on page 150.

2.3.5.3 Wiring: Safe double-width inverter modules (2-axis modules)

2.3.5.3.1 ACOPOSmulti SafeMOTION EnDat 2.2 - Pinout overview

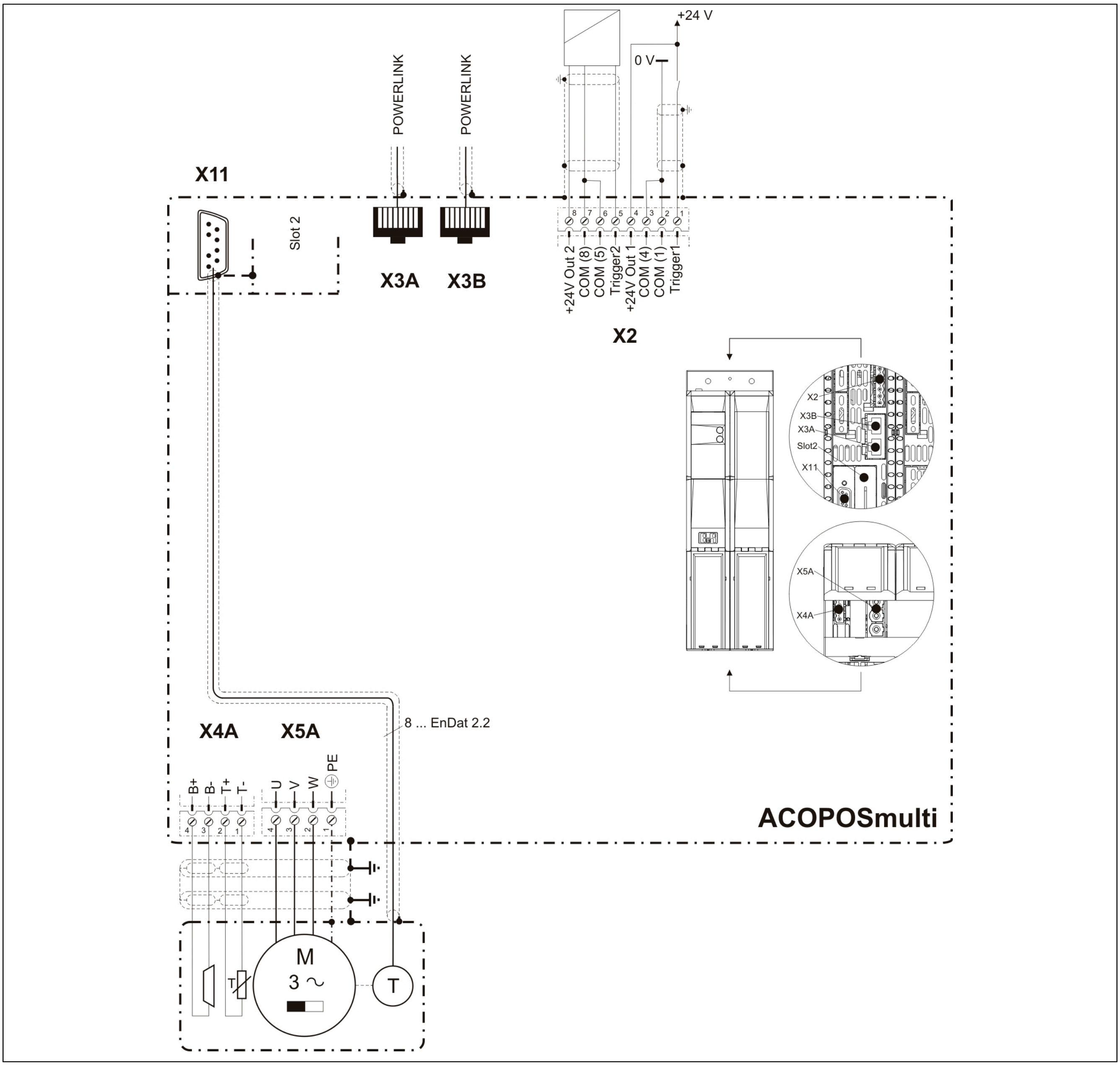


Figure 11: Pinout overview

2.3.5.3.2 Connector X2 - Pinout

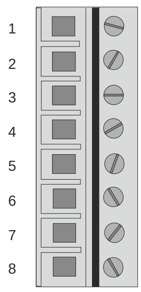
X2	Pin	Description	Function
	1	Trigger 1	Trigger 1
	2	COM (1)	Trigger 1 0 V
	3	COM (2)	+24 V output 1 0 V
	4	+24 V Out 1	+24 V output 1
	5	Trigger 2	Trigger 2
	6	COM (5)	Trigger 2 0 V
	7	COM (8)	+24 V output 2 0 V
	8	+24 V Out 2	+24 V output 2

Table 56: Connector X2 - Pinout

2.3.5.3.3 Connectors X3A, X3B - Pinout

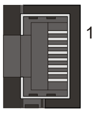
X3A, X3B	Pin	Description	Function
	1	RXD	Receive signal
	2	RXD\	Receive signal inverted
	3	TXD	Transmit signal
	4	Shield	Shield
	5	Shield	Shield
	6	TXD\	Transmit signal inverted
	7	Shield	Shield
	8	Shield	Shield

Table 57: X3A, X3B connectors - Pinout

2.3.5.3.4 Connector X4A - Pinout

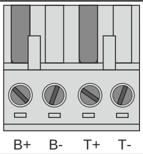
X4A	Description	Function
	T-	Axis 1: Temperature sensor -
	T+	Axis 1: Temperature sensor +
	B-	Axis 1: Brake -
	B+	Axis 1: Brake +

Table 58: Connector X4A - Pinout

Danger!

A short circuit of SBC output B+ against 24 V results in state FUNCTIONAL FAIL SAFE being enabled. This means that safe pulse disabling is enabled. The brake always remains switched on / released, however, due to the short circuit to 24 V!
This can lead to dangerous situations since the motor holding brake cannot brake, prevent the spin-out movement or prevent the unbraked lowering movement when loads are suspended!
A short circuit of SBC output B+ against 24 V must be prevented by suitable wiring measures!

For a 2-axis module, it is therefore especially important to prevent a cross fault between the two B+ connections of the two axes!

Danger!

The following applies to the SBC output:

- **It is not permitted to be wired across modules!**
- **It is not permitted to be wired as an open emitter!**
- **It is not permitted to be wired as an open collector!**

Danger!

Only an output voltage of ≤ 5 V can be ensured for the safe motor holding brake output when switched off. When selecting the motor holding brake, the user must ensure that the required braking torque is achieved with a voltage of 5 V applied.

Information:

The transistors of the SBC output stage are tested cyclically. When the output channels are active, this test emits low pulses on the output with a maximum length of 600 µs.

This must be taken into consideration when choosing the motor holding brake!

Danger!

The connections for the motor temperature sensors and the motor holding brake are safely isolated circuits. These connections are therefore only permitted to be connected to devices or components that have sufficient isolation per IEC 60364-4-41 or EN 61800-5-1.

Caution!

If B+ and B- are swapped when connecting the permanent magnet holding brakes, then the brakes cannot be opened! ACOPOSmulti inverter modules cannot determine if a holding brake is connected with reverse polarity!

Warning!

Temperature sensors are only permitted to be connected to the X4A/T+ and X4A/T- connectors on an ACOPOSmulti module under the following conditions:

- **SLOT1 of the ACOPOSmulti module does not contain an ACOPOSmulti plug-in module to which a temperature sensor is connected on the T+ and T- connections.**

Otherwise, the temperature monitoring functions on the ACOPOSmulti module may become ineffective, which in extreme cases can cause the hardware (e.g. motors) connected to the ACOPOSmulti module to be destroyed!

2.3.5.3.5 Connector X4B - Pinout

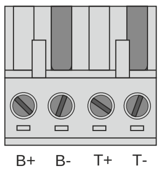
X4B	Description	Function
	T-	Axis 2: Temperature sensor -
	T+	Axis 2: Temperature sensor +
	B-	Axis 2: Brake -
	B+	Axis 2: Brake +

Table 59: Connector X4B - Pinout

Danger!

A short circuit of SBC output B+ against 24 V results in state FUNCTIONAL FAIL SAFE being enabled. This means that safe pulse disabling is enabled. The brake always remains switched on / released, however, due to the short circuit to 24 V!
This can lead to dangerous situations since the motor holding brake cannot brake, prevent the spin-out movement or prevent the unbraked lowering movement when loads are suspended!
A short circuit of SBC output B+ against 24 V must be prevented by suitable wiring measures!

For a 2-axis module, it is therefore especially important to prevent a cross fault between the two B+ connections of the two axes!

Danger!

The following applies to the SBC output:

- **It is not permitted to be wired across modules!**
- **It is not permitted to be wired as an open emitter!**
- **It is not permitted to be wired as an open collector!**

Danger!

Only an output voltage of ≤ 5 V can be ensured for the safe motor holding brake output when switched off. When selecting the motor holding brake, the user must ensure that the required braking torque is achieved with a voltage of 5 V applied.

Information:

The transistors of the SBC output stage are tested cyclically. When the output channels are active, this test emits low pulses on the output with a maximum length of 600 µs.

This must be taken into consideration when choosing the motor holding brake!

Danger!

The connections for the motor temperature sensors and the motor holding brake are safely isolated circuits. These connections are therefore only permitted to be connected to devices or components that have sufficient isolation per IEC 60364-4-41 or EN 61800-5-1.

Caution!

If B+ and B- are swapped when connecting the permanent magnet holding brakes, then the brakes cannot be opened! ACOPOSmulti inverter modules cannot determine if a holding brake is connected with reverse polarity!

Warning!

Temperature sensors are only permitted to be connected to the X4B/T+ and X4B/T- connectors on an ACOPOSmulti module under the following conditions:

- **SLOT2 of the ACOPOSmulti module does not contain an ACOPOSmulti plug-in module to which a temperature sensor is connected on the T+ and T- connections.**

Otherwise, the temperature monitoring functions on the ACOPOSmulti module may become ineffective, which in extreme cases can cause the hardware (e.g. motors) connected to the ACOPOSmulti module to be destroyed!

2.3.5.3.6 Connector X5A - Pinout

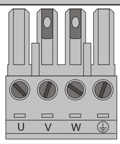
X5A	Description	Function
	⏚	Axis 1: Protective ground conductor
	W	Axis 1: Motor connection W
	V	Axis 1: Motor connection V
	U	Axis 1: Motor connection U

Table 60: Connector X5A - Pinout

Information:

An additional PE wire does not have to be connected to the threaded bolt beside the X5A connector. The PE connection on the male X5A connector is required and sufficient.

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

2.3.5.3.7 Connector X5B - Pinout

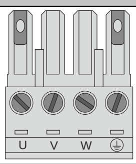
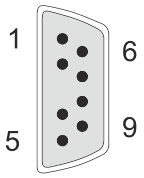
X5B	Description	Function
	⏚	Axis 2: Protective ground conductor
	W	Axis 2: Motor connection W
	V	Axis 2: Motor connection V
	U	Axis 2: Motor connection U

Table 61: Connector X5B - Pinout

Information:

Only B&R 8BCM motor cables are permitted to be used for wiring the motor connections!

2.3.5.3.8 SafeMOTION EnDat 2.2 module - Pinout

Figure	X11 (X12)	Pin	Description	Function
		1	U+	Encoder power supply +12.5 V
		2	---	---
		3	---	---
		4	D	Data input
		5	T	Clock output
		6	COM (1)	Encoder power supply 0 V
		7	---	---
		8	D\	Data input inverted
		9	T\	Clock output inverted

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

Information:

The SafeMOTION module cannot be replaced! The SafeMOTION module and the ACOPOSmulti SafeMOTION inverter module together form a single unit. In the event of an error, the entire module must be replaced.

2.3.6 Safe 4x width inverter modules (1-axis modules)

2.3.6.1 8BVI0660HCSS.000-1, 8BVI0660HWSS.000-1, 8BVI0660HCSA.000-1, 8BVI0660HWSA.000-1

2.3.6.1.1 General information

- Clearly structured, straightforward implementation via network-based safety technology
- Modular expandability through virtual wiring
- Immediate triggering of safety function due to short cycle times
- Easy implementation with transparent control and status information, even in the standard application
- Compact design

2.3.6.1.2 Order data

Model number	Short description	Figure
	Cold plate or feed-through mounting	
8BVI0660HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 66 A, HV, cold plate or feed-through mounting	
8BVI0660HCSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 66 A, HV, cold plate or feed-through mounting	
	Wall mounting	
8BVI0660HWSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 66 A, HV, wall mounting	
8BVI0660HWSA.000-1	ACOPOSmulti SafeMOTION SinCos inverter module, 66 A, HV, wall mounting	
	Required accessories	
	Terminal block sets	
8BZVI1650SS.000-1A	Screw clamp terminal block set for ACOPOSmulti 8BVI0660HxSS, 8BVI0880HxSS, 8BVI1650HxSS, 8BVI0660HxSA, 8BVI0880HxSA and 8BVI1650HxSA modules: 1x 8TB2104.203L-00, 1x 8TB2108.2010-00	
	Optional accessories	
	Accessory sets	
8BXB000.0000-00	ACOPOSmulti accessory set for encoder buffering consists of the following: 1 lithium battery AA 3.6 V, 1 cover for battery compartment	
	Fan modules	
8BXF001.0000-00	ACOPOSmulti fan module, replacement fan for ACOPOSmulti modules (8BxP/8B0C/8BVI/8BVE/8B0K)	
	POWERLINK/Ethernet cables	
X20CA0E61.00020	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.2 m	
X20CA0E61.00025	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.25 m	
X20CA0E61.00030	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.3 m	
X20CA0E61.00035	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.35 m	
X20CA0E61.00050	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.5 m	
X20CA0E61.00100	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 1 m	
	Plug-in modules	
8BAC0120.000-1	ACOPOSmulti plug-in module, EnDat 2.1 interface	
8BAC0120.001-2	ACOPOSmulti plug-in module, EnDat 2.2 interface	
8BAC0121.000-1	ACOPOSmulti plug-in module, HIPERFACE interface	
8BAC0122.000-1	ACOPOSmulti plug-in module, resolver interface 10 kHz	
8BAC0123.000-1	ACOPOSmulti plug-in module, incremental encoder and SSI absolute encoder interface for RS422 signals	
8BAC0123.001-1	ACOPOSmulti plug-in module, incremental encoder interface for 5 V single-ended and 5 V differential signals	
8BAC0123.002-1	ACOPOSmulti plug-in module, incremental encoder interface for 24 V single-ended and 24 V differential signals	
8BAC0124.000-1	ACOPOSmulti plug-in module, SinCos interface	
8BAC0125.000-1	ACOPOSmulti plug-in module, SinCos EnDat 2.1/SSI/BiSS interface	
8BAC0130.000-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 2 digital outputs, 500 mA, max. 1.25 kHz, 2 digital inputs 24 VDC	
8BAC0130.001-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 4 digital outputs, 500 mA, max. 1.25 kHz	
8BAC0132.000-1	ACOPOSmulti plug-in module, 4 analog inputs ±10 V	
8BAC0133.000-1	ACOPOSmulti plug-in module, 3 RS422 outputs for ABR encoder emulation, 1 MHz	
	Shield component sets	
8SCS001.0000-00	ACOPOSmulti shield component set: 1x shield plate 4x type 1, 1x hose clamp, B 9 mm, D 12-22 mm	
8SCS002.0000-00	ACOPOSmulti shield component set: 1x clamping plate; 2x clamps D 4-13.5 mm; 4x screws	

Table 62: 8BVI0660HCSS.000-1, 8BVI0660HCSA.000-1, 8BVI0660HWSS.000-1, 8BVI0660HWSA.000-1 - Order data

Model number	Short description	Figure
8SCS003.0000-00	ACOPOSmulti shield component set: 1x shield mounting plate 4x 45°, 8x screws	
8SCS004.0000-00	ACOPOSmulti shield component set: 1x shield plate 4x type 0, 2x hose clamps, B 9 mm, D 32-50 mm	
8SCS010.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK14-20, 1x shield connection clamp SK20	
	Terminal blocks	
8TB2104.203L-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, L keying: 1010	
8TB2106.2010-00	6-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	
8TB2106.2210-00	Push-in terminal block 6-pin, 1-row, spacing: 5.08 mm, label 1: numbered consecutively	
8TB2108.2010-00	8-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	

Table 62: 8BVI0660HCSS.000-1, 8BVI0660HCSA.000-1, 8BVI0660HWSS.000-1, 8BVI0660HWSA.000-1 - Order data

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

ACOPOSmulti SafeMOTION SinCos

Information:

Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.

Information:

Only 8BCS encoder cables from B&R are permitted to be connected to the encoder interfaces on B&R standard motors.

For details, see 6.1.2 "Safe power transmission system " on page 283.

2.3.6.1.3 Technical data

Model number	8BVI0660HCSS.000-1	8BVI0660HWSS.000-1	8BVI0660HCSA.000-1	8BVI0660HWSA.000-1
General information				
B&R ID code	0xBE89	0xBE8B	0xE0B8	0xE0B9
Cooling and mounting type	Cold plate or feed-through mounting	Wall mounting	Cold plate or feed-through mounting	Wall mounting
Slots for plug-in modules	2 1)			
Certifications				
CE	Yes			
Functional safety 2)	Yes (openSAFETY)			
UL	cULus E225616 Power conversion equipment			
EAC	Yes			
KC	Yes		-	
DC bus connection				
Voltage				
Nominal	750 VDC			
Continuous power consumption 3)	48.8 kW			
Power dissipation depending on switching frequency 4)				
Switching frequency 5 kHz	$[0.03 * I_M^2 + 7.9 * I_M + 90]$ W			
Switching frequency 10 kHz	$[0.11 * I_M^2 + 11 * I_M + 185]$ W			
Switching frequency 20 kHz	$[0.17 * I_M^2 + 27 * I_M + 310]$ W			
DC bus capacitance	1980 µF			
Variant	ACOPOSmulti backplane			
24 VDC power supply				
Input voltage	25 VDC ±1.6%			

Table 63: 8BVI0660HCSS.000-1, 8BVI0660HWSS.000-1, 8BVI0660HCSA.000-1, 8BVI0660HWSA.000-1 - Technical data

Model number	8BVI0660HCSS.000-1	8BVI0660HWSS.000-1	8BVI0660HCSA.000-1	8BVI0660HWSA.000-1
Input capacitance	32.9 µF			
Max. power consumption	33 W + P_{SMC1} + P_{SLOT2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake}$ 5)		25 W + P_{SMC1} + P_{SLOT2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake}$ 6)	
Variant	ACOPOSmulti backplane			
24 VDC output				
Quantity	2			
Output voltage				
DC bus voltage (U_{DC}): 260 to 315 VDC	25 VDC * (U_{DC}/315)			
DC bus voltage (U_{DC}): 315 to 800 VDC	24 VDC ±6%			
Fuse protection	250 mA (slow-blow) electronic, automatic reset			
Motor connection 7)				
Quantity	1			
Continuous power per motor connection 3)	48 kW			
Continuous current per motor connection 3)	66 A_{eff}			
Reduction of continuous current depending on switching frequency 8)				
Switching frequency 5 kHz	-	1.4 A/K (starting at 41°C) 9)	-	1.4 A/K (starting at 41°C) 9)
Switching frequency 10 kHz	-	0.92 A/K (starting at -5°C) 10)	-	0.92 A/K (starting at -5°C) 10)
Switching frequency 20 kHz	-	0.56 A/K (starting at -90°C) 10)	-	0.56 A/K (starting at -90°C) 10)
Reduction of continuous current depending on switching frequency and mounting type 11)				
Switching frequency 5 kHz				
Cold plate mounting 12)	1.9 A/K (starting at 58°C) 9)	-	1.9 A/K (starting at 58°C) 9)	-
Feed-through mounting	1.82 A/K (starting at 40°C) 9)	-	1.82 A/K (starting at 40°C) 9)	-
Switching frequency 10 kHz				
Cold plate mounting 12)	1.36 A/K (starting at 27°C) 13)	-	1.36 A/K (starting at 27°C) 13)	-
Feed-through mounting	0.88 A/K (starting at -12°C) 10)	-	0.88 A/K (starting at -12°C) 10)	-
Switching frequency 20 kHz				
Cold plate mounting 12)	0.75 A/K (starting at -37°C) 13)	-	0.75 A/K (starting at -37°C) 13)	-
Feed-through mounting	0.54 A/K (starting at -106°C) 10)	-	0.54 A/K (starting at -106°C) 10)	-
Reduction of continuous current depending on installation elevation				
Starting at 500 m above sea level	6.6 A_{eff} per 1000 m			
Peak current	132 A_{eff}			
Nominal switching frequency	5 kHz			
Possible switching frequencies 14)	5 / 10 / 20 kHz			
Electrical stress of connected motor per IEC TS 60034-25 15)	Limit value curve A			
Protective measures				
Overload protection	Yes			
Short circuit and ground fault protection	Yes			
Max. output frequency	598 Hz 16)			
Variant				
U, V, W, PE	M8 threaded bolt			
Shield connection	Yes			
Connection cross section range				
Flexible and fine-stranded wires	--- 17)			
Terminal cable cross section dimension of shield connection	12 to 50 mm 18)			
Max. motor cable length depending on switching frequency				
Switching frequency 5 kHz	25 m			
Switching frequency 10 kHz	25 m			
Switching frequency 20 kHz	25 m			
Motor holding brake connection				
Quantity	1			
Output voltage 19)	24 VDC +5.8% / -0.5% 20)			
Continuous current	4.2 A			
Max. internal resistance	0.15 Ω			
Extinction potential	Approx. 30 V			
Max. extinction energy per switching operation	3 Ws			
Max. switching frequency	0.5 Hz			

Table 63: 8BVI0660HCSS.000-1, 8BVI0660HWSS.000-1, 8BVI0660HCSA.000-1, 8BVI0660HWSA.000-1 - Technical data

Model number	8BVI0660HCSS.000-1	8BVI0660HWSS.000-1	8BVI0660HCSA.000-1	8BVI0660HWSA.000-1
Protective measures				
Overload and short-circuit protection	Yes			
Open circuit monitoring	Yes			
Undervoltage monitoring	Yes			
Response threshold for open circuit monitoring	Approx. 0.5 A			
Response threshold for undervoltage monitoring	24 VDC -2% / -4%			
Encoder interfaces [21)]				
Quantity	1			
Type	EnDat 2.2 [22)]		SinCos	
Connections	9-pin female DSUB connector		15-pin female DSUB connector	
Status indicators	UP/DN LEDs			
Electrical isolation				
Encoder - ACOPOSmulti	No			
Encoder monitoring	Yes			
Max. encoder cable length	100 m Depends on the cross section of the power supply wires of the encoder cable [23)]		50 m [24)]	
Encoder power supply				
Output voltage	Typ. 12.5 V		5 V ±5% [25)]	
Load capacity	350 mA		300 mA [26)]	
Sense lines	-		2, compensation of max. 2 x 0.7 V	
Protective measures				
Short-circuit proof	Yes			
Overload-proof	Yes			
Synchronous serial interface				
Signal transmission	RS485			
Data transfer rate	6.25 Mbit/s		781.25 kbit/s	
Sine/Cosine inputs				
Signal transmission	-		Differential signals, symmetrical	
Differential voltage				
In motion	-		0.5 to 1.35 V [27)]	
At standstill	-		0.8 to 1.35 V [28)]	
Differential voltage deviation per signal period	-		±10% [29)]	
Common-mode voltage	-		Max. ±7 V	
Terminating resistor	-		120 Ω	
Max. input frequency	-		200 kHz	
Signal frequency (-5 dB)	-		<300 kHz	
Signal frequency (-3 dB)	-		DC up to 200 kHz	
ADC resolution	-		12-bit	
Reference input				
Signal transmission	-		Differential signal, symmetrical	
Differential voltage for low	-		≤-0.2 V	
Differential voltage for high	-		≥0.2 V	
Common-mode voltage	-		Max. -5 V to +9 V	
Terminating resistor	-		120 Ω	
Position				
Resolution @ 1 V_{SS} [30)]	-		Number of encoder lines * 5700	
Accuracy [31)]	-		---	
Noise [31)]	-		---	
Max. power consumption per encoder interface	P_{SMC}[W] = 19 V * $I_{Encoder}$[A] [32)]		P_{SMC}[W] = 25 V * (0.376 A + 0.35 * $I_{Encoder}$[A]) [32)]	
Trigger inputs				
Quantity	2			
Circuit	Sink			
Electrical isolation				
Input - Inverter module	Yes			
Input - Input	Yes			
Input voltage				
Nominal	24 VDC			
Maximum	30 VDC			
Switching threshold				
Low	<5 V			
High	>15 V			
Input current at nominal voltage	Approx. 10 mA			
Switching delay				
Rising edge	52 µs ±0.5 µs (digitally filtered)			
Falling edge	53 µs ±0.5 µs (digitally filtered)			
Modulation compared to ground potential	Max. ±38 V			

Table 63: 8BVI0660HCSS.000-1, 8BVI0660HWSS.000-1, 8BVI0660HCSA.000-1, 8BVI0660HWSA.000-1 - Technical data

Model number	8BVI0660HCSS.000-1	8BVI0660HWSS.000-1	8BVI0660HCSA.000-1	8BVI0660HWSA.000-1
Electrical properties				
Discharge capacitance	0.44 µF			
Operating conditions				
Permissible mounting orientations				
Hanging vertically	Yes			
Horizontal, face up	Yes			
Standing horizontally	No			
Installation elevation above sea level				
Nominal	0 to 500 m			
Maximum [33]	4000 m			
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)			
Overvoltage category per EN 61800-5-1	III			
Degree of protection per EN 60529	IP20 [34]			
Ambient conditions				
Temperature				
Operation				
Nominal	5 to 40°C			
Maximum [35]	55°C			
Storage	-25 to 55°C			
Transport	-25 to 70°C			
Relative humidity				
Operation	5 to 85%			
Storage	5 to 95%			
Transport	Max. 95% at 40°C			
Mechanical properties				
Dimensions [36]				
Width	213.5 mm			
Height	317 mm			
Depth				
Wall mounting	-	263 mm	-	263 mm
Cold plate	212 mm	-	212 mm	-
Feed-through mounting	209 mm	-	209 mm	-
Weight	Approx. 8 kg	Approx. 10.2 kg	Approx. 8 kg	Approx. 10.9 kg
Module width	4			

Table 63: 8BVI0660HCSS.000-1, 8BVI0660HWSS.000-1, 8BVI0660HCSA.000-1, 8BVI0660HWSA.000-1 - Technical data

1) SLOT 2 is available. SLOT 1 of the ACOPOSmulti module is occupied by the SafeMOTION module.
2) Achievable safety classifications (safety integrity level, safety category, performance level) are documented in the user's manual (section "Safety technology").
3) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
4) I_M ... Current on motor connection X5A [A_{eff}]
5) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
$P_{24\ V\ Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
6) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
$P_{24\ V\ Out}$ ... Power [W] that is output to the connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
7) Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.
8) Valid in the following conditions: 750 VDC DC bus voltage. The temperature specifications refer to the ambient temperature.
9) Value for the nominal switching frequency.
10) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
11) Valid for the following conditions: 750 VDC DC bus voltage, minimum permissible coolant flow volume (3 l/min).
12) The temperature specifications refer to the return temperature of the cold plate mounting plate.
13) The module cannot supply the full continuous current at this switching frequency. This unusual value for the return temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
Caution! Condensation can occur at low flow temperatures and return temperatures.
14) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
15) If necessary, the stress of the motor isolation system can be reduced by an additional externally wired dv/dt choke. For example, the RWK 305 three-phase du/dt choke from Schaffner (www.schaffner.com) can be used. Important: Even when using a dv/dt choke, it is necessary to ensure that an EMC-compatible, low inductance shield connection is used!
16) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
17) The connection is made with cable lugs for M8 (0.32") threaded bolts. The nominal cross section of the cable lug must match the cross section of the conductor that is to be connected in the particular application.
18) The maximum diameter that can be clamped depends on the shield component set.
19) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.

20) The specified value is only valid under the following conditions:
- The 24 VDC supply for the module is provided by an 8B0C auxiliary supply module installed on the same mounting plate.
- Connection between S1 and S2 (activation of the external holding brake) using a jumper with a max. length of 10 cm.
If the 24 VDC supply for the module is applied to the mounting plate using an 8BVE expansion module, then the output voltage is reduced because of voltage drops on the expansion cable. In this case, undervoltage monitoring must be disabled.
If jumpers longer than 10 cm are used to connect S1 and S2, then the output voltage is reduced because of voltage drops on the jumpers.
21) Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.
22) An EnDat 2.2 functional safety encoder is required when using ACOPOSmulti SafeMOTION inverter modules! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!
23) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 100 m is not permitted to be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A]
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
24) The maximum permissible cable length is 50 m.
25) During the power-on procedure for the encoder power supply voltage (2 seconds), the monitoring limit for the supply voltage is increased from 5.25 V to 6 V. In this phase, overvoltages up to 6 V are not detected.
A short-term overvoltage of maximum 6 V is not permitted to damage the encoder electronics in any way.
An undervoltage on the encoder power supply will result in a sine or cosine signal outside the specification.
26) An actual reserve of 12 mA exists for the terminating resistor.
27) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length z = 2 √((Sin - nSin)² + (Cos - nCos)²) is monitored according to the specified limits.
28) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length z = 2 √((Sin - nSin)² + (Cos - nCos)²) is also monitored according to the specified limits from the time the evaluation circuit is switched on until a signal period has passed.
29) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length z = 2 √((Sin - nSin)² + (Cos - nCos)²) is permitted to deviate by a maximum of ±10% per signal period.
30) This value does not correspond to the encoder resolution that must be configured in Automation Studio (16384 * number of encoder lines).
31) Limited by the encoder in practice.
32) $I_{Encoder}$ ... Max. power consumption of the connected encoder [A].
33) Continuous operation at elevations ranging from 500 m to 4,000 m above sea level is possible (taking the specified continuous current reductions into consideration).
34) This value only applies in its delivered state (SLOT2 of the module is sealed by a slot cover / shield plate). If SLOT2 on the module is not sealed, then the level of protection is reduced to IP10. It is important to note that a 8SCS005.0000-00 shield set (slot cover / shield plate) or plug-in module must always be inserted!
35) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous current reductions into consideration), but this will result in a shorter service life.
36) These dimensions refer to the actual device dimensions including the respective mounting plate. Make sure to leave additional space above and below the devices for mounting, connections and air circulation.

2.3.6.1.4 Wiring

For details, see section 2.3.6.3 "Wiring: Safe 4x width inverter modules (1-axis modules)" on page 130.

For general information, see section 2.6 "Wiring" on page 150.

2.3.6.2 8BVI0880HCSS.004-1, 8BVI0880HWSS.004-1, 8BVI0880HCSA.004-1, 8BVI0880HWSA.004-1

2.3.6.2.1 General information

- Clearly structured, straightforward implementation via network-based safety technology
- Modular expandability through virtual wiring
- Immediate triggering of safety function due to short cycle times
- Easy implementation with transparent control and status information, even in the standard application
- Compact design

2.3.6.2.2 Order data

Model number	Short description	Figure
	Cold plate or feed-through mounting	
8BVI0880HCSS.004-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 88 A, HV, cold plate or feed-through mounting	
8BVI0880HCSA.004-1	ACOPOSmulti SafeMOTION SinCos inverter module, 88 A, HV, cold plate or feed-through mounting	
	Wall mounting	
8BVI0880HWSS.004-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 88 A, HV, wall mounting	
8BVI0880HWSA.004-1	ACOPOSmulti SafeMOTION SinCos inverter module, 88 A, HV, wall mounting	
	Required accessories	
	Terminal block sets	
8BZVI1650SS.000-1A	Screw clamp terminal block set for ACOPOSmulti 8BVI0660HxSS, 8BVI0880HxSS, 8BVI1650HxSS, 8BVI0660HxSA, 8BVI0880HxSA and 8BVI1650HxSA modules: 1x 8TB2104.203L-00, 1x 8TB2108.2010-00	
	Optional accessories	
	Accessory sets	
8BXB000.0000-00	ACOPOSmulti accessory set for encoder buffering consists of the following: 1 lithium battery AA 3.6 V, 1 cover for battery compartment	
	Fan modules	
8BXF001.0000-00	ACOPOSmulti fan module, replacement fan for ACOPOSmulti modules (8BxP/8B0C/8BVI/8BVE/8B0K)	
	POWERLINK/Ethernet cables	
X20CA0E61.00020	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.2 m	
X20CA0E61.00025	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.25 m	
X20CA0E61.00030	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.3 m	
X20CA0E61.00035	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.35 m	
X20CA0E61.00050	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.5 m	
X20CA0E61.00100	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 1 m	
	Plug-in modules	
8BAC0120.000-1	ACOPOSmulti plug-in module, EnDat 2.1 interface	
8BAC0120.001-2	ACOPOSmulti plug-in module, EnDat 2.2 interface	
8BAC0121.000-1	ACOPOSmulti plug-in module, HIPERFACE interface	
8BAC0122.000-1	ACOPOSmulti plug-in module, resolver interface 10 kHz	
8BAC0123.000-1	ACOPOSmulti plug-in module, incremental encoder and SSI absolute encoder interface for RS422 signals	
8BAC0123.001-1	ACOPOSmulti plug-in module, incremental encoder interface for 5 V single-ended and 5 V differential signals	
8BAC0123.002-1	ACOPOSmulti plug-in module, incremental encoder interface for 24 V single-ended and 24 V differential signals	
8BAC0124.000-1	ACOPOSmulti plug-in module, SinCos interface	
8BAC0125.000-1	ACOPOSmulti plug-in module, SinCos EnDat 2.1/SSI/BiSS interface	
8BAC0130.000-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 2 digital outputs, 500 mA, max. 1.25 kHz, 2 digital inputs 24 VDC	
8BAC0130.001-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 4 digital outputs, 500 mA, max. 1.25 kHz	
8BAC0132.000-1	ACOPOSmulti plug-in module, 4 analog inputs ±10 V	
8BAC0133.000-1	ACOPOSmulti plug-in module, 3 RS422 outputs for ABR encoder emulation, 1 MHz	
	Shield component sets	
8SCS001.0000-00	ACOPOSmulti shield component set: 1x shield plate 4x type 1, 1x hose clamp, B 9 mm, D 12-22 mm	
8SCS002.0000-00	ACOPOSmulti shield component set: 1x clamping plate; 2x clamps D 4-13.5 mm; 4x screws	
8SCS003.0000-00	ACOPOSmulti shield component set: 1x shield mounting plate 4x 45°, 8x screws	
8SCS004.0000-00	ACOPOSmulti shield component set: 1x shield plate 4x type 0, 2x hose clamps, B 9 mm, D 32-50 mm	
8SCS010.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK14-20, 1x shield connection clamp SK20	
	Terminal blocks	
8TB2104.203L-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, L keying: 1010	
8TB2106.2010-00	6-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	
8TB2106.2210-00	Push-in terminal block 6-pin, 1-row, spacing: 5.08 mm, label 1: numbered consecutively	
8TB2108.2010-00	8-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	

Table 64: 8BVI0880HCSS.004-1, 8BVI0880HCSA.004-1, 8BVI0880HWSS.004-1, 8BVI0880HWSA.004-1 - Order data

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

ACOPOSmulti SafeMOTION SinCos

Information:

Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.

Information:

Only 8BCS encoder cables from B&R are permitted to be connected to the encoder interfaces on B&R standard motors.

For details, see 6.1.2 "Safe power transmission system " on page 283.

2.3.6.2.3 Technical data

Model number	8BVI0880HCSS.004-1	8BVI0880HWSS.004-1	8BVI0880HCSA.004-1	8BVI0880HWSA.004-1
General information				
B&R ID code	0xB450	0xB451	0xDD1E	0xE0BA
Cooling and mounting type	Cold plate or feed-through mounting	Wall mounting	Cold plate or feed-through mounting	Wall mounting
Slots for plug-in modules	2 [1]			
Certifications				
CE	Yes			
Functional safety[2]	Yes (openSAFETY)			
UL	cULus E225616 Power conversion equipment			
EAC	Yes			
KC	Yes		-	
DC bus connection				
Voltage				
Nominal	750 VDC			
Continuous power consumption [3]	65 kW			
Power dissipation depending on switching frequency [4]				
Switching frequency 5 kHz	$[0.03 * I_M^2 + 7.9 * I_M + 90]$ W			
Switching frequency 10 kHz	$[0.11 * I_M^2 + 11 * I_M + 185]$ W			
Switching frequency 20 kHz	$[0.17 * I_M^2 + 27 * I_M + 310]$ W			
DC bus capacitance	1980 µF			
Variant	ACOPOSmulti backplane			
24 VDC power supply				
Input voltage	25 VDC ±1.6%			
Input capacitance	32.9 µF			
Max. power consumption	33 W + P_{SMC1} + P_{SLOT2} + $P_{24\,V\,Out}$ + $P_{HoldingBrake}$ [5]		25 W + P_{SMC1} + P_{SLOT2} + $P_{24\,V\,Out}$ + $P_{HoldingBrake}$ [6]	
Variant	ACOPOSmulti backplane			
24 VDC output				
Quantity	2			
Output voltage				
DC bus voltage (U_{DC}): 260 to 315 VDC	25 VDC * (U_{DC}/315)			
DC bus voltage (U_{DC}): 315 to 800 VDC	24 VDC ±6%			
Fuse protection	250 mA (slow-blow) electronic, automatic reset			
Motor connection [7]				
Quantity	1			
Continuous power per motor connection [3]	64 kW			
Continuous current per motor connection [3]	88 A_{eff}			

Table 65: 8BVI0880HCSS.004-1, 8BVI0880HWSS.004-1, 8BVI0880HCSA.004-1, 8BVI0880HWSA.004-1 - Technical data

Model number	8BVI0880HCSS.004-1	8BVI0880HWSS.004-1	8BVI0880HCSA.004-1	8BVI0880HWSA.004-1
Reduction of continuous current depending on switching frequency [8]				
Switching frequency 5 kHz	-	1.4 A/K (starting at 41°C) [9]	-	1.4 A/K (starting at 41°C) [9]
Switching frequency 10 kHz	-	0.92 A/K (starting at -5°C) [10]	-	0.92 A/K (starting at -5°C) [10]
Switching frequency 20 kHz	-	0.56 A/K (starting at -90°C) [10]	-	0.56 A/K (starting at -90°C) [10]
Reduction of continuous current depending on switching frequency and mounting type [11]				
Switching frequency 5 kHz				
Cold plate mounting [12]	1.9 A/K (starting at 58°C) [9]	-	1.9 A/K (starting at 58°C) [9]	-
Feed-through mounting	1.82 A/K (starting at 40°C) [9]	-	1.82 A/K (starting at 40°C) [9]	-
Switching frequency 10 kHz				
Cold plate mounting [12]	1.36 A/K (starting at 27°C) [13]	-	1.36 A/K (starting at 27°C) [13]	-
Feed-through mounting	0.88 A/K (starting at -12°C) [10]	-	0.88 A/K (starting at -12°C) [10]	-
Switching frequency 20 kHz				
Cold plate mounting [12]	0.75 A/K (starting at -37°C) [13]	-	0.75 A/K (starting at -37°C) [13]	-
Feed-through mounting	0.54 A/K (starting at -106°C) [10]	-	0.54 A/K (starting at -106°C) [10]	-
Reduction of continuous current depending on installation elevation				
Starting at 500 m above sea level	8.8 A_{eff} per 1000 m			
Peak current	176 A_{eff}			
Nominal switching frequency	5 kHz			
Possible switching frequencies [14]	5 / 10 / 20 kHz			
Electrical stress of connected motor per IEC TS 60034-25 [15]	Limit value curve A			
Protective measures				
Overload protection	Yes			
Short circuit and ground fault protection	Yes			
Max. output frequency	598 Hz [16]			
Variant				
U, V, W, PE	M8 threaded bolt			
Shield connection	Yes			
Connection cross section range				
Flexible and fine-stranded wires	--- [17]			
Terminal cable cross section dimension of shield connection	12 to 50 mm [18]			
Max. motor cable length depending on switching frequency				
Switching frequency 5 kHz	25 m			
Switching frequency 10 kHz	25 m			
Switching frequency 20 kHz	25 m			
Motor holding brake connection				
Quantity	1			
Output voltage [19]	24 VDC +5.8% / -0.5% [20]			
Continuous current	4.2 A			
Max. internal resistance	0.15 Ω			
Extinction potential	Approx. 30 V			
Max. extinction energy per switching operation	3 Ws			
Max. switching frequency	0.5 Hz			
Protective measures				
Overload and short-circuit protection	Yes			
Open circuit monitoring	Yes			
Undervoltage monitoring	Yes			
Response threshold for open circuit monitoring	Approx. 0.5 A			
Response threshold for undervoltage monitoring	24 VDC -2% / -4%			
Encoder interfaces [21]				
Quantity	1			
Type	EnDat 2.2 [22]		SinCos	
Connections	9-pin female DSUB connector		15-pin female DSUB connector	
Status indicators	UP/DN LEDs			
Electrical isolation				
Encoder - ACOPOSmulti	No			
Encoder monitoring	Yes			

Table 65: 8BVI0880HCSS.004-1, 8BVI0880HWSS.004-1, 8BVI0880HCSA.004-1, 8BVI0880HWSA.004-1 - Technical data

Model number	8BVI0880HCSS.004-1	8BVI0880HWSS.004-1	8BVI0880HCSA.004-1	8BVI0880HWSA.004-1
Max. encoder cable length	100 m Depends on the cross section of the power supply wires of the encoder cable [23]		50 m [24]	
Encoder power supply				
Output voltage	Typ. 12.5 V		5 V ±5% [25]	
Load capacity	350 mA		300 mA [26]	
Sense lines	-		2, compensation of max. 2 x 0.7 V	
Protective measures				
Short-circuit proof	Yes			
Overload-proof	Yes			
Synchronous serial interface				
Signal transmission	RS485			
Data transfer rate	6.25 Mbit/s		781.25 kbit/s	
Sine/Cosine inputs				
Signal transmission	-		Differential signals, symmetrical	
Differential voltage				
In motion	-		0.5 to 1.35 V [27]	
At standstill	-		0.8 to 1.35 V [28]	
Differential voltage deviation per signal period	-		±10% [29]	
Common-mode voltage	-		Max. ±7 V	
Terminating resistor	-		120 Ω	
Max. input frequency	-		200 kHz	
Signal frequency (-5 dB)	-		<300 kHz	
Signal frequency (-3 dB)	-		DC up to 200 kHz	
ADC resolution	-		12-bit	
Reference input				
Signal transmission	-		Differential signal, symmetrical	
Differential voltage for low	-		≤-0.2 V	
Differential voltage for high	-		≥0.2 V	
Common-mode voltage	-		Max. -5 V to +9 V	
Terminating resistor	-		120 Ω	
Position				
Resolution @ 1 V_{SS} [30]	-		Number of encoder lines * 5700	
Accuracy [31]	-		---	
Noise [31]	-		---	
Max. power consumption per encoder interface	P_{SMC}[W] = 19 V * $I_{Encoder}$[A] [32]		P_{SMC}[W] = 25 V * (0.376 A + 0.35 * $I_{Encoder}$[A]) [32]	
Trigger inputs				
Quantity	2			
Circuit	Sink			
Electrical isolation				
Input - Inverter module	Yes			
Input - Input	Yes			
Input voltage				
Nominal	24 VDC			
Maximum	30 VDC			
Switching threshold				
Low	<5 V			
High	>15 V			
Input current at nominal voltage	Approx. 10 mA			
Switching delay				
Rising edge	52 µs ±0.5 µs (digitally filtered)			
Falling edge	53 µs ±0.5 µs (digitally filtered)			
Modulation compared to ground potential	Max. ±38 V			
Electrical properties				
Discharge capacitance	0.44 µF			
Operating conditions				
Permissible mounting orientations				
Hanging vertically	Yes			
Horizontal, face up	Yes			
Standing horizontally	No			
Installation elevation above sea level				
Nominal	0 to 500 m			
Maximum [33]	4000 m			
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)			
Overvoltage category per EN 61800-5-1	III			
Degree of protection per EN 60529	IP20 [34]			

Table 65: 8BVI0880HCSS.004-1, 8BVI0880HWSS.004-1, 8BVI0880HCSA.004-1, 8BVI0880HWSA.004-1 - Technical data

Model number	8BVI0880HCSS.004-1	8BVI0880HWSS.004-1	8BVI0880HCSA.004-1	8BVI0880HWSA.004-1
Ambient conditions				
Temperature				
Operation				
Nominal	5 to 40°C			
Maximum 35)	55°C			
Storage	-25 to 55°C			
Transport	-25 to 70°C			
Relative humidity				
Operation	5 to 85%			
Storage	5 to 95%			
Transport	Max. 95% at 40°C			
Mechanical properties				
Dimensions 36)				
Width	213.5 mm			
Height	317 mm			
Depth				
Wall mounting	-	263 mm	-	263 mm
Cold plate	212 mm	-	212 mm	-
Feed-through mounting	209 mm	-	209 mm	-
Weight	Approx. 8 kg	Approx. 10.2 kg	Approx. 8 kg	Approx. 10.9 kg
Module width	4			

Table 65: 8BVI0880HCSS.004-1, 8BVI0880HWSS.004-1, 8BVI0880HCSA.004-1, 8BVI0880HWSA.004-1 - Technical data

1) SLOT 2 is available. SLOT 1 of the ACOPOSmulti module is occupied by the SafeMOTION module.
2) Achievable safety classifications (safety integrity level, safety category, performance level) are documented in the user's manual (section "Safety technology").
3) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
4) I_M ... Current on motor connection X5A [A_{eff}]
5) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
$P_{24\,V\,Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
6) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
$P_{24\,V\,Out}$ ... Power [W] that is output to the connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
7) Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.
8) Valid in the following conditions: 750 VDC DC bus voltage. The temperature specifications refer to the ambient temperature.
9) Value for the nominal switching frequency.
10) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
11) Valid for the following conditions: 750 VDC DC bus voltage, minimum permissible coolant flow volume (3 l/min).
12) The temperature specifications refer to the return temperature of the cold plate mounting plate.
13) The module cannot supply the full continuous current at this switching frequency. This unusual value for the return temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
Caution! Condensation can occur at low flow temperatures and return temperatures.
14) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
15) If necessary, the stress of the motor isolation system can be reduced by an additional externally wired dv/dt choke. For example, the RWK 305 three-phase du/dt choke from Schaffner (www.schaffner.com) can be used. Important: Even when using a dv/dt choke, it is necessary to ensure that an EMC-compatible, low inductance shield connection is used!
16) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
17) The connection is made with cable lugs for M8 (0.32") threaded bolts. The nominal cross section of the cable lug must match the cross section of the conductor that is to be connected in the particular application.
18) The maximum diameter that can be clamped depends on the shield component set.
19) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
20) The specified value is only valid under the following conditions:
- The 24 VDC supply for the module is provided by an 8B0C auxiliary supply module installed on the same mounting plate.
- Connection between S1 and S2 (activation of the external holding brake) using a jumper with a max. length of 10 cm.
If the 24 VDC supply for the module is applied to the mounting plate using an 8BVE expansion module, then the output voltage is reduced because of voltage drops on the expansion cable. In this case, undervoltage monitoring must be disabled.
If jumpers longer than 10 cm are used to connect S1 and S2, then the output voltage is reduced because of voltage drops on the jumpers.
21) Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.
22) An EnDat 2.2 functional safety encoder is required when using ACOPOSmulti SafeMOTION inverter modules! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!
23) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 100 m is not permitted to be exceeded):

$l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

I_G ... Max. current consumption of the encoder [A].
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
24) The maximum permissible cable length is 50 m.

25) During the power-on procedure for the encoder power supply voltage (2 seconds), the monitoring limit for the supply voltage is increased from 5.25 V to 6 V. In this phase, overvoltages up to 6 V are not detected.
A short-term overvoltage of maximum 6 V is not permitted to damage the encoder electronics in any way.
An undervoltage on the encoder power supply will result in a sine or cosine signal outside the specification.
26) An actual reserve of 12 mA exists for the terminating resistor.
27) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2 \sqrt{(\mathrm{Sin} - \mathrm{nSin})^2 + (\mathrm{Cos} - \mathrm{nCos})^2}$ is monitored according to the specified limits.
28) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2 \sqrt{(\mathrm{Sin} - \mathrm{nSin})^2 + (\mathrm{Cos} - \mathrm{nCos})^2}$ is also monitored according to the specified limits from the time the evaluation circuit is switched on until a signal period has passed.
29) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2 \sqrt{(\mathrm{Sin} - \mathrm{nSin})^2 + (\mathrm{Cos} - \mathrm{nCos})^2}$ is permitted to deviate by a maximum of ±10% per signal period.
30) This value does not correspond to the encoder resolution that must be configured in Automation Studio (16384 * number of encoder lines).
31) Limited by the encoder in practice.
32) $I_{Encoder}$ ... Max. power consumption of the connected encoder [A].
33) Continuous operation at elevations ranging from 500 m to 4,000 m above sea level is possible (taking the specified continuous current reductions into consideration).
34) This value only applies in its delivered state (SLOT2 of the module is sealed by a slot cover / shield plate). If SLOT2 on the module is not sealed, then the level of protection is reduced to IP10. It is important to note that a 8SCS005.0000-00 shield set (slot cover / shield plate) or plug-in module must always be inserted!
35) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous current reductions into consideration), but this will result in a shorter service life.
36) These dimensions refer to the actual device dimensions including the respective mounting plate. Make sure to leave additional space above and below the devices for mounting, connections and air circulation.

2.3.6.2.4 Wiring

For details, see section 2.3.6.3 "Wiring: Safe 4x width inverter modules (1-axis modules)" on page 130.

For general information, see section 2.6 "Wiring" on page 150.

2.3.6.3 Wiring: Safe 4x width inverter modules (1-axis modules)

2.3.6.3.1 ACOPOSmulti SafeMOTION EnDat 2.2 - Pinout overview

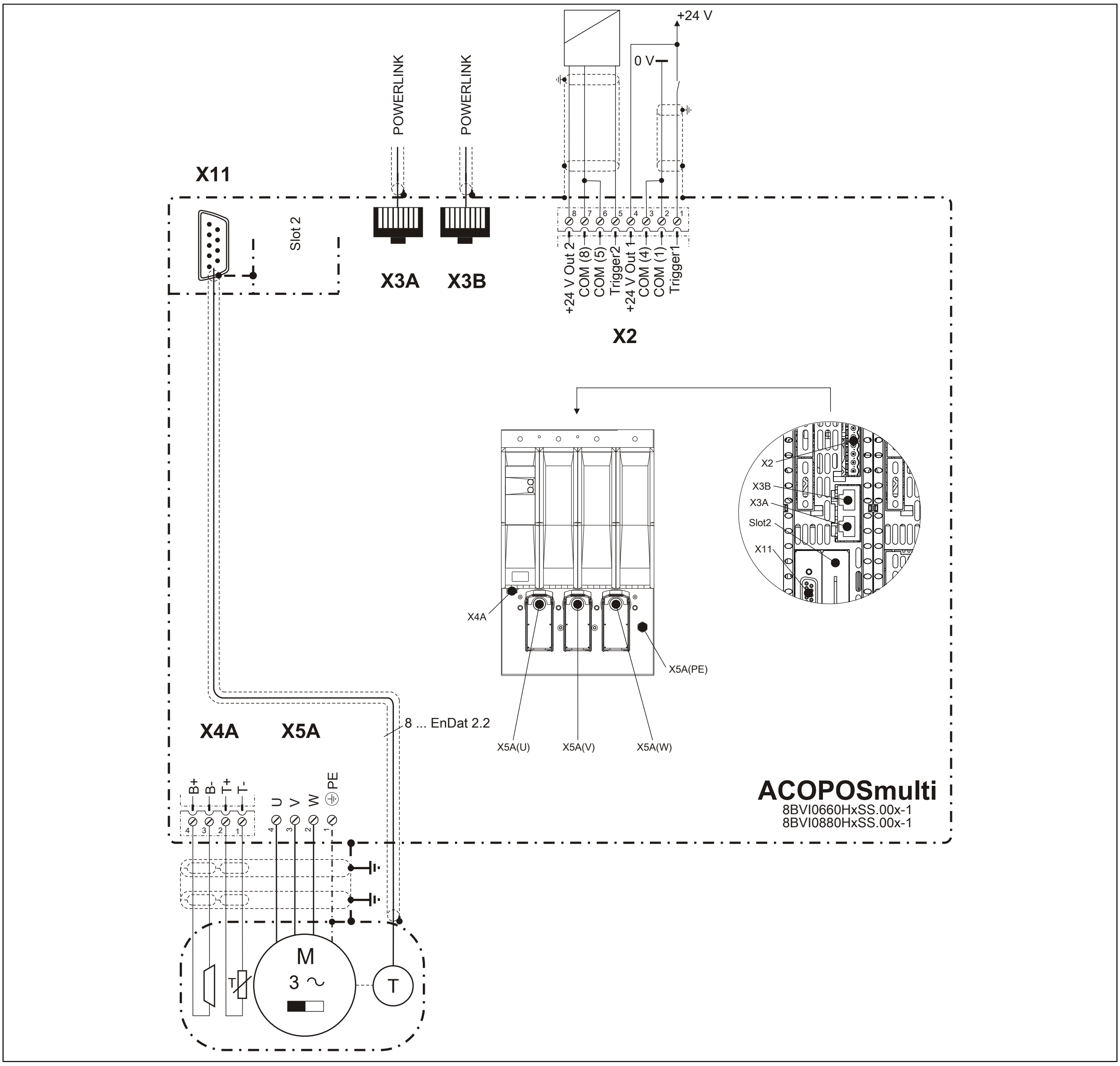


Figure 12: Pinout overview

2.3.6.3.2 ACOPOSmulti SafeMOTION SinCos - Pinout overview

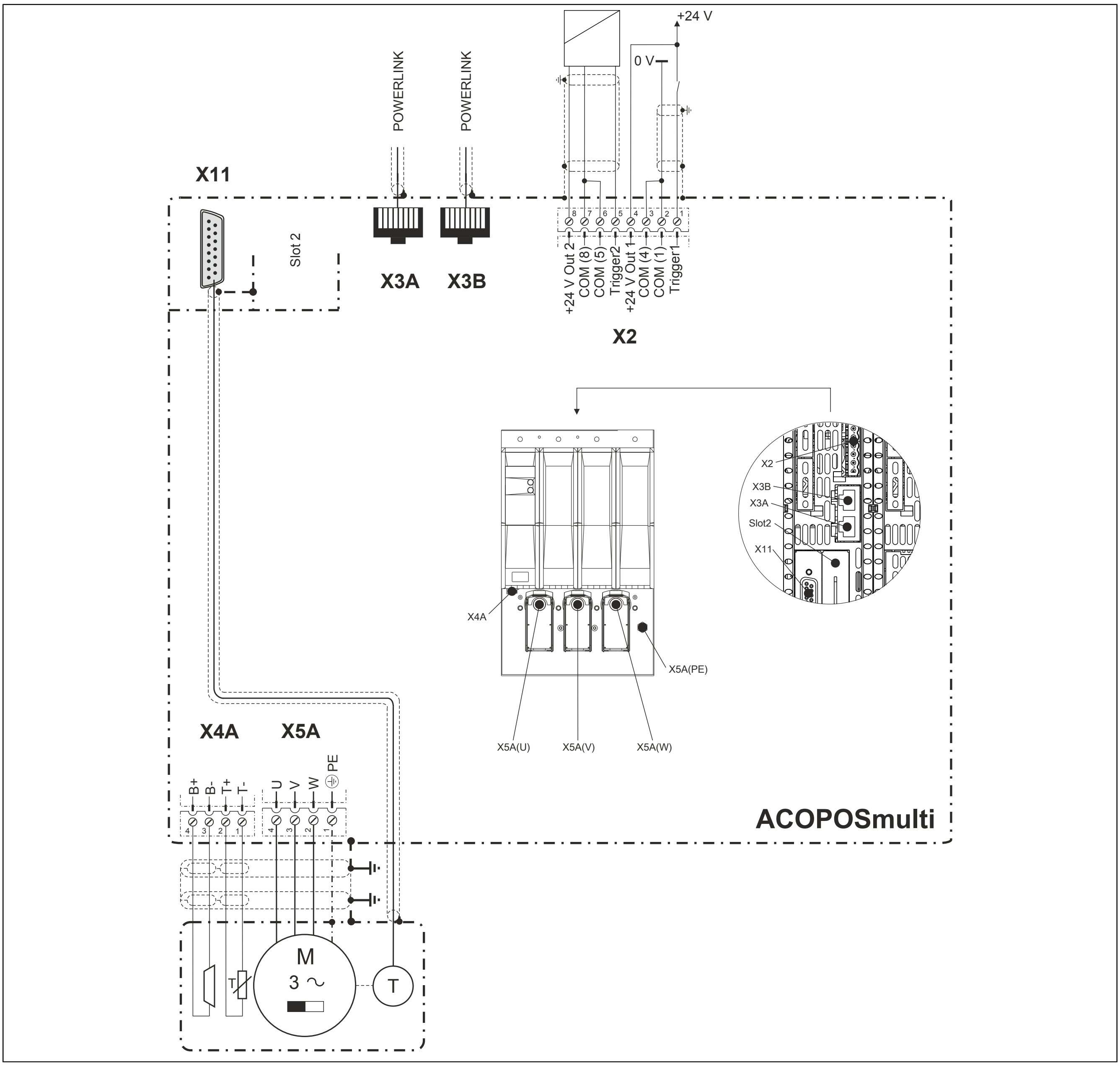


Figure 13: Pinout overview

2.3.6.3.3 Connector X2 - Pinout

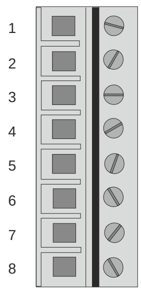
X2	Pin	Description	Function
	1	Trigger 1	Trigger 1
	2	COM (1)	Trigger 1 0 V
	3	COM (2)	+24 V output 1 0 V
	4	+24 V Out 1	+24 V output 1
	5	Trigger 2	Trigger 2
	6	COM (5)	Trigger 2 0 V
	7	COM (8)	+24 V output 2 0 V
	8	+24 V Out 2	+24 V output 2

Table 66: Connector X2 - Pinout

2.3.6.3.4 Connectors X3A, X3B - Pinout

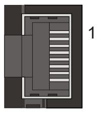
X3A, X3B	Pin	Description	Function
	1	RXD	Receive signal
	2	RXD\	Receive signal inverted
	3	TXD	Transmit signal
	4	Shield	Shield
	5	Shield	Shield
	6	TXD\	Transmit signal inverted
	7	Shield	Shield
	8	Shield	Shield

Table 67: X3A, X3B connectors - Pinout

2.3.6.3.5 X4A connector - Pinout

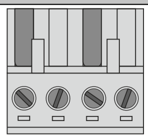
X4A	Description	Function
	T-	Axis 1: Temperature sensor -
	T+	Axis 1: Temperature sensor +
	B-	Axis 1: Brake -
	B+	Axis 1: Brake +

Table 68: Connector X4A - Pinout

Danger!

A short circuit of SBC output B+ against 24 V results in state FUNCTIONAL FAIL SAFE being enabled. This means that safe pulse disabling is enabled. The brake always remains switched on / released, however, due to the short circuit to 24 V!
This can lead to dangerous situations since the motor holding brake cannot brake, prevent the spin-out movement or prevent the unbraked lowering movement when loads are suspended!
A short circuit of SBC output B+ against 24 V must be prevented by suitable wiring measures!

Danger!

The following applies to the SBC output:

- **It is not permitted to be wired across modules!**
- **It is not permitted to be wired as an open emitter!**
- **It is not permitted to be wired as an open collector!**

Danger!

Only an output voltage of ≤ 5 V can be ensured for the safe motor holding brake output when switched off. When selecting the motor holding brake, the user must ensure that the required braking torque is achieved with a voltage of 5 V applied.

Information:

The transistors of the SBC output stage are tested cyclically. When the output channels are active, this test emits low pulses on the output with a maximum length of 600 µs.

This must be taken into consideration when choosing the motor holding brake!

Danger!

The connections for the motor temperature sensors and the motor holding brake are safely isolated circuits. These connections are therefore only permitted to be connected to devices or components that have sufficient isolation per IEC 60364-4-41 or EN 61800-5-1.

Caution!

If B+ and B- are swapped when connecting the permanent magnet holding brakes, then the brakes cannot be opened! ACOPOSmulti inverter modules cannot determine if a holding brake is connected with reverse polarity!

Warning!

Temperature sensors are only permitted to be connected to the X4A/T+ and X4A/T- connectors on an ACOPOSmulti module under the following conditions:

- **SLOT1 of the ACOPOSmulti module does not contain an ACOPOSmulti plug-in module to which a temperature sensor is connected on the T+ and T- connections.**

Otherwise, the temperature monitoring functions on the ACOPOSmulti module may become ineffective, which in extreme cases can cause the hardware (e.g. motors) connected to the ACOPOSmulti module to be destroyed!

2.3.6.3.6 X5A - Pinout

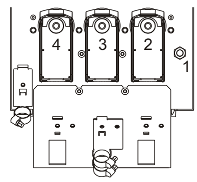
X5A	Name	Function
	1	Axis 1: Protective ground conductor
	2	Axis 1: Motor connection W
	3	Axis 1: Motor connection V
	4	Axis 1: Motor connection U

Table 69: X5A - Pinout

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

ACOPOSmulti SafeMOTION SinCos

Information:

Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.

Motor connections U, V, W - Cable installation

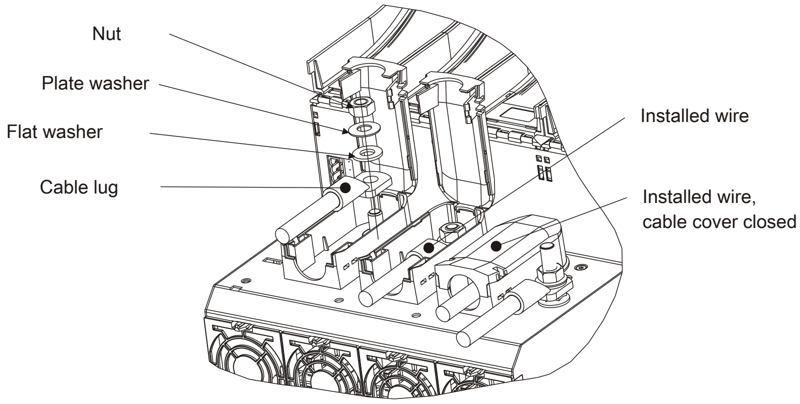
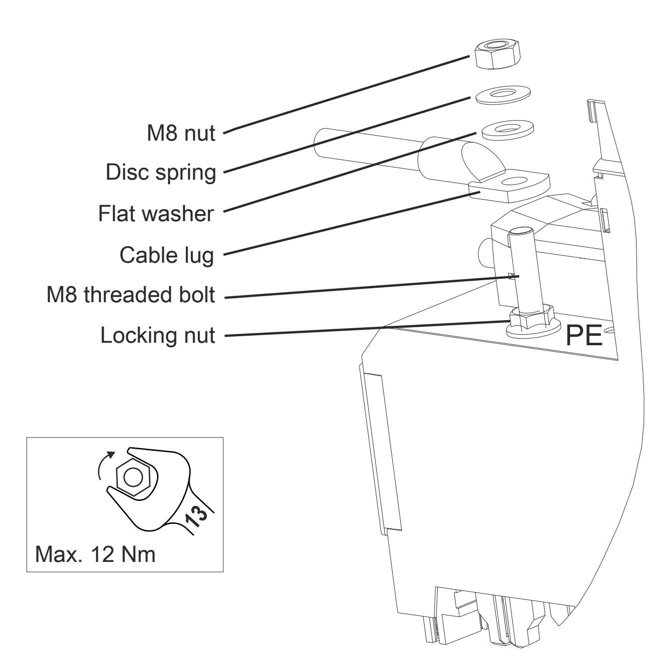
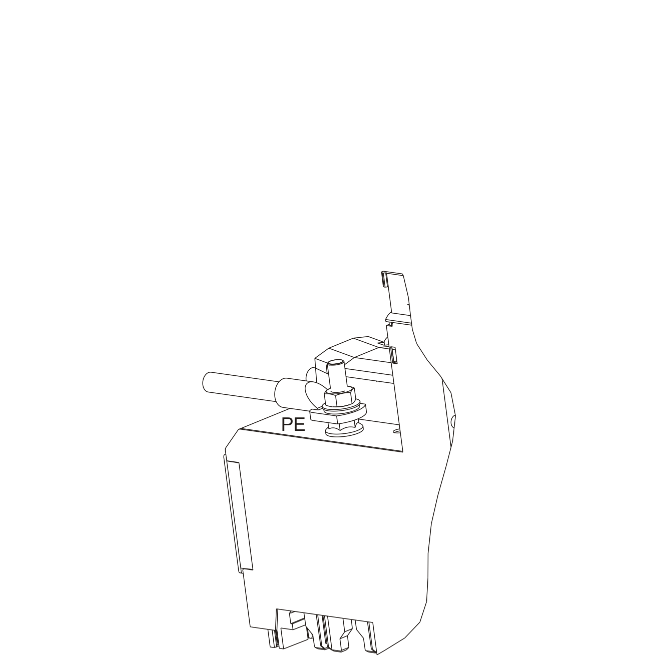


Figure 14: X5A - Cable installation

PE connection (1-wire) - Cable installation



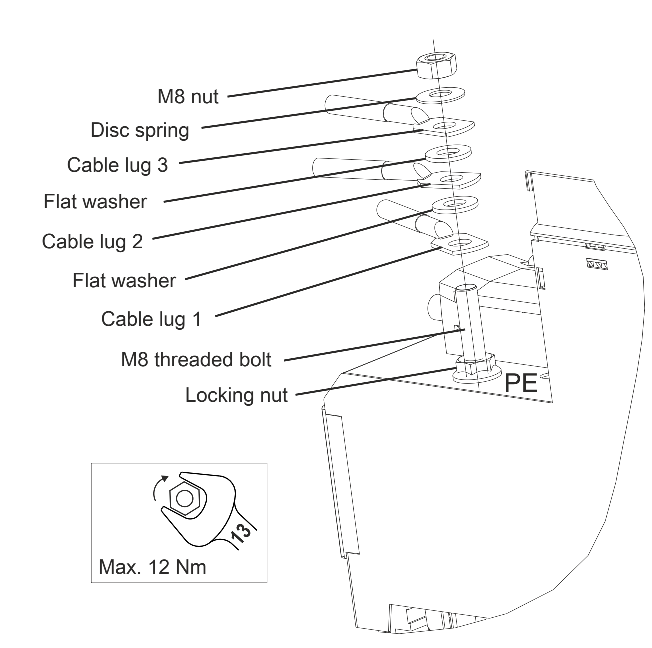
PE connection (1-wire) - Overview of installation material



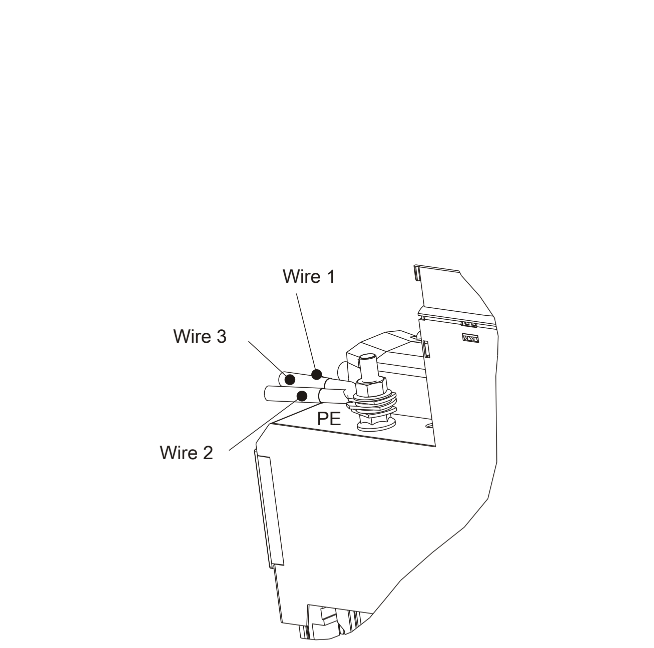
Installed wire

Table 70: PE connection (1-wire) - Cable installation

PE connection (3-wire) - Cable installation



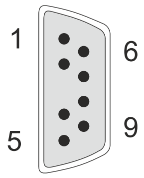
PE connection (3-wire) - Overview of installation material



Installed wire

Table 71: PE connection (3-wire) - Cable installation

2.3.6.3.7 SafeMOTION EnDat 2.2 module - Pinout

Figure	X11 (X12)	Pin	Description	Function
		1	U+	Encoder power supply +12.5 V
		2	---	---
		3	---	---
		4	D	Data input
		5	T	Clock output
		6	COM (1)	Encoder power supply 0 V
		7	---	---
		8	D\	Data input inverted
		9	T\	Clock output inverted

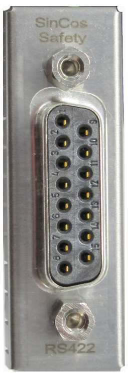
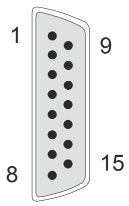
Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

Information:

The SafeMOTION module cannot be replaced! The SafeMOTION module and the ACOPOSmulti SafeMOTION inverter module together form a single unit. In the event of an error, the entire module must be replaced.

2.3.6.3.8 SafeMOTION SinCos module - Pinout

Figure	X11	Pin	Name	Function
		1	A	Channel A/Sin
		2	COM	Ground
		3	B	Channel B/COS
		4	+5 V	Encoder power supply +
		5	D	Data
		6	---	---
		7	R\	Reference pulse inverted/nREF
		8	T	Clock
		9	A\	Channel A inverted/nSIN
		10	Sense COM	Sense ground
		11	B\	Channel B inverted/nCOS
		12	Sense +5V	Sense input +5 V
		13	D\	Data inverted
		14	R	Reference pulse/REF
		15	T\	Clock cycle inverted

Information:

The SafeMOTION module cannot be replaced! The SafeMOTION module and the ACOPOSmulti SafeMOTION inverter module together form a single unit. In the event of an error, the entire module must be replaced.

2.3.7 Safe 8x width inverter modules (1-axis modules)

2.3.7.1 8BVI1650HCSS.000-1

2.3.7.1.1 General information

- Clearly structured, straightforward implementation via network-based safety technology
- Modular expandability through virtual wiring
- Immediate triggering of safety function due to short cycle times
- Easy implementation with transparent control and status information, even in the standard application
- Compact design

2.3.7.1.2 Order data

Model number	Short description	Figure
	Cold plate or feed-through mounting	
8BVI1650HCSS.000-1	ACOPOSmulti SafeMOTION EnDat 2.2 inverter module, 165 A, HV, cold plate or feed-through mounting	
	Required accessories	
	Terminal block sets	
8BZVI1650SS.000-1A	Screw clamp terminal block set for ACOPOS-multi 8BVI0660HxSS, 8BVI0880HxSS, 8BVI1650HxSS, 8BVI0660HxSA, 8BVI0880HxSA and 8BVI1650HxSA modules: 1x 8TB2104.203L-00, 1x 8TB2108.2010-00	
	Optional accessories	
	Accessory sets	
8BXB000.0000-00	ACOPOSmulti accessory set for encoder buffering consists of the following: 1 lithium battery AA 3.6 V, 1 cover for battery compartment	
	Fan modules	
8BXF001.0000-00	ACOPOSmulti fan module, replacement fan for ACOPOSmulti modules (8BxP/8B0C/8BVI/8BVE/8B0K)	
	Plug-in modules	
8BAC0120.000-1	ACOPOSmulti plug-in module, EnDat 2.1 interface	
8BAC0120.001-2	ACOPOSmulti plug-in module, EnDat 2.2 interface	
8BAC0121.000-1	ACOPOSmulti plug-in module, HIPERFACE interface	
8BAC0122.000-1	ACOPOSmulti plug-in module, resolver interface 10 kHz	
8BAC0123.000-1	ACOPOSmulti plug-in module, incremental encoder and SSI absolute encoder interface for RS422 signals	
8BAC0123.001-1	ACOPOSmulti plug-in module, incremental encoder interface for 5 V single-ended and 5 V differential signals	
8BAC0123.002-1	ACOPOSmulti plug-in module, incremental encoder interface for 24 V single-ended and 24 V differential signals	
8BAC0124.000-1	ACOPOSmulti plug-in module, SinCos interface	
8BAC0125.000-1	ACOPOSmulti plug-in module, SinCos EnDat 2.1/SSI/BiSS interface	
8BAC0130.000-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 2 digital outputs, 500 mA, max. 1.25 kHz, 2 digital inputs 24 VDC	
8BAC0130.001-1	ACOPOSmulti plug-in module, 2 digital outputs, 50 mA, max. 62.5 kHz, 4 digital outputs, 500 mA, max. 1.25 kHz	
8BAC0132.000-1	ACOPOSmulti plug-in module, 4 analog inputs ±10 V	
8BAC0133.000-1	ACOPOSmulti plug-in module, 3 RS422 outputs for ABR encoder emulation, 1 MHz	
	POWERLINK/Ethernet cables	
X20CA0E61.00020	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.2 m	
X20CA0E61.00025	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.25 m	
X20CA0E61.00030	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.3 m	
X20CA0E61.00035	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.35 m	
X20CA0E61.00050	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 0.5 m	
X20CA0E61.00100	POWERLINK/Ethernet connection cable, RJ45 to RJ45, 1 m	
	Shield component sets	
8SCS001.0000-00	ACOPOSmulti shield component set: 1x shield plate 4x type 1, 1x hose clamp, B 9 mm, D 12-22 mm	
8SCS002.0000-00	ACOPOSmulti shield component set: 1x clamping plate; 2x clamps D 4-13.5 mm; 4x screws	
8SCS003.0000-00	ACOPOSmulti shield component set: 1x shield mounting plate 4x 45°, 8x screws	
8SCS004.0000-00	ACOPOSmulti shield component set: 1x shield plate 4x type 0, 2x hose clamps, B 9 mm, D 32-50 mm	

Table 72: 8BVI1650HCSS.000-1 - Order data

Model number	Short description	Figure
8SCS010.0000-00	ACOPOSmulti shield component set: 1x ACOPOSmulti holding plate SK14-20, 1x shield connection clamp SK20	
	Terminal blocks	
8TB2104.203L-00	4-pin screw clamp, single row, spacing: 5.08 mm, label 3: T- T + B- B+, L keying: 1010	
8TB2108.2010-00	8-pin screw clamp, single row, spacing: 5.08 mm, label 1: numbered serially	

Table 72: 8BVI1650HCSS.000-1 - Order data

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

For details, see 6.1.2 "Safe power transmission system " on page 283.

2.3.7.1.3 Technical data

Model number	8BVI1650HCSS.000-1
General information	
B&R ID code	0xB878
Cooling and mounting type	Cold plate or feed-through mounting
Slots for plug-in modules	2 [1)]
Certifications	
CE	Yes
Functional safety[2)]	Yes (openSAFETY)
UL	cULus E225616 Power conversion equipment
EAC	Yes
KC	Yes
DC bus connection	
Voltage	
Nominal	750 VDC
Continuous power consumption [3)]	121.8 kW
Power dissipation depending on switching frequency [4)]	
Switching frequency 5 kHz	[0.001 * I_M² + 9.9 * I_M + 165] W
Switching frequency 10 kHz	[0.17 * I_M² + 10.8 * I_M + 320] W
Switching frequency 20 kHz	In preparation
DC bus capacitance	3630 µF
Variant	ACOPOSmulti backplane
24 VDC power supply	
Input voltage	25 VDC ±1.6%
Input capacitance	32.9 µF
Max. power consumption	43 W + P_{SMC1} + P_{SLOT2} + $P_{24\ V\ Out}$ + $P_{HoldingBrake}$[5)]
Variant	ACOPOSmulti backplane
24 VDC output	
Quantity	2
Output voltage	
DC bus voltage (U_{DC}): 260 to 315 VDC	25 VDC * (U_{DC}/315)
DC bus voltage (U_{DC}): 315 to 800 VDC	24 VDC ±6%
Fuse protection	250 mA (slow-blow) electronic, automatic reset
Motor connection [6)]	
Quantity	1
Continuous power per motor connection [3)]	120 kW
Continuous current per motor connection [3)]	165 A_{eff}

Table 73: 8BVI1650HCSS.000-1 - Technical data

Model number	8BVI1650HCSS.000-1
Reduction of continuous current depending on switching frequency and mounting type [7]	
Switching frequency 5 kHz	
Cold plate mounting [8]	3.1 A/K (starting at 53°C) [9]
Feed-through mounting	2.82 A/K (starting at 40°C) [9]
Switching frequency 10 kHz	
Cold plate mounting [8]	1.8 A/K (starting at 17°C) [10]
Feed-through mounting	1.5 A/K (starting at -13°C) [11]
Switching frequency 20 kHz	
Cold plate mounting [8]	1.2 A/K (starting at -60°C) [10]
Feed-through mounting	0.72 A/K (starting at 141°C) [11]
Reduction of continuous current depending on installation elevation	
Starting at 500 m above sea level	16.5 A_{eff} per 1000 m
Peak current	330 A_{eff}
Nominal switching frequency	5 kHz
Possible switching frequencies [12]	5 / 10 / 20 kHz
Electrical stress of connected motor per IEC TS 60034-25 [13]	Limit value curve A
Protective measures	
Overload protection	Yes
Short circuit and ground fault protection	Yes
Max. output frequency	598 Hz [14]
Variant	
U, V, W, PE	M8 threaded bolt
Shield connection	Yes
Connection cross section range	
Flexible and fine-stranded wires	--- [15]
Terminal cable cross section dimension of shield connection	12 to 50 mm [16]
Max. motor cable length depending on switching frequency	
Switching frequency 5 kHz	25 m
Switching frequency 10 kHz	25 m
Switching frequency 20 kHz	25 m
Motor holding brake connection	
Quantity	1
Output voltage [17]	24 VDC +5.8% / -0.5% [18]
Continuous current	4.2 A
Max. internal resistance	0.15 Ω
Extinction potential	Approx. 30 V
Max. extinction energy per switching operation	3 Ws
Max. switching frequency	0.5 Hz
Protective measures	
Overload and short-circuit protection	Yes
Open circuit monitoring	Yes
Undervoltage monitoring	Yes
Response threshold for open circuit monitoring	Approx. 0.5 A
Response threshold for undervoltage monitoring	24 VDC -2% / -4%
Encoder interfaces [19]	
Quantity	1
Type	EnDat 2.2 [20]
Connections	9-pin female DSUB connector
Status indicators	UP/DN LEDs
Electrical isolation	
Encoder - ACOPOSmulti	No
Encoder monitoring	Yes
Max. encoder cable length	100 m Depends on the cross section of the power supply wires of the encoder cable [21]
Encoder power supply	
Output voltage	Typ. 12.5 V
Load capacity	350 mA
Protective measures	
Short-circuit proof	Yes
Overload-proof	Yes
Synchronous serial interface	
Signal transmission	RS485
Data transfer rate	6.25 Mbit/s
Max. power consumption per encoder interface	$P_{SMC}[W] = 19\ V * I_{Encoder}[A]$ [22]
Trigger inputs	
Quantity	2
Circuit	Sink

Table 73: 8BVI1650HCSS.000-1 - Technical data

Model number	8BVI1650HCSS.000-1
Electrical isolation	
Input - Inverter module	Yes
Input - Input	Yes
Input voltage	
Nominal	24 VDC
Maximum	30 VDC
Switching threshold	
Low	<5 V
High	>15 V
Input current at nominal voltage	Approx. 10 mA
Switching delay	
Rising edge	52 µs ±0.5 µs (digitally filtered)
Falling edge	53 µs ±0.5 µs (digitally filtered)
Modulation compared to ground potential	Max. ±38 V
Electrical properties	
Discharge capacitance	0.9 µF
Operating conditions	
Permissible mounting orientations	
Hanging vertically	Yes
Horizontal, face up	Yes
Standing horizontally	No
Installation elevation above sea level	
Nominal	0 to 500 m
Maximum [23)]	4000 m
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)
Overvoltage category per EN 61800-5-1	III
Degree of protection per EN 60529	IP20 [24)]
Ambient conditions	
Temperature	
Operation	
Nominal	5 to 40°C
Maximum [25)]	55°C
Storage	-25 to 55°C
Transport	-25 to 70°C
Relative humidity	
Operation	5 to 85%
Storage	5 to 95%
Transport	Max. 95% at 40°C
Mechanical properties	
Dimensions [26)]	
Width	427.5 mm
Height	317 mm
Depth	
Cold plate	212 mm
Feed-through mounting	209 mm
Weight	Approx. 19.5 kg
Module width	8

Table 73: 8BVI1650HCSS.000-1 - Technical data

1) SLOT 2 is available. SLOT 1 of the ACOPOSmulti module is occupied by the SafeMOTION module.
2) Achievable safety classifications (safety integrity level, safety category, performance level) are documented in the user's manual (section "Safety technology").
3) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
4) I_M ... Current on motor connection X5A [A_{eff}]
5) P_{SMC1} ... Max. power consumption P_{SMC} [W] of the SafeMOTION module in SLOT1 (see the "Encoder interfaces" section).
P_{SLOT2} ... Max. power consumption P_{8BAC} [W] of the plug-in module in SLOT2 (see the technical data for the respective plug-in module).
$P_{24\ V\ Out}$ ... Power [W] that is output to connections X2/+24 V Out 1 and X2/+24 V Out 2 on the module (max. 10 W).
6) Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.
7) Valid for the following conditions: 750 VDC DC bus voltage, minimum permissible coolant flow volume (3 l/min).
8) The temperature specifications refer to the return temperature of the cold plate mounting plate.
9) Value for the nominal switching frequency.
10) The module cannot supply the full continuous current at this switching frequency. This unusual value for the return temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
Caution! Condensation can occur at low flow temperatures and return temperatures.
11) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
12) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
13) If necessary, the stress of the motor isolation system can be reduced by an additional externally wired dv/dt choke. For example, the RWK 305 three-phase du/dt choke from Schaffner (www.schaffner.com) can be used. Important: Even when using a dv/dt choke, it is necessary to ensure that an EMC-compatible, low inductance shield connection is used!
14) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").

15) The connection is made with cable lugs for M8 (0.32") threaded bolts. The nominal cross section of the cable lug must match the cross section of the conductor that is to be connected in the particular application.
16) The maximum diameter that can be clamped depends on the shield component set.
17) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
18) The specified value is only valid under the following conditions:
    - The 24 VDC supply for the module is provided by an 8B0C auxiliary supply module installed on the same mounting plate.
    - Connection between S1 and S2 (activation of the external holding brake) using a jumper with a max. length of 10 cm.
    If the 24 VDC supply for the module is applied to the mounting plate using an 8BVE expansion module, then the output voltage is reduced because of voltage drops on the expansion cable. In this case, undervoltage monitoring must be disabled.
    If jumpers longer than 10 cm are used to connect S1 and S2, then the output voltage is reduced because of voltage drops on the jumpers.
19) Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.
20) An EnDat 2.2 functional safety encoder is required when using ACOPOSmulti SafeMOTION inverter modules! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!
21) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 100 m is not permitted to be exceeded):

    $l_{Max} = 7.9 / I_G * A * 1/(2*\rho)$

    I_G ... Max. current consumption of the encoder [A].
    A ... Cross section of the power supply wires [mm²]
    ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
22) $I_{Encoder}$ ... Max. power consumption of the connected encoder [A].
23) Continuous operation at elevations ranging from 500 m to 4,000 m above sea level is possible (taking the specified continuous current reductions into consideration).
24) This value only applies in its delivered state (SLOT2 of the module is sealed by a slot cover / shield plate). If SLOT2 on the module is not sealed, then the level of protection is reduced to IP10. It is important to note that a 8SCS005.0000-00 shield set (slot cover / shield plate) or plug-in module must always be inserted!
25) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous current reductions into consideration), but this will result in a shorter service life.
26) These dimensions refer to the actual device dimensions including the respective mounting plate. Make sure to leave additional space above and below the devices for mounting, connections and air circulation.

2.3.7.1.4 Wiring

For details, see section 2.3.7.2 "Wiring: Safe 8x width inverter modules (1-axis modules)" on page 142.

For general information, see section 2.6 "Wiring" on page 150.

2.3.7.2 Wiring: Safe 8x width inverter modules (1-axis modules)

2.3.7.2.1 Pinout overview

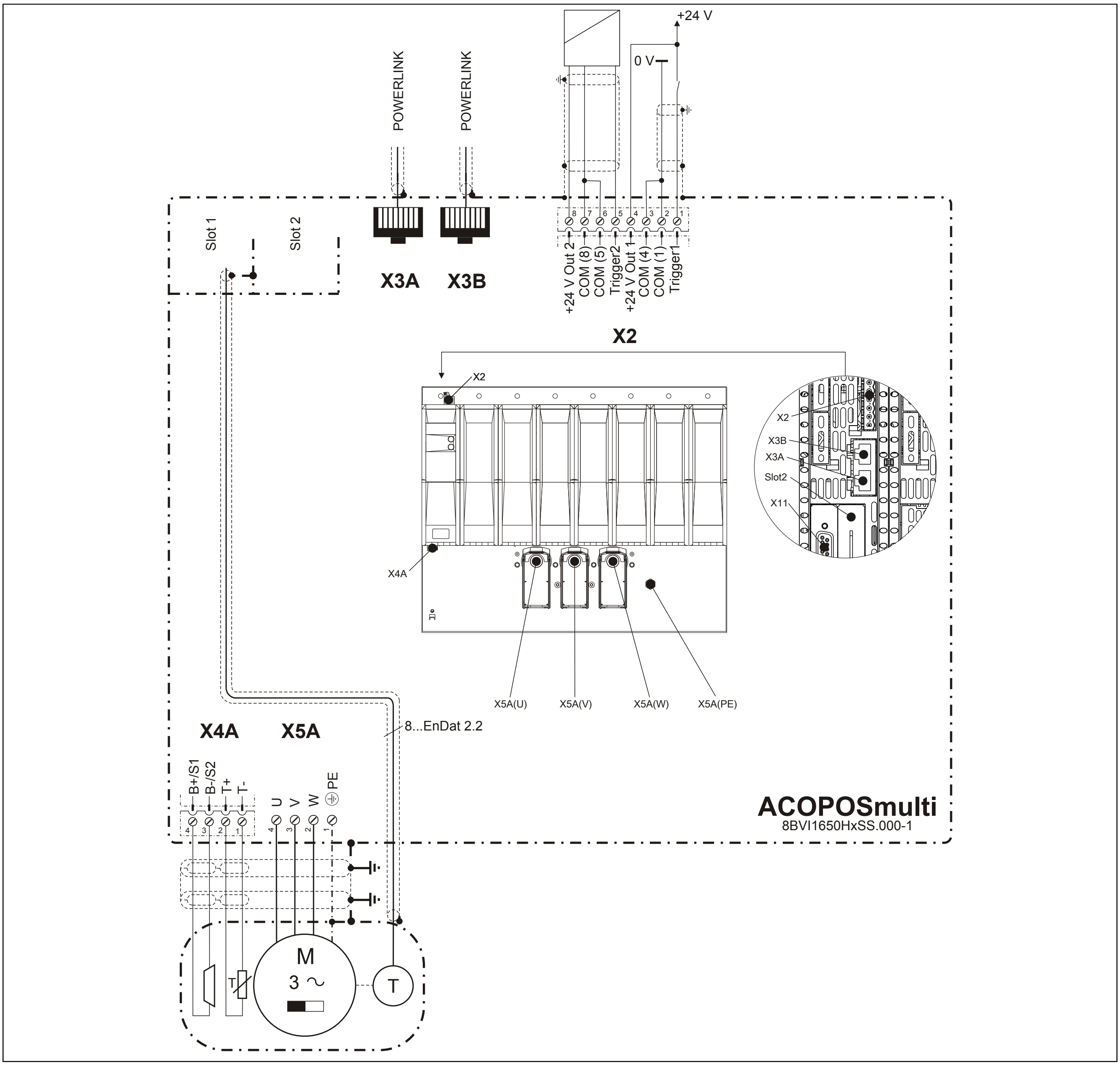


Figure 15: Pinout overview

2.3.7.2.2 Connector X2 - Pinout

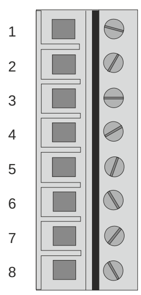
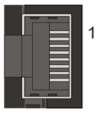
X2	Pin	Description	Function
	1	Trigger 1	Trigger 1
	2	COM (1)	Trigger 1 0 V
	3	COM (2)	+24 V output 1 0 V
	4	+24 V Out 1	+24 V output 1
	5	Trigger 2	Trigger 2
	6	COM (5)	Trigger 2 0 V
	7	COM (8)	+24 V output 2 0 V
	8	+24 V Out 2	+24 V output 2

Table 74: Connector X2 - Pinout

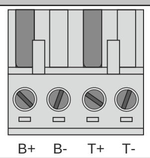
2.3.7.2.3 Connectors X3A, X3B - Pinout



X3A, X3B	Pin	Description	Function
	1	RXD	Receive signal
	2	RXD\	Receive signal inverted
	3	TXD	Transmit signal
	4	Shield	Shield
	5	Shield	Shield
	6	TXD\	Transmit signal inverted
	7	Shield	Shield
	8	Shield	Shield

Table 75: X3A, X3B connectors - Pinout

2.3.7.2.4 X4A connector - Pinout



X4A	Description	Function
	T-	Axis 1: Temperature sensor -
	T+	Axis 1: Temperature sensor +
	B-	Axis 1: Brake -
	B+	Axis 1: Brake +

Table 76: Connector X4A - Pinout

Danger!

A short circuit of SBC output B+ against 24 V results in state FUNCTIONAL FAIL SAFE being enabled. This means that safe pulse disabling is enabled. The brake always remains switched on / released, however, due to the short circuit to 24 V!
This can lead to dangerous situations since the motor holding brake cannot brake, prevent the spin-out movement or prevent the unbraked lowering movement when loads are suspended!
A short circuit of SBC output B+ against 24 V must be prevented by suitable wiring measures!

Danger!

The following applies to the SBC output:

- **It is not permitted to be wired across modules!**
- **It is not permitted to be wired as an open emitter!**
- **It is not permitted to be wired as an open collector!**

Danger!

Only an output voltage of ≤ 5 V can be ensured for the safe motor holding brake output when switched off. When selecting the motor holding brake, the user must ensure that the required braking torque is achieved with a voltage of 5 V applied.

Information:

The transistors of the SBC output stage are tested cyclically. When the output channels are active, this test emits low pulses on the output with a maximum length of 600 µs.

This must be taken into consideration when choosing the motor holding brake!

Danger!

The connections for the motor temperature sensors and the motor holding brake are safely isolated circuits. These connections are therefore only permitted to be connected to devices or components that have sufficient isolation per IEC 60364-4-41 or EN 61800-5-1.

Caution!

If B+ and B- are swapped when connecting the permanent magnet holding brakes, then the brakes cannot be opened! ACOPOSmulti inverter modules cannot determine if a holding brake is connected with reverse polarity!

Warning!

Temperature sensors are only permitted to be connected to the X4A/T+ and X4A/T- connectors on an ACOPOSmulti module under the following conditions:

- **SLOT1 of the ACOPOSmulti module does not contain an ACOPOSmulti plug-in module to which a temperature sensor is connected on the T+ and T- connections.**

Otherwise, the temperature monitoring functions on the ACOPOSmulti module may become ineffective, which in extreme cases can cause the hardware (e.g. motors) connected to the ACOPOSmulti module to be destroyed!

2.3.7.2.5 X5A - Pinout

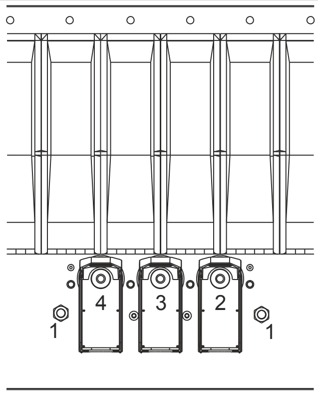
X5A	Pin	Description	Function
	1	PE	Axis 1: Protective ground conductor
	2	W	Axis 1: Motor connection W
	3	V	Axis 1: Motor connection V
	4	U	Axis 1: Motor connection U
	Tightening torque for the M8 nuts: 12 Nm		

Table 77: X5A - Pinout

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

Motor connections U, V, W - Cable installation

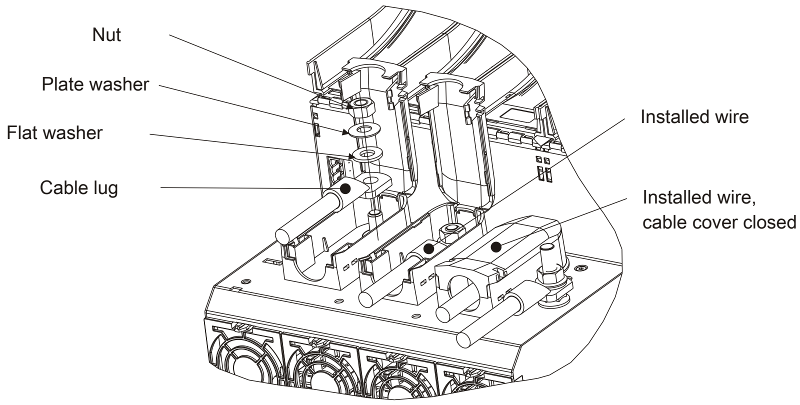
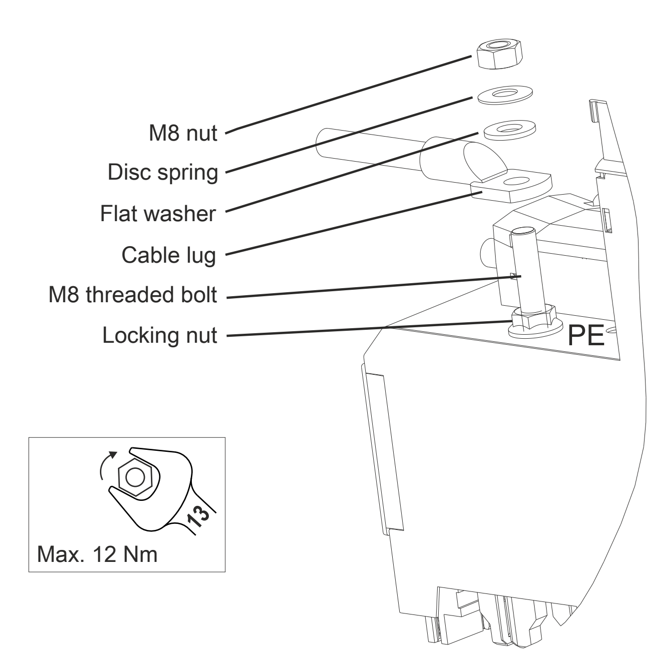
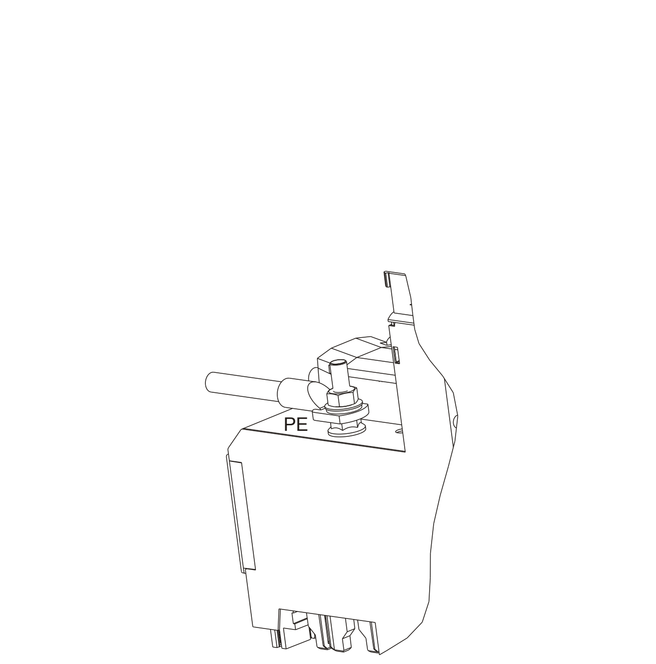


Figure 16: X5A - Cable installation

PE connection (1-wire) - Cable installation



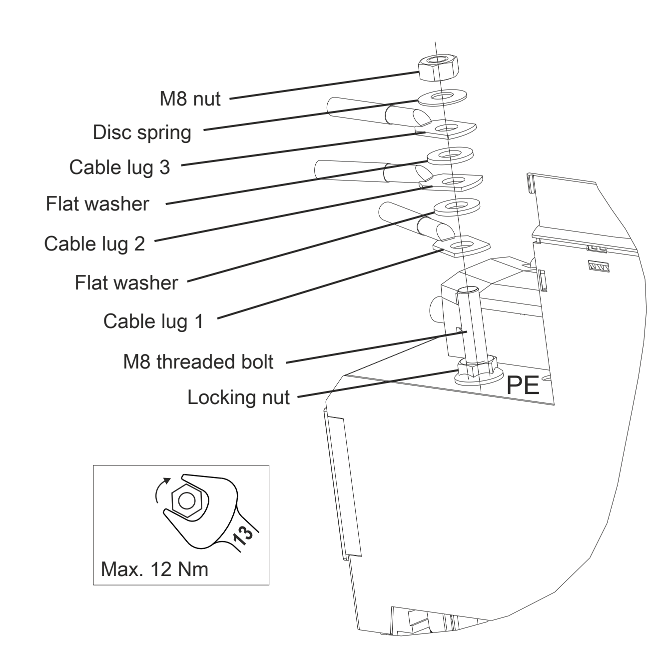
PE connection (1-wire) - Overview of installation material



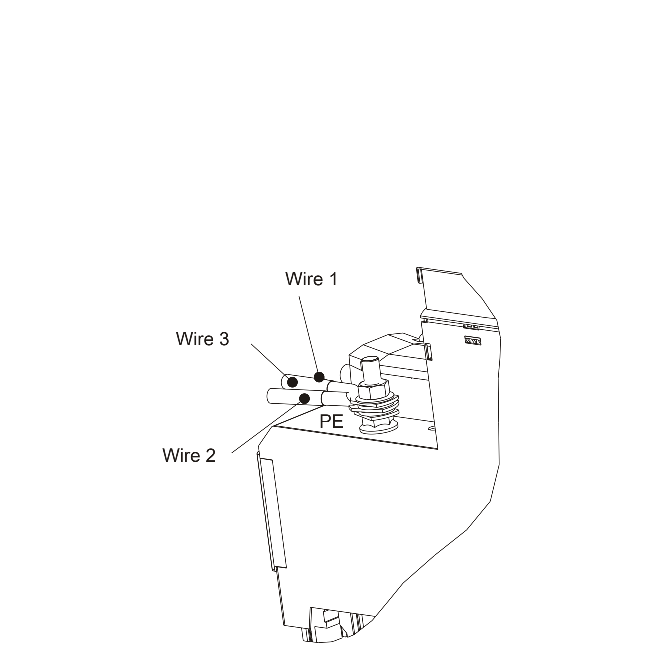
Installed wire

Table 78: PE connection (1-wire) - Cable installation

PE connection (3-wire) - Cable installation



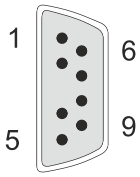
PE connection (3-wire) - Overview of installation material



Installed wire

Table 79: PE connection (3-wire) - Cable installation

2.3.7.2.6 SafeMOTION EnDat 2.2 module - Pinout

Figure	X11 (X12)	Pin	Description	Function
		1	U+	Encoder power supply +12.5 V
		2	---	---
		3	---	---
		4	D	Data input
		5	T	Clock output
		6	COM (1)	Encoder power supply 0 V
		7	---	---
		8	D\	Data input inverted
		9	T\	Clock output inverted

Information:

Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!

Information:

The SafeMOTION module cannot be replaced! The SafeMOTION module and the ACOPOSmulti SafeMOTION inverter module together form a single unit. In the event of an error, the entire module must be replaced.

2.4 Installation

See the ACOPOSmulti user's manual MAACPM-ENG, chapter "Installation".

2.5 Dimensioning

See the ACOPOSmulti user's manual MAACPM-ENG, chapter "Dimensioning".

2.6 Wiring

2.6.1 General information

2.6.1.1 EMC-compatible installation

General information

If the directives for electromagnetic compatibility of the installation are followed, the ACOPOSmulti drive system meets the EMC directive 2004/108/EC and low-voltage directives 2006/95/CE. It also meets the requirements for harmonized EMC product standard IEC 61800-3:2004 for industry (second environment).

Additional EMC measures must be implemented by the machine or system manufacturer in the event that the product standard for the machine includes lower limit values or the machine conforms to the IEC 61000-6-4 basic standard. Proof of conformity to required limit values must be provided by the manufacturer or distributor of the machine or system in accordance with the guidelines for implementing the EMC directive.

Additional EMC measures are required when operating ACOPOSmulti drive systems in a residential area or when connecting ACOPOSmulti drive systems to a low voltage system that also supplies buildings in a residential area (first environment) without an intermediate transformer.

Installation notes

1. The control cabinet or system must be constructed properly.
2. To prevent the effects of disturbances, the following lines must be properly shielded:
    - Motor cables
    - Encoder cables
    - Control cables
    - Data cables
3. Inductive switching elements such as contactors or relays must be equipped with corresponding suppressor elements such as varistors, RC elements or damping diodes.
4. All electrical connections must be kept as short as possible.
5. Cable shields must be attached to designated shield connection clamps and the connector housing.
6. Shielded cables with copper braiding or tinned copper braiding must be used. Twisting the braided shield or extending it with single conductors is not permitted.
7. Unused cable conductors must be grounded on both sides whenever possible.

2.6.1.2 Overview

Passive power supply

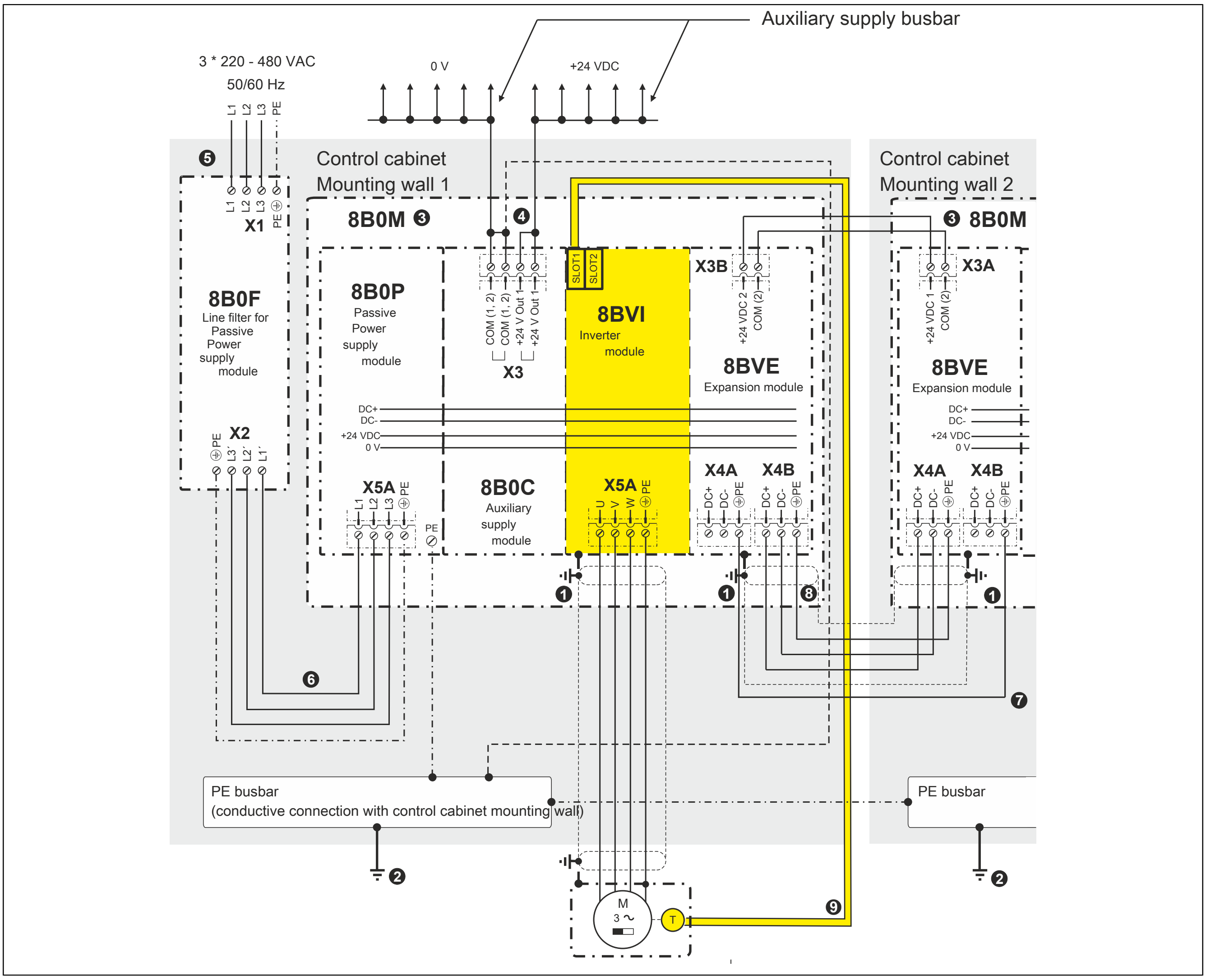


Figure 17: Overview of ground/shield for ACOPOSmulti drive system (passive power supply)

1 Shielding connection via module-specific shield component set.
2 Central grounding point.
3 8B0M mounting plate, large-surface conductive connection with control cabinet mounting wall.
4 One of the two COM connections (1, 2) on the X3 connector must be grounded to achieve a defined relationship between the signal ground and ground potential. Otherwise, the Safe Brake Control (SBC) safety function could fail if an error occurs (ground fault).
5 The mains power input must be kept as short as possible inside the control cabinet.
6 The connection between the line filter and power supply module is never shielded. To prevent disturbances in the mains power input (❺), they cannot be routed parallel to the connection between the line filter and power supply module.
7 An additional PE connection must be made between two 8BVE expansion modules in order to meet the conditions necessary for the ACOPOSmulti drive systems mains connection on all 8B0M mounting plates that are connected using 8BVE expansion modules. This additional PE connection must be made with the same wire cross section as the PE wire routed in the expansion cable (at least 2.5 mm² with protected wiring or 4 mm² with unprotected wiring).
9 ACOPOSmulti SafeMOTION EnDat 2.2: Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.

Active power supply

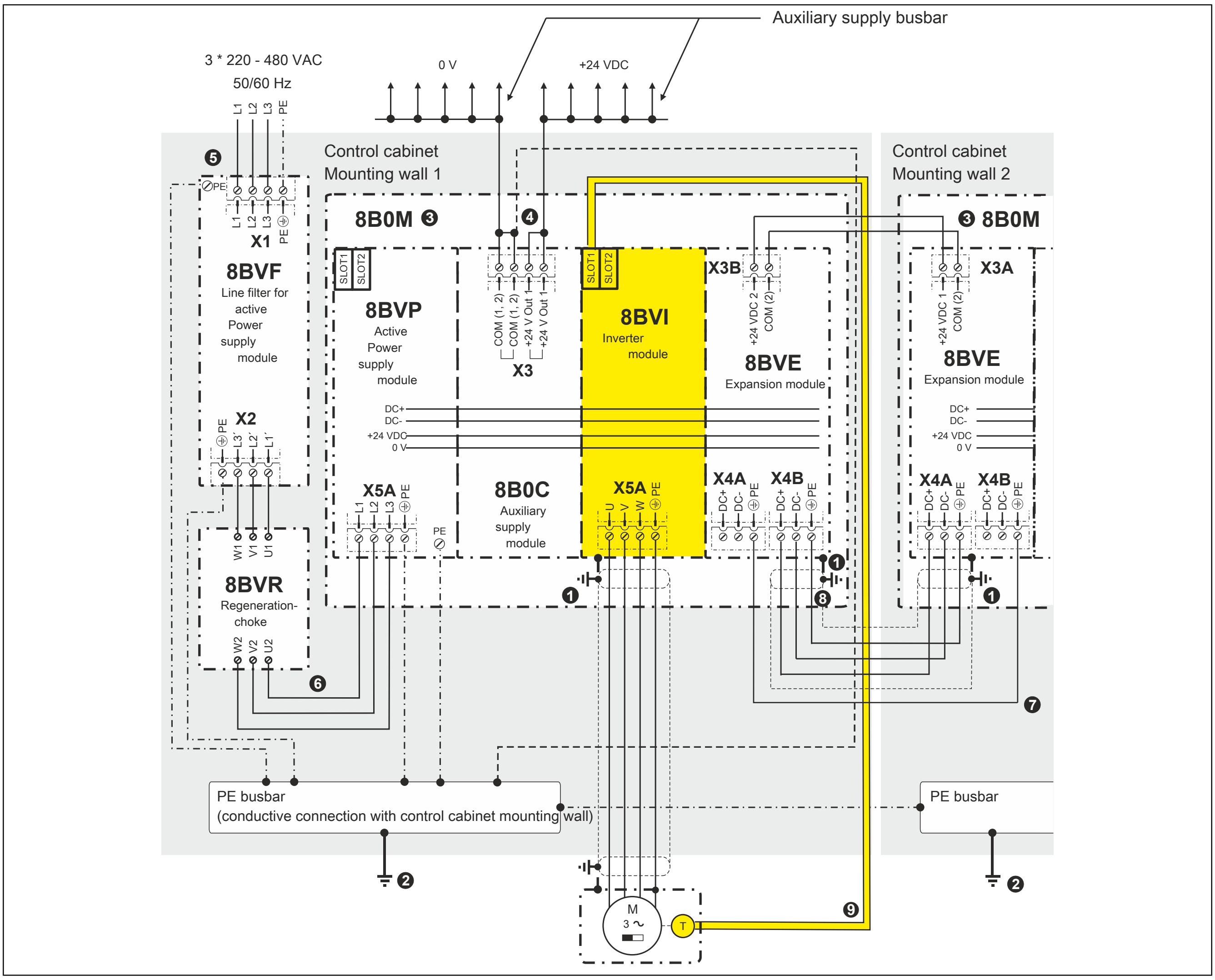


Figure 18: Overview of ground/shield for ACOPOSmulti drive system (active power supply)

1 Shielding connection via module-specific shield component set.
2 Central grounding point.
3 8B0M mounting plate, large-surface conductive connection with control cabinet mounting wall.
4 One of the two COM connections (1, 2) on the X3 connector must be grounded to achieve a defined relationship between the signal ground and ground potential. Otherwise, the Safe Brake Control (SBC) safety function could fail if an error occurs (ground fault).
5 The mains power input must be kept as short as possible inside the control cabinet.
6 The connection between the line filter and power supply module is never shielded. To prevent disturbances in the mains power input (❺), they cannot be routed parallel to the connection between the line filter and power supply module.
7 An additional PE connection must be made between two 8BVE expansion modules in order to meet the conditions necessary for the ACOPOSmulti drive systems mains connection on all 8B0M mounting plates that are connected using 8BVE expansion modules. This additional PE connection must be made with the same wire cross section as the PE wire routed in the expansion cable (at least 2.5 mm² with protected wiring or 4 mm² with unprotected wiring).
9 ACOPOSmulti SafeMOTION EnDat 2.2: Only 8BCF EnDat 2.2 cables from B&R are permitted to be connected to the encoder interfaces.

Danger!

One of the two COM connections (1, 2) on the X3 connector must be grounded to achieve a defined relationship between the signal ground and ground potential. Otherwise, the Safe Brake Control (SBC) safety function could fail if an error occurs (ground fault).

Caution!

No additional consumers/components are permitted to be connected between the 8BVF line filter, 8BVR regeneration choke and 8BVP power supply module!

Warning!

ACOPOSmulti drive systems are only permitted to be used with specially designed line filters. Line filters from third-party manufacturers are not permitted to be used under any circumstances; there is a risk of irreparable damage to these line filters or components of the ACOPOSmulti drive system.

2.6.1.2.1 Additional PE connection on 8BVE expansion modules

The PE connection must always be made between the first and last 8BVE expansion module.

DC connection between 2 8BVE expansion modules

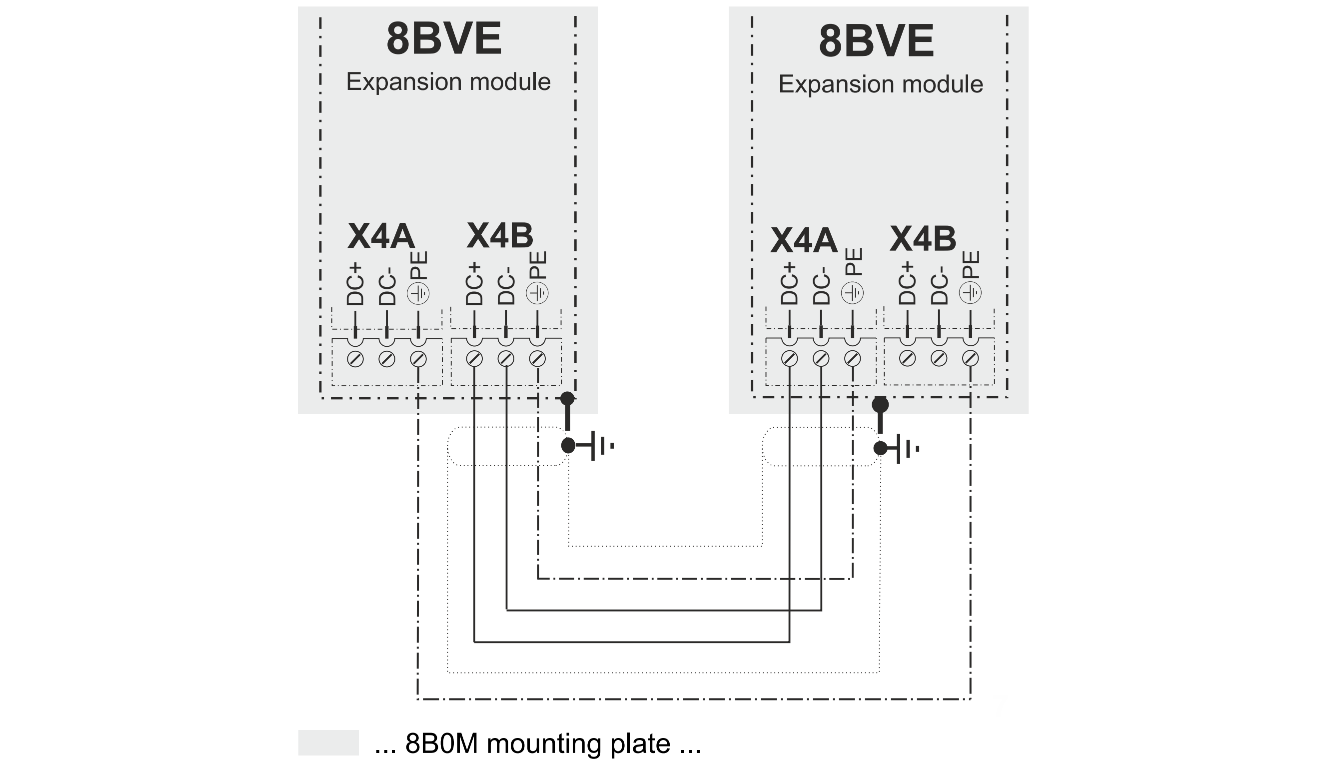


Figure 19: DC connection between 2 8BVE expansion modules

DC connection between more than 2 8BVE expansion modules

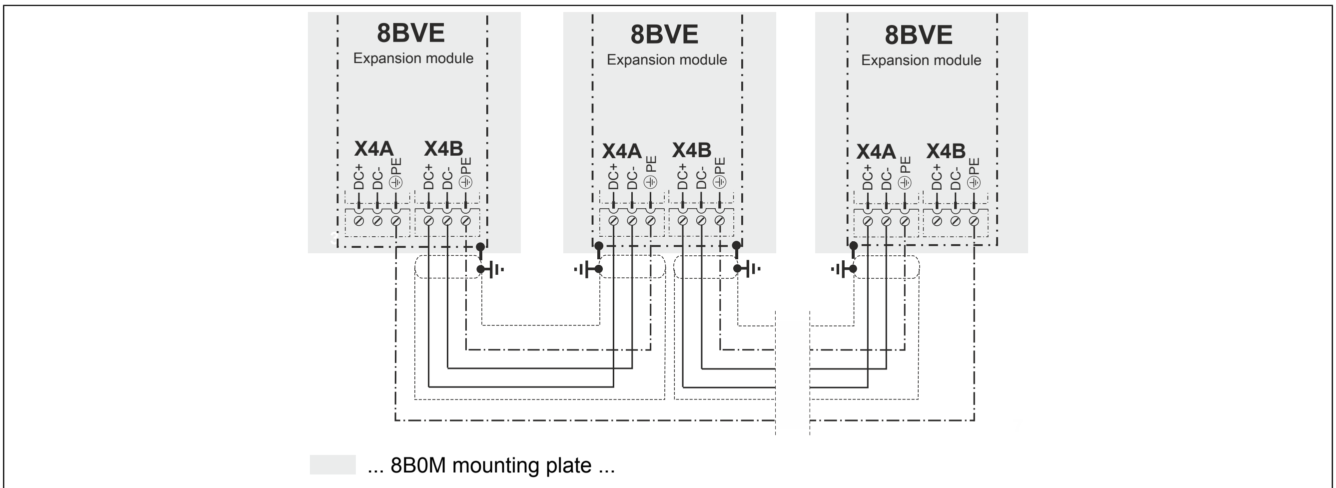


Figure 20: DC connection between more than 2 8BVE expansion modules

Connection between two 8BVE expansion modules in combination with 8CVI inverter modules

Variant 1: 8CVI inverter modules to both 8BVE expansion modules

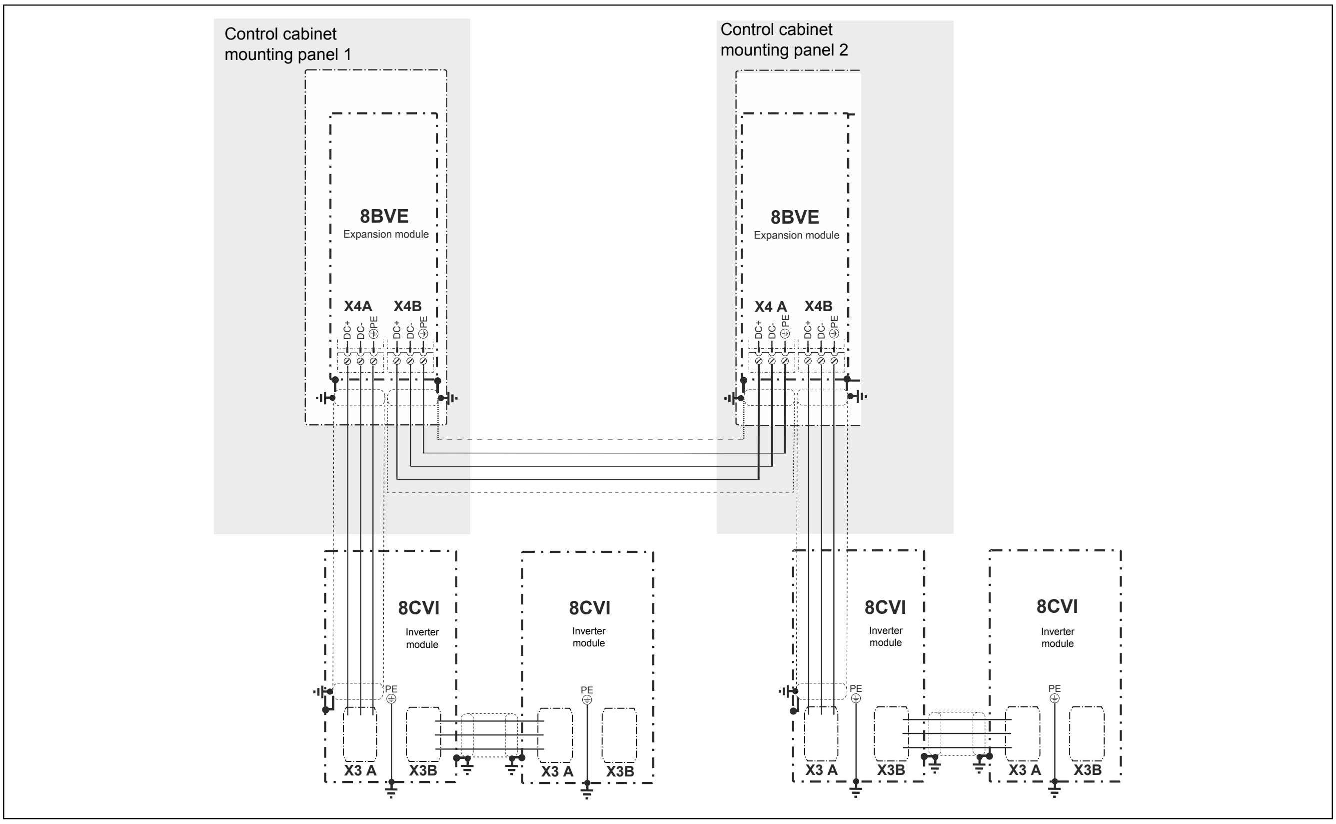


Figure 21: 8CVI inverter module to both 8BVE expansion modules

Variant 2: 8CVI inverter modules to the last 8BVE expansion module

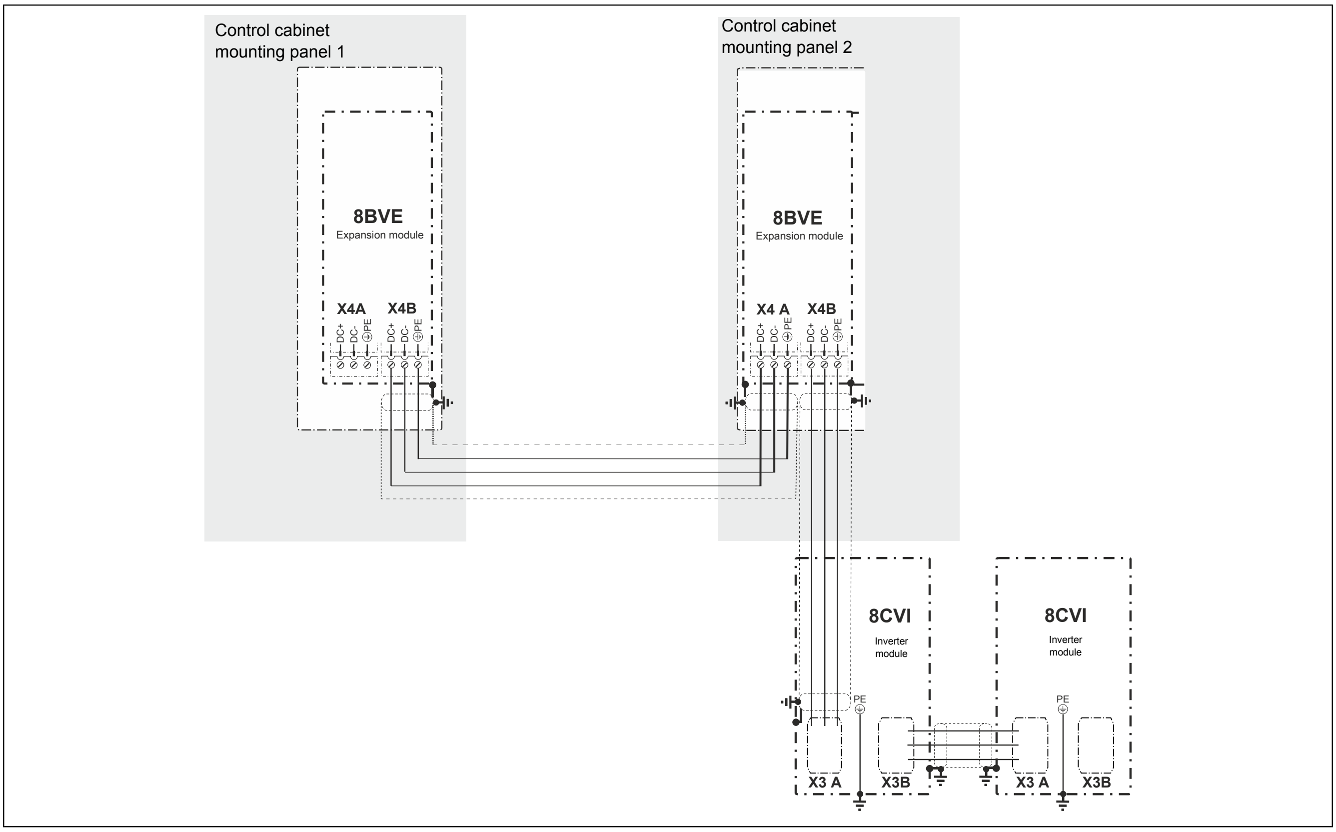


Figure 22: 8CVI inverter modules to the last 8BVE expansion module

2.6.1.3 Ground and shield connection diagrams

2.6.1.3.1 8BVI SafeMOTION inverter modules (1-axis modules)

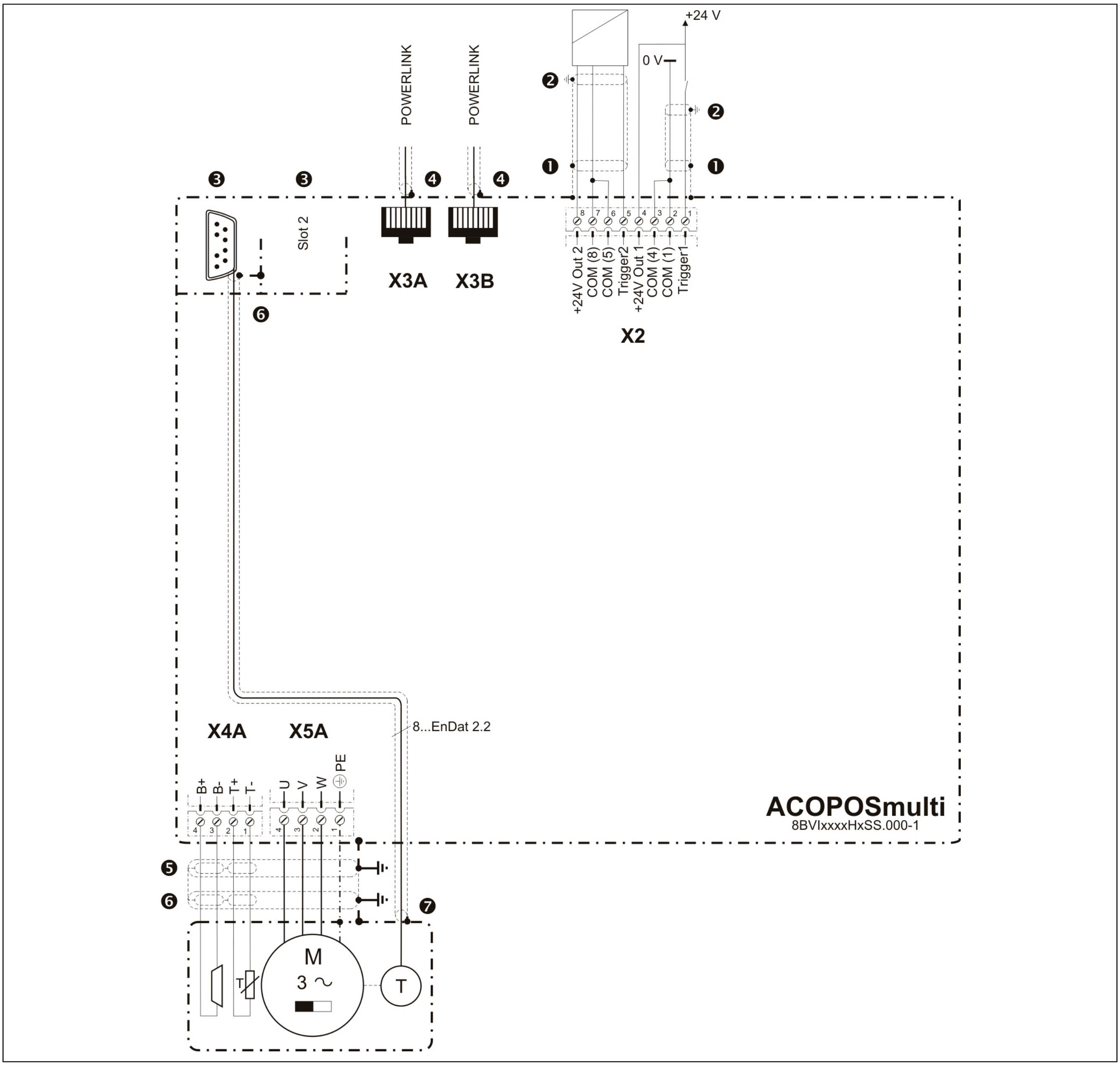


Figure 23: Ground connections and shield connections for 8BVI SafeMOTION EnDat 2.2 inverter modules

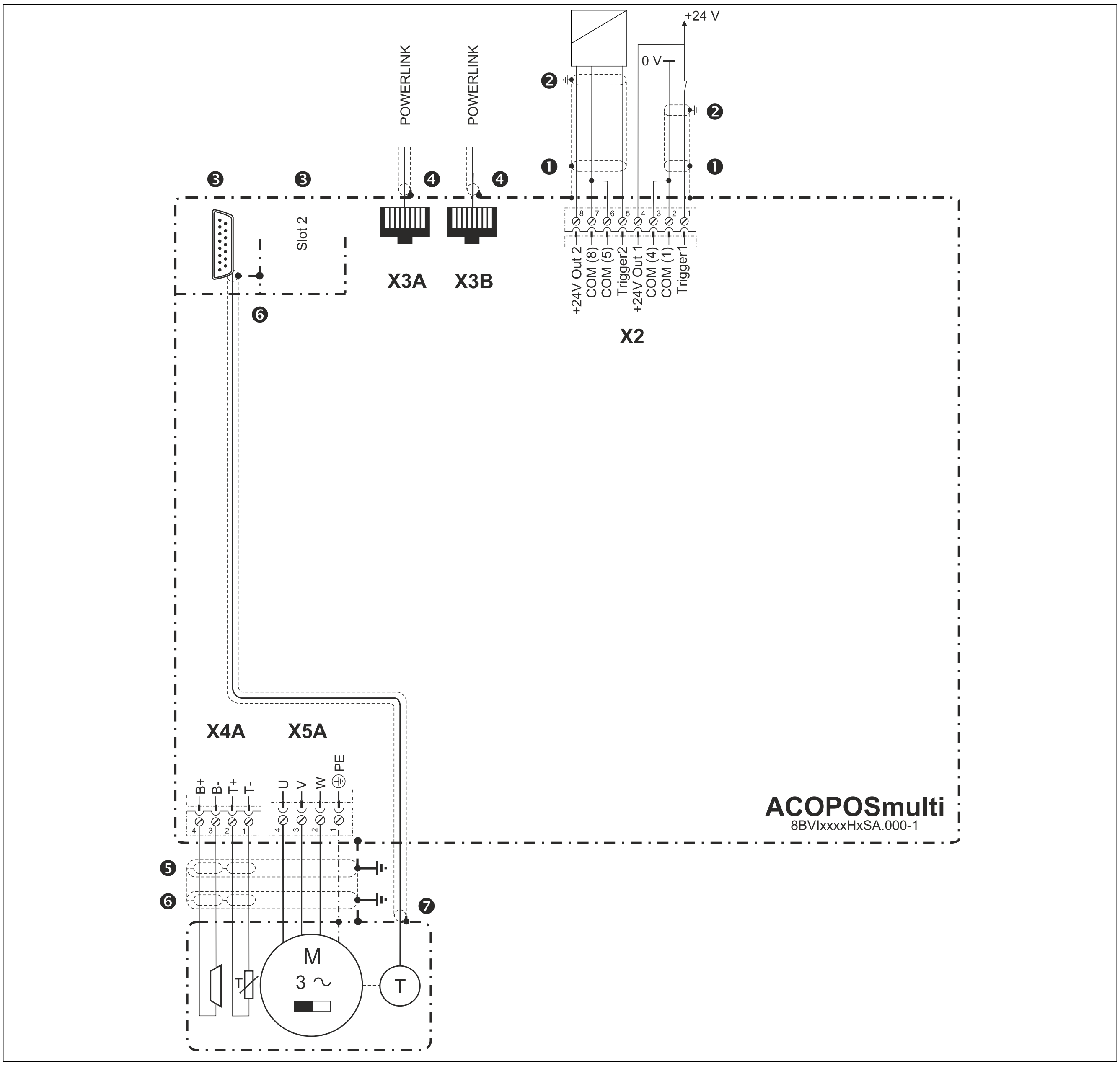
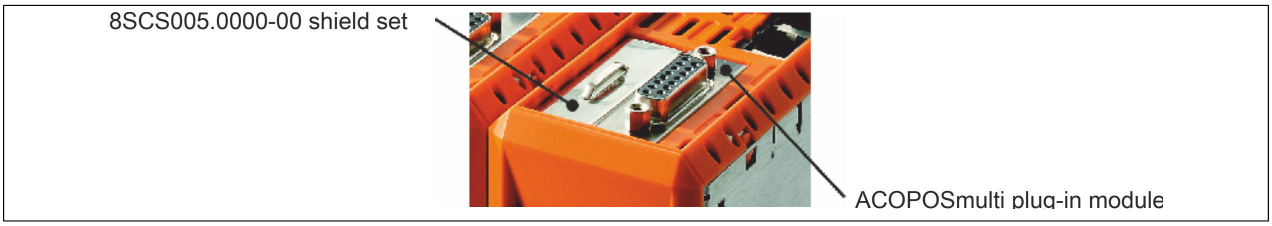


Figure 24: Ground connections and shield connections for 8BVI SafeMOTION SinCos inverter modules

1. Both trigger inputs are only filtered internally with approx. 50 µs. Make sure the cable shield is grounded properly. The optional 8SCS002.0000-00 shield set can be used for this.
2. The cable shield must be attached to the shield connector.

3. ACOPOSmulti plug-in modules automatically come in contact with the housing when inserted in the module slot:



Open module slots on ACOPOSmulti modules can be closed with the optional 8SCS005.0000-00 shield set available from B&R. The standard shield set for closing open module slots on ACOPOSmulti SafeMOTION inverter modules is the 8SCS005.0000-00.

4. Cable connection with DSUB connector:
The cable shield must be secured over a wide area in the metallic or metal-plated DSUB housing using the clamp provided for this purpose. The fastening screws on the DSUB housing must be tightened.

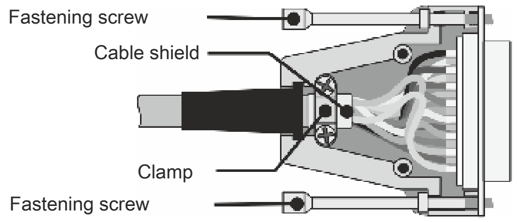


Figure 25: Cable shield in DSUB housing

Cable connection with terminals:
The cable shield must be connected to the housing of the ACOPOSmulti module using optional shielding set 8SCS002.0000-00.

Cable connection with RJ45 connector:
Additional grounding of the cable shield improves the EMC resistance. Grounding should take place on both sides, over a large area and near the connector. The optional 8SCS002.0000-00 shield set, available from B&R, can be used on the ACOPOSmulti module for this.

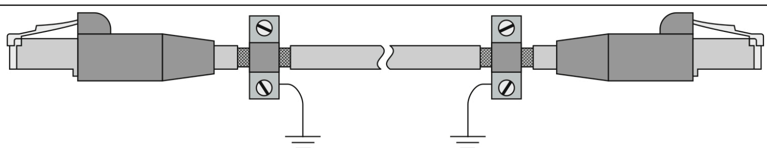


Figure 26: Male RJ45 connector - Grounding the cable shield

Information:

When cabling POWERLINK networks with B&R POWERLINK cables, no additional grounding of the cable shield is required to ensure resistance to disturbances per EN 61800-3!

5. The cable shield can be connected to the ACOPOSmulti module housing using the optional shield sets available from B&R.
6. On the motor side, the cable shield of the motor line is connected to the motor housing via the motor connector and connected to ground via the machine.
7. The cable shield of the encoder cable must be connected to the motor housing on the motor side via the encoder connector and subsequently to ground potential via the machine.

   With external encoders, the cable shield of the encoder cable must be connected to the machine on the encoder side via the encoder connector and subsequently to ground potential.

2.6.1.4 Insulation and high voltage testing

2.6.1.4.1 Insulation resistance testing in accordance with EN 60204

In accordance with EN 60204, the insulation resistance of electrical equipment is measured with 500 VDC between the main circuit conductors and the protective ground conductor system and is not permitted to fall below the value 1 MΩ. Testing individual sections of the system is permitted.

Motor connectors on ACOPOSmulti inverter modules (X5A / X5B)

> **Warning!**
>
> **An insulation test is not permitted to be carried out on the motor connectors (X5A / X5B) of ACOPOS-multi inverter modules since this would destroy the ACOPOSmulti inverter modules!**
>
> **The motor cable must be disconnected from the motor connector (X5A / X5B) of the ACOPOSmulti inverter module before insulation resistance is measured!**

B&R motors and B&R motor cables

In principle, insulation resistance measurement can be carried out on B&R motor cables and B&R motors. The insulation resistance can be lower than 1 MΩ, however, depending on the motor that is connected. The 50 kΩ minimum value required as specified in EN 60204, Section 18.3 is exceeded in any case.

> **Warning!**
>
> **An insulation test is not permitted to be carried out on the motor connectors (X5A / X5B) of ACOPOS-multi inverter modules since this would destroy the ACOPOSmulti inverter modules!**
>
> **The motor cable must be disconnected from the motor connector (X5A / X5B) of the ACOPOSmulti inverter module before insulation resistance is measured!**

2.6.1.4.2 High voltage testing

In accordance with EN 60204, the electrical equipment must be able to withstand a test voltage connected between the conductors of all circuits and the protective ground conductor system for at least 1 s (exception: all circuits with a voltage < PELV voltage). The test voltage must be twice the rated voltage for the equipment, but at least 1000 VAC (50/60 Hz). Components that cannot handle this test voltage must be disconnected before carrying out the high voltage test.

Motor connectors on ACOPOSmulti inverter modules (X5A / X5B)

> **Warning!**
>
> **A high voltage test is not permitted to be carried out on the motor connection (X5A / X5B) of ACOPOS-multi inverter modules since this would destroy the ACOPOSmulti inverter modules!**

B&R motors and B&R motor cables

In principle, high voltage testing can be carried out on B&R motor cables and B&R motors. Depending on the size of the motor and length of the motor cable, increased measurement currents can occur because of capacitive coupling.

> **Warning!**
>
> **A high voltage test is not permitted to be carried out on the motor connection (X5A / X5B) of ACOPOS-multi inverter modules since this would destroy the ACOPOSmulti inverter modules!**
>
> **The motor cable must be removed from the motor connection (X5A / X5B) of the ACOPOSmulti inverter module before the high voltage measurement is made!**

2.6.1.4.3 Typical procedure

Isolation test

a) Disconnect the motor cable from the X5A / X5B connector on the ACOPOSmulti inverter module.
b) Perform the insulation test on the X1 mains connection (mains side) of the ACOPOSmulti line filter.
c) Perform the insulation test on the B&R motor.

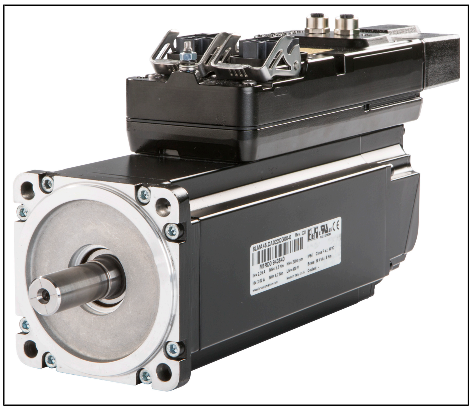
High voltage testing

a) Disconnect the connection cable between the X2 connector of the ACOPOSmulti line filter and the U1 / V1 / W1 connectors of the ACOPOSmulti regeneration choke on the X2 connector of the ACOPOSmulti line filter.
b) Disconnect the connection cable between the X5A connector on the ACOPOSmulti power supply module and the U2 / V2 / W2 connections of the ACOPOSmulti regeneration choke on the X5A connector of the ACOPOSmulti power supply module.
c) Perform the high voltage test on the U1 / V1 / W1 connectors of the ACOPOSmulti regeneration choke.
d) Disconnect the motor cable from the X5A / X5B connector on the ACOPOSmulti inverter module.
e) Perform the high voltage test on the B&R motor.

3 ACOPOSmotor SafeMOTION

3.1 System characteristics

3.1.1 Compact and safe



ACOPOSmotor modules combine the following components in a single compact unit:

- Servo drive
- Servo motor as an energy transducer
- The built-in position sensor

ACOPOSmotor modules deliver maximum performance through the use of advanced power component technology that minimizes power loss as well as a motor series optimized for motion applications.

Available in 3 different sizes, ACOPOSmotor modules cover the entire spectrum with a torque range of 5.7 to 17 Nm and a power range of 1 kW to 2.3 kW. For applications that demand more power, an optional fan component can be added at any time to boost performance considerably.

3.1.2 Decentralized and flexible

In terms of topology, the ACOPOSmotor module can be integrated into a simple line or tree structure. Node number assignment takes place automatically in the line structure. If the address still needs to be set, however, this can be done without opening the housing.

The connection to the drive network is made using a hybrid connector. It contains all power and signal lines needed to operate the ACOPOSmotor module as well as those required by the POWERLINK network.

Highly effective IP65 protection allows ACOPOSmotor modules to be mounted directly on the machine. The control cabinet then only has to contain the power supply, high-powered inverter modules and other necessary electromechanical components. This makes it much easier to implement modular machine architectures and optional machine functions since they can be easily connected – with the requisite dimensioning of the power supply – to the machine's main line using hybrid cables.

Also ideal for modular machine engineering is the ability to connect X67 modules directly to ACOPOSmotor modules, something that paves the way for implementing machine modules as completely self-sufficient and testable production units.

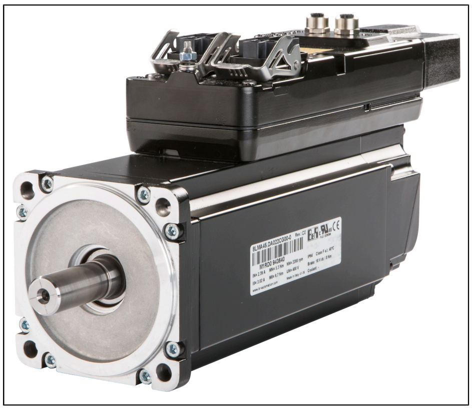
3.1.3 Homogeneous and compatible

ACOPOSmotor modules provide the well-known functionality of the ACOPOSmulti drive family and can therefore be completely integrated into a drive solution.

3.1.4 Cooling

8DI ACOPOSmotor modules are self-cooling and have a long, slim design. The modules must be installed on the cooling surface (flange).

3.1.5 ACOPOSmotor SafeMOTION



B&R's well-established safety solution – consisting of X20 SafeIO modules, SafeLOGIC controllers and the SafeDESIGNER toolset in Automation Studio – is rounded off by ACOPOSmulti SafeMOTION inverter modules and ACOPOSmotor SafeMOTION modules. All B&R "Integrated Safety Technology" products are optimized to work together, delivering elegant applications at extremely low cost levels.

openSAFETY sets technical standards

Although there are many new approaches to safe fieldbus systems, most of them are restricted by proprietary standards and sluggish response times. The B&R safety system – including its ACOPOSmotor SafeMOTION modules – takes a different approach by implementing openSAFETY across the board. This approach allows integrated safety functions such as Safely Limited Speed to be activated directly over the network instead of having to wire these types of safety-related signals to the drive.

Information is collected directly from its source via safe digital inputs and outputs before being distributed to the respective sensors and actuators – in this case, the drive with integrated safety functions – via a safe CPU, the SafeLOGIC controller. Connecting over a POWERLINK network makes it easy to achieve the best possible communication between the SafeLOGIC controller and the standard controller for non safety-related program engineering.

Short cycle times

Cycle times of 800 µs are achieved on ACOPOSmotor SafeMOTION modules while still satisfying SIL 3 requirements.

Modular, expandable system

Because not all drives and axes in a production machine are safety-related, ACOPOSmotor modules are offered both with and without integrated safety functionality (SafeMOTION). This makes it possible to combine safe and non-safe axes in an application as needed.

3.1.6 ACOPOSmotor configurations

ACOPOSmotor drive systems have access to multiple technology-specific functions whose performance, flexibility and capability have been remarkably proven in countless applications. The ACOPOSmotor functions listed below are basic functions that the user can switch between as needed within 400 µs. In addition, manipulations such as changes in product length, registration mark control, overlying torque control, brief process adaptations and quality checks can be carried out at any time.

- Point-to-point
- Electronic gears
- Electronic compensation gears
- Cross cutter
- Electronic cams
- Flying saws
- Line shafts
- CNC

ACOPOSmotor drive systems can be used in various configurations depending on the requirements of the application. The functions listed above are available to the user in each of the topology examples shown.

Reaction speeds are not influenced by the control system being used if technology functions are processed directly on the ACOPOSmotor drive system. Additional sensors and actuators must be integrated in the control system for more complex processes. In these cases, the level of performance depends mostly on the type of network and control system being used. The topology examples shown on the following pages provide an overview of the bandwidths that are possible with B&R automation components.

Decentralized architecture with ACOPOSremote and ACOPOSmotor

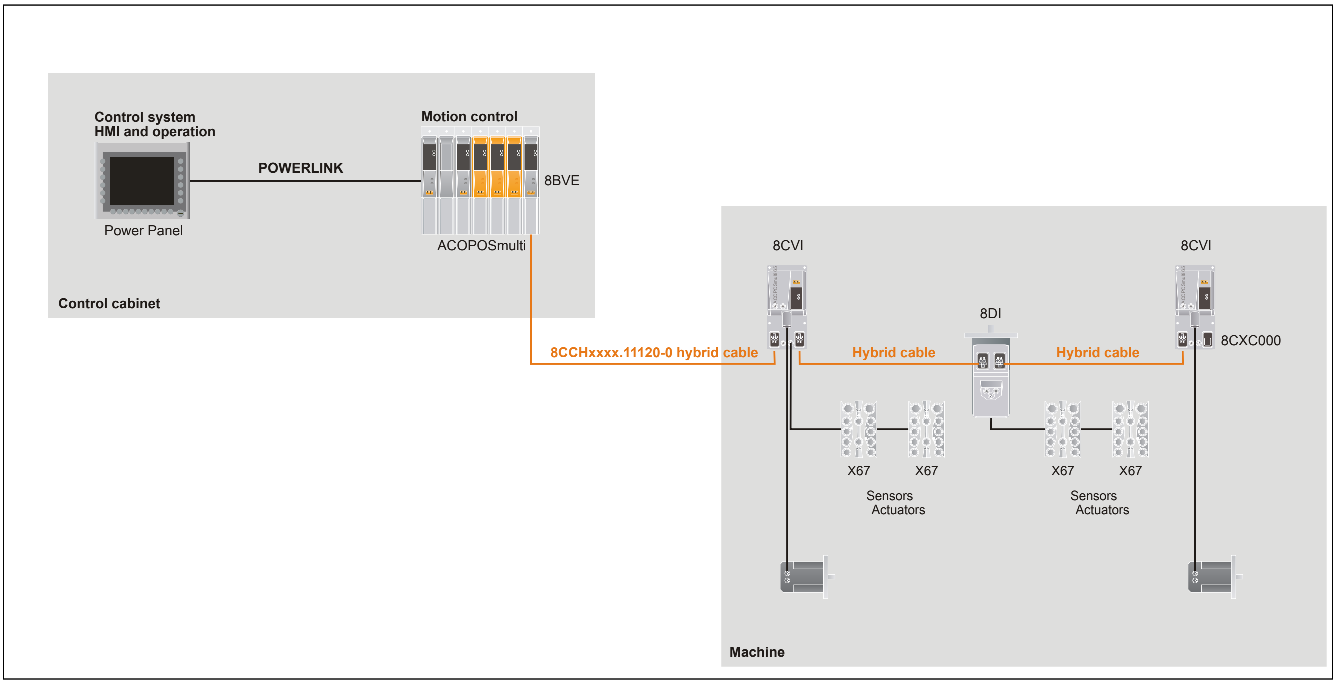


Figure 27: Decentralized architecture with ACOPOSremote and ACOPOSmotor

Decentralized architecture with connection box 8CVE, ACOPOSremote and ACOPOSmotor

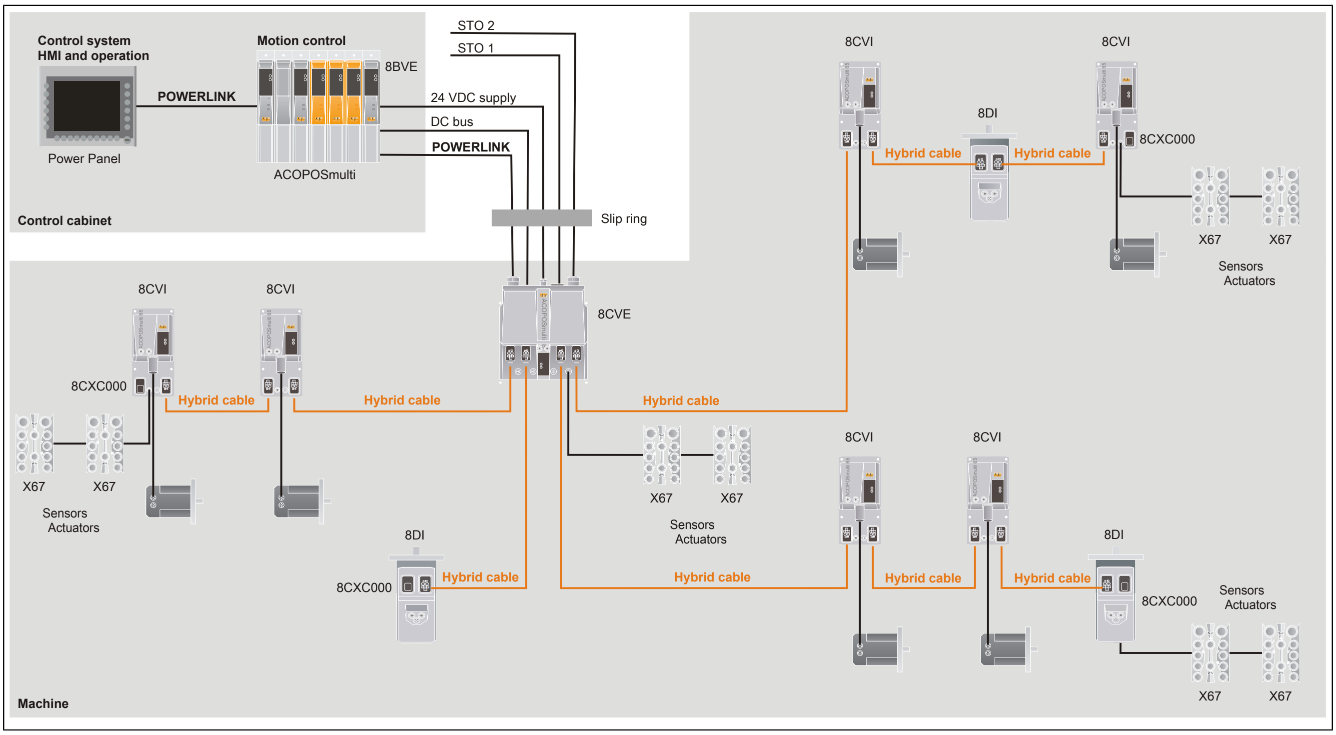


Figure 28: Decentralized architecture with connection box 8CVE, ACOPOSremote and ACOPOSmotor

3.1.7 Order key

8DI	c	d	e	.	ff	ggg	h	i	0	0	-	1

Size (see "Size")
Valid values: **3,4,5**

Length (see "Length")
Valid values: **3,4,5**

Safety technology (see "Safety technology")
Valid values: **0, S**

Encoder system (see "Encoder system")

For motor size 3:
S8/D8 ...inductive, EnDat 2.2 single-turn FS, 19-bit
S9/D9 ...inductive, EnDat 2.2 multi-turn FS, 12-bit

For motor sizes 4 and 5

SA/DA ...inductive, EnDat 2.2 single-turn FS, 19-bit
SB/DB ...inductive, EnDat 2.2 multi-turn FS, 12-bit

Nominal speed (see "Nominal speed")
ggg...Nominal speed/100, e.g. 015 corresponds to a nominal speed of 1500 rpm

Electronics options (see "Electronics options")

Motor options (see "Motor options")

Motor version assigned automatically

Other motor options must be arranged with B&R.

3.1.7.1 Size (c)

8DI ACOPOSmotor modules are available in three different sizes (3, 4 and 5). They have different dimensions (especially flange dimensions) and power ratings. These different sizes are indicated by a number represented by (c) in the model number. The larger the number, the larger the flange dimensions and power rating for the ACOPOSmotor module.

3.1.7.2 Length (d)

8DI ACOPOSmotor modules are available in three different sizes. They have different power ratings with identical flange dimensions. These different lengths are indicated by a number represented by (d) in the model number.

Length	Available sizes		
	3	4	5
3	Yes	No	No
4	Yes	Yes	Yes
5	No	Yes	Yes
6	No	Yes	Yes

3.1.7.3 Safety technology (e)

8DI ACOPOSmotor modules are delivered with wired safety technology or SafeMOTION EnDat 2.2. as a standard feature.

Name	Note	Code for order key
Wired safety technology	---	0
SafeMOTION EnDat 2.2	---	S

The following table lists the safety functions integrated in ACOPOSmotor SafeMOTION modules as well as the safety levels that can be achieved when they are used:

Safety function	ACOPOSmotor SafeMOTION	EN ISO 13849-1	EN 61508 / EN 62061	Safe Encoder evaluation Necessary
	Starting in Safety Release			
Safe Torque Off (STO)	R 1.10	PL e / Cat. 4	SIL 3	No
Safe Torque Off One Channel (STO1)	R 1.10	PL d / Cat. 3	SIL 2	No
Safe Operation Stop (SOS)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Stop 1 (SS1)	R 1.10	Time-based monitoring: PL e / Cat. 4 Ramp-based monitoring: PL d / Cat. 3	Time-based monitoring: SIL 3 Ramp-based monitoring: SIL 2	Time-based monitoring: No Ramp-based monitoring: Yes
Safe Stop 2 (SS2)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safely Limited Speed (SLS)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Maximum Speed (SMS)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Direction (SDI)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safely Limited Increment (SLI)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safely Limited Acceleration (SLA)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Brake Control (SBC) 1)	R 1.10	PL d / Cat. 3	SIL 2	No
Safely Limited Position (SLP)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Maximum Position (SMP)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Homing	R 1.10	PL d / Cat. 3	SIL 2	Yes
Remanent Safe Position (RSP)	R 1.10	PL d / Cat. 3	SIL 2	Yes

Table 80: ACOPOSmotor SafeMOTION: Safety functions and associated safety levels

1) Safety function SBC does not apply to the motor holding brake integrated in the ACOPOSmotor SafeMOTION; it is not safety-related.

3.1.7.4 Encoder system (ff)

EnDat 2.2 encoder

General information

Digital drive systems and position control loops require fast and highly secure transfer of data obtained from position measuring instruments. In addition, other data such as drive-specific characteristics, correction tables, etc. should also be available. To ensure a high level of system security, measuring instruments must be integrated in routines for detecting errors and be able to perform diagnostics.

The EnDat interface from HEIDENHAIN is a digital, bidirectional interface for measuring instruments. It is able to output position values from incremental and absolute measuring instruments and can also read and update information on the measuring instrument or store new data there. Because it relies on serial data transfer, only 4 signal lines are needed. Data is transferred synchronously to the clock signal defined by the subsequent electronics. The type of transfer used (e.g. for position values, parameters, diagnostics, etc.) is selected using mode commands sent to the measuring instrument by the subsequent electronics.

As a serial interface, EnDat 2.2 is also suitable for safety-related applications up to SIL 3.

Technical data

Name				
Order code (ff)	S8/D8	S9/D9	SA/DA	SB/DB
Can be used with	Size 3	Size 3	Motor sizes 4 and 5	Motor sizes 4 and 5
Encoder type	EnDat single-turn functional safety	EnDat multi-turn functional safety	EnDat single-turn functional safety	EnDat multi-turn functional safety
Operating principle	Inductive			
EnDat protocol	EnDat 2.2			
Position values per revolution	524 288 (19-bit)			
Distinguishable revolutions	---	4096 (12-bit)	---	4096 (12-bit)
Precision	±120"		±65"	
Vibration during operation 55 to 2000 Hz	Stator: ≤400 m/s², rotor: ≤600 m/s² (EN 60068-2-6) 1)		Stator: ≤200 m/s², rotor: ≤600 m/s² (IEC 60068-2-6) 2)	
Shock during operation Duration 6 ms	≤2.000 m/s² (EN 60068-2-27)			
Manufacturer's website	Dr. Johannes Heidenhain GmbH www.heidenhain.de			
Manufacturer's product ID	ECI 1119	EQI 1131	ECI 1319	EQI 1331

1) Valid according to the standard at room temperature;
10 to 55 Hz, constant path, 4.9 mm peak to peak
10 to 55 Hz, constant lift, 4.9 mm peak to peak
10 to 55 Hz, constant amplitude, 4.9 mm peak to peak

2) In accordance with the standard at room temperature; the following values apply at a working temperature up to 100°C: ≤300 m/s², up to 115°C: ≤150 m/s².
10 to 55 Hz, constant path, 4.9 mm peak to peak
10 to 55 Hz, constant lift, 4.9 mm peak to peak
10 to 55 Hz, constant amplitude, 4.9 mm peak to peak

3.1.7.5 Nominal speed (ggg)

The nominal speed is listed as part of the model number in the form of a 3-digit code (ggg). This code represents the nominal speed divided by 100.

Size	**Available nominal speeds n_N [rpm]**				
	2200 (code for order key: 022)			**4500 (code for order key: 045)**	
3	No	No	No	Yes	Yes
4	Yes	Yes	Yes	No	No
5	Yes	Yes	Yes	No	No
Length	**4**	**5**	**6**	**3**	**4**

3.1.7.6 Electronics options (h)

8DI ACOPOSmotor modules are available with optional external connections:

- One additional POWERLINK connection
- Two 24 VDC outputs for supplying external components (e.g. X67 modules)
- Two trigger inputs

The respective execution of the module is listed in the form of a 1-digit code (h) as part of the model number.

POWERLINK	**24 VDC outputs (2x)**	**Trigger inputs (2x)**	**Code for order key**
No	No	No	0
Yes	Yes	Yes	7

3.1.7.7 Motor options (i)

8DI ACOPOSmotor modules are available with the following features depending on size and length:

- With or without a holding brake
- With a smooth or keyed shaft end
- With or without an oil seal

The respective combination of motor options is listed in the form of a 1-digit code (i) as part of the model number.

Code for order key (i)	Holding brake	Design of the shaft end	Oil seal
0	No	Smooth shaft end	No
1			Yes
2		Keyed shaft end	No
3			Yes
4	Yes	Smooth shaft end	No
5			Yes
6		Keyed shaft end	No
7			Yes

Holding brake

All 8DI ACOPOSmotor modules can be delivered with a holding brake. It is installed directly behind the A-side flange on the module and is used to hold the motor shaft when the power is switched off on the ACOPOSmotor module.

The holding brake is a spring-loaded brake. Based on principle, this type of holding brake exhibits a minimal amount of backlash.

This brake is designed as a holding brake and is not permitted to be used for operational braking! Under these conditions, the brake has a service life of approximately 5,000,000 cycles (opening and closing the brake is one cycle). Loaded braking during an emergency stop is permitted but reduces its service life. The required brake holding torque is determined based on the actual load torque. If not enough information is known about the load torque, it is recommended to assume a safety factor of 2.

Name	ACOPOSmotor module		
	8DI3...	8DI4...	8DI5...
Holding torque M_{Br} [Nm]	3.2	9	18
Connected load P_{On} [W]	12	18	24
Activation delay t_{on} [ms]	29	40	50
Release delay t_{off} [ms]	19	7	10
Moment of inertia J_{Br} [kgcm²]	0.38	0.54	1.66
Mass m_{Br} [kg]	0.3	0.46	0.9

Table 81: Technical data for the holding brake per ACOPOSmotor module

Design of the shaft end

8DI ACOPOSmotor module shafts comply with the DIN 748 standard and are available with a smooth or keyed shaft end.

Smooth shaft end

A smooth shaft end is used for a force-fit shaft-hub connection and guarantees a backlash-free connection between the shaft and hub as well as a high degree of operating smoothness. The end of the shaft has a threaded center hole.

Keyed shaft end

A keyed shaft end is used for a form-fit torque transfer with low demands on the shaft-hub connection and for handling torque in a constant direction.

The keyways for 8DI ACOPOSmotor modules conform to keyway form N1 in accordance with DIN 6885-1. Form A keyed shafts that conform to DIN 6885-1 are used. Balancing motors with keyways is done using the shaft and fitment key convention in accordance with DIN ISO 8821.

The end of the shaft has a threaded center hole that can be used to mount machine actuators with shaft end cover plates.

Oil seal

All 8DI ACOPOSmotor modules are available with an optional Form A oil seal in accordance with DIN 3760.

When equipped with an oil seal, 8DI ACOPOSmotor modules have IP65 protection in accordance with EN 60034-5.

Proper lubrication of the oil seal must be ensured throughout the entire service life of the motor.

3.1.7.8 Version

ACOPOSmotor module versions are assigned automatically.

3.1.8 8ZDFB fan kits

8DI ACOPOSmotor modules can be optionally equipped with a fan kit depending on size. The fan kit considerably improves the nominal values of 8DI ACOPOSmotor modules (see speed-torque characteristic curve for the respective 8DI ACOPOSmotor module).

The fan kit is mounted on the back of the 8DI ACOPOSmotor module, with 24 VDC supplied to the fan kit either externally or via connector X31 on the ACOPOSmotor module (8DIcde.ffggg**7**i00-1).

Size	Corresponding fan kit
3	In preparation
4	8ZDFB4000000.000-0
5	8ZDFB5000000.000-0

3.1.9 Load capacity of the shaft end and bearings

8DI ACOPOSmotor modules are equipped with grooved ball bearings that are sealed on both sides and lubricated. Radial and axial forces (F_r, F_a) applied to the shaft end during operation and installation must be within the specifications listed below. Bearing elements must not be subjected to shocks or impacts! Incorrect handling will reduce the service life and result in damage to the bearings.

The axial forces F_a permitted during the installation of pinion gears, couplings, etc. depend on the size of the ACOPOSmotor module and can be found in the following table:

Size	Permissible axial force F_a [N]
	Standard bearing
3	1400
4	2300
5	2500

Radial force

The radial force F_r on the shaft end is a function of the loads during installation (e.g. belt tension on pulleys) and operation (e.g. load torque on the pinion). The maximum radial force F_r depends on the shaft end type, bearing type, average speed, the position where the radial force is applied and the desired service life of the bearings.

Axial force, shift in shaft position caused by axial force

The axial force F_a on the shaft end is a function of the loads during installation (e.g. stress caused by mounting) and operation (e.g. thrust caused by slanted tooth pinions). The maximum axial force F_a depends on the bearing type and the desired lifespan of the bearings. The fixed bearing is secured on the A flange with a retaining ring. The floating bearing is preloaded on the B flange with a spring in the direction of the A flange. Axial forces in the direction of the B flange can cause the spring bias to be overcome, which shifts the shaft by the amount of axial backlash in the bearing (approx. 0.1 - 0.2 mm). This shift can cause problems on ACOPOSmotor modules with holding brakes or ACOPOSmotor modules with EnDat encoders (D8, D9, DA and DB). As a result, no axial force is permitted in the direction of the B flange when using these ACOPOSmotor modules.
Axial loads are not permitted on shaft ends of ACOPOSmotor modules with holding brakes. It is especially important to prevent axial forces in the direction of the B flange since these forces can cause the brake to fail!

Determining permissible values of F_r and F_a

Information for determining permissible values of F_r and F_a can be found in the technical data for the respective ACOPOSmotor modules. Permissible values are based on a bearing lifespan of 20,000 h (bearing lifespan calculation based on DIN ISO 281).

Definitions for maximum shaft load diagrams

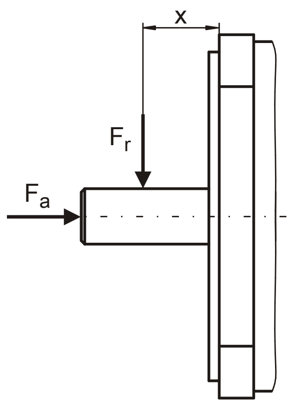


Figure 29: Definition of shaft load

- F_r.......... Radial force
- F_a......... Axial force
- x........... Distance between the motor flange and the point where radial force Fr is applied

3.2 Status indicators

3.2.1 ACOPOSmotor SafeMOTION

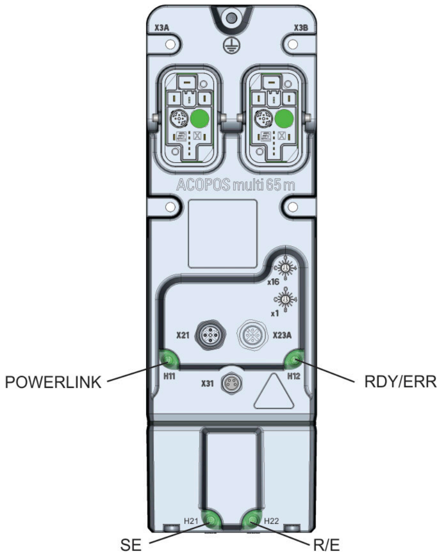


Figure 30: ACOPOSmotor SafeMOTION - Display

3.2.1.1 LED status indicators

Status indicator group	Label	Color	Function	Description
POWERLINK	R/E	Green/Red	Ready/Error	see "POWERLINK - LED status indicators" on page 169
Power inverter	RDY	Green	Ready	see "RDY/ERR - LED status indicators" on page 169
	RUN	Orange	Run	
	ERR	Red	Error	
Power supply	24 V	Green	24 V OK	The 24 V module power supply voltage is within the tolerance range.
Status of SafeMOTION module	R/E	Green/Red	Ready/Error	see "SafeMOTION module - LED status indicators" on page 170
Safety status of SafeMOTION module	SE	Red	Safe/Error	

Table 82: 8BVI SafeMOTION inverter modules (1-axis modules) - LED status indicators

3.2.1.2 RDY/ERR - LED status indicators

Label	Color	Function	Description	
H12	Green	Ready	Solid green	The module is operational and the power stage can be enabled (operating system present and booted, no permanent or temporary errors).
			Blinking green	The module is not ready for operation. **Examples:** • No signal on one or both enable inputs • DC bus voltage outside the tolerance range • Overtemperature on the motor (temperature sensor) • Motor feedback not connected or defective • Motor temperature sensor not connected or defective • Overtemperature on the module (IGBT junction, heat sink, etc.) • Disturbance on network
	Red	Error	Solid red	There is a permanent error on the module. **Examples:** • Permanent overcurrent • Invalid data in EPROM

Table 83: RDY/ERR - LED status indicators

3.2.1.3 POWERLINK - LED status indicators

Label	Color	Function	Description	
H11	Green/Red	Ready/Error	LED off	The module is not receiving power or initialization of the network interface has failed.
			Solid red	The POWERLINK node number of the module is 0.
			Blinking red/green	The client is in an error state (drops out of cyclic operation).

Table 84: POWERLINK - LED status indicators

Label	Color	Function	Description	
			Blinking green (1x)	The client detects a valid POWERLINK frame on the network.
			Blinking green (2x)	Cyclic operation on the network is taking place, but the client itself is not yet a participant.
			Blinking green (3x)	Cyclic operation of the client is in preparation.
			Solid green	The client is participating in cyclic operation.
			Flickering green	The client is not participating in cyclic operation and also does not detect any other stations on the network participating in cyclic operation.

Table 84: POWERLINK - LED status indicators

3.2.1.4 SafeMOTION module - LED status indicators

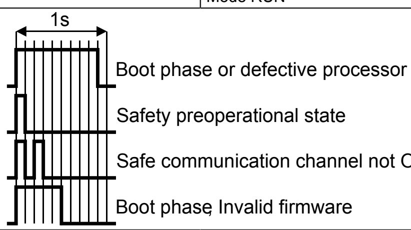
LED	Function	Color		Description
H22	Ready/Error	Green	Red	
		Off	Off	Module not supplied with current, no communication
		Single flash		Unlink mode
		Double flash		Updating firmware
		Blinking		PREOPERATIONAL mode
		On		Mode RUN
		On	Single flash, inverse	Safety-related firmware invalid
			Triple flash, inverse	Updating safety-related firmware
			On	Communication error
		Off	On	Errors
H21	Safe/Error	Red	Off	Mode RUN
				
			On	Non-acknowledgeable error state, FAIL SAFE state
		The two "H21" indicators are two separate LEDs that show the states of safety processor 1 and safety processor 2.		

Table 85: SafeMOTION module - LED status indicators

Danger!

Constantly lit "SE" LEDs indicate a non-acknowledgeable FAIL SAFE state. The cause of this could be a defective module or faulty configuration.
Check the entries in the logbook! If you are able to rule out a faulty configuration, then the module is defective and must be replaced immediately.

It is your responsibility to ensure that all necessary repair measures or corrections to the configuration are initiated after an error occurs since subsequent errors can result in dangerous situations!

3.2.1.5 Status changes when starting up the operating system loader

The following intervals are used for the LED status indicators:

Width of box: 50 ms
Repeats after: 3,000 ms

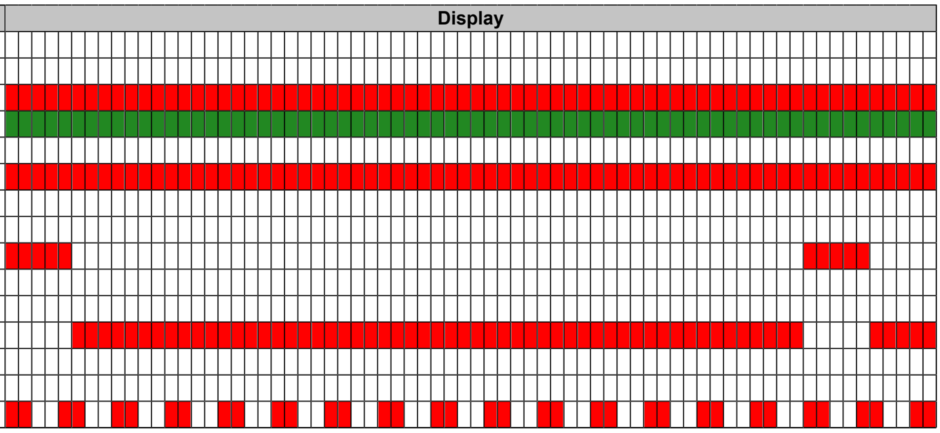
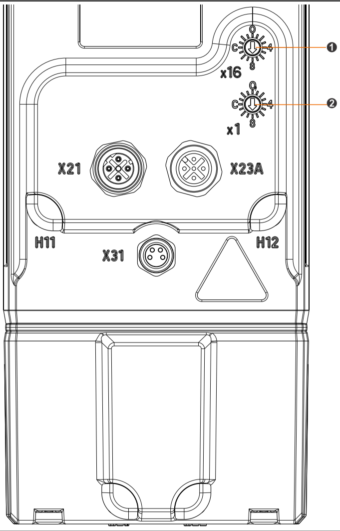
Status	LED	Display
1. Boot procedure for base hardware active	RDY	
	RUN	
	ERR	
2. Network configuration active	RDY	
	RUN	
	ERR	
3. Waiting for network telegram	RDY	
	RUN	
	ERR	
4. Network communication active	RDY	
	RUN	
	ERR	
5. ACOPOS operating system being transferred/burned [1]	RDY	
	RUN	
	ERR	

Table 86: Status changes when starting up the operating system loader

1) Firmware V2.140 and later.

3.2.1.6 POWERLINK node number setting

The POWERLINK station number can be set using the two coded hexadecimal rotary switches located on top of the module:

<table>
<tr><th>Figure</th><th>Coded rotary switches</th><th>POWERLINK node number</th></tr>
<tr><td rowspan="3">
</td><td>1</td><td>16s position (high)</td></tr>
<tr><td>2</td><td>1s position (low)</td></tr>
<tr><td colspan="2">Changed POWERLINK node numbers will not take effect until the drive system is restarted.

Information:

In principle, node numbers between $01 and $FD are permitted. However, node numbers between $F0 and $FD are intended for future system expansions. To ensure compatibility, these node numbers should be avoided.

Node numbers $00, $FE and $FF are reserved and may therefore not be set.</td></tr>
</table>

3.3 Data sheets

3.3.1 ACOPOSmotor SafeMOTION modules

Danger!

An ACOPOSmotor SafeMOTION module can only be replaced in its entirety. Replacing individual components is not possible since they are permanently installed.

3.3.1.1 ACOPOSmotor SafeMOTION with electronics options - Order data

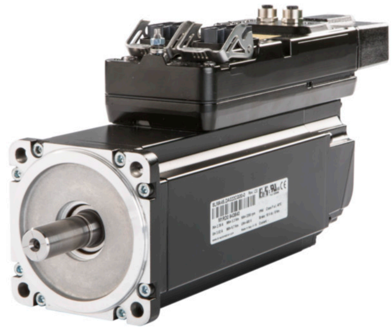
Model number	Short description	Figure
	ACOPOSmotor	
8DIcde.ffggg7i00-1	ACOPOSmotor module configuration with electronics options 1x PLK, 1x 24VOut, 2x trigger	
	Required accessories	
	Threaded caps	
X67AC0M08	X67 M8 threaded caps, 50 pcs.	
X67AC0M12	X67 M12 threaded caps, 50 pcs.	
	Accessory sets	
8CXC000.0000-00	Accessory set: 1x slot cover for male hybrid connector	
	Optional accessories	
	Hybrid cable	
8CCH0001.11110-1	Hybrid cable, length 1 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 2x 15-pin female hybrid connector	
8CCH0002.11110-1	Hybrid cable, length 2 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 2x 15-pin female hybrid connector	
8CCH0005.11110-1	Hybrid cable, length 5 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 2x 15-pin female hybrid connector	
8CCH01X1.11110-1	Hybrid cable, length 1.10 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 2x 15-pin female hybrid connector	
8CCH01X2.11110-1	Hybrid cable, length 1.20 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 2x 15-pin female hybrid connector	
	I/O supply cables	
X67CA0P00.0010	Power connection cable, 1 m	
X67CA0P00.0020	Power connection cable, 2 m	
X67CA0P00.0050	Power connection cable, 5 m	
X67CA0P10.0010	Power connection cable, angled, 1 m	
X67CA0P10.0020	Power connection cable, angled, 2 m	
X67CA0P10.0050	Power connection cable, angled, 5 m	
X67CA0P40.0002	Power open-ended cable, 0.20 m	
X67CA0P40.0020	Power open-ended cable, 2m	
X67CA0P40.0050	Power open-ended cable, 5m	
	Pre-assembled cables	
X67CA0E41.0010	POWERLINK attachment cable, RJ45 to M12, 1 m	
X67CA0E41.0050	POWERLINK attachment cable, RJ45 to M12, 5 m	
X67CA0E61.0020	POWERLINK connection cable, M12 to M12, 2 m	
X67CA0E61.0050	POWERLINK connection cable, M12 to M12, 5 m	
X67CA0E61.0100	POWERLINK connection cable, M12 to M12, 10 m	
	Sensor cable	
X67CA0A41.0020	M12 sensor cable, 2 m	
X67CA0A41.0050	M12 sensor cable, 5 m	
X67CA0A41.0100	M12 sensor cable, 10 m	
X67CA0A51.0020	M12 sensor cable, angled, 2 m	
X67CA0A51.0050	M12 sensor cable, angled, 5 m	
X67CA0A51.0100	M12 sensor cable, angled, 10 m	
	8BVE/8CVI connection cables	
8CCH0002.11120-1	Hybrid cable for connecting 8BVE to 8CVI or 8DI, length 2 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 1x 15-pin female hybrid connector	
8CCH0005.11120-1	Hybrid cable for connecting 8BVE to 8CVI or 8DI, length 5 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 1x 15-pin female hybrid connector	
8CCH0007.11120-1	Hybrid cable for connecting 8BVE to 8CVI or 8DI, length 7 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 1x 15-pin female hybrid connector	
8CCH0010.11120-1	Hybrid cable for connecting 8BVE to 8CVI or 8DI, length 10 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 1x 15-pin female hybrid connector	

Table 87: 8DIcde.ffggg7i00-1 - Order data

3.3.1.2 ACOPOSmotor SafeMOTION without electronics options - Order data

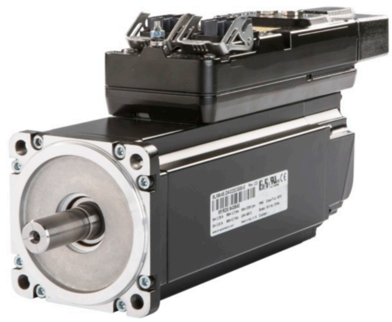
Model number	Short description	Figure
	ACOPOSmotor	
8DIcde.ffggg0i00-1	ACOPOSmotor module configuration without electronics options	
	Required accessories	
	Accessory sets	
8CXC000.0000-00	Accessory set: 1x slot cover for male hybrid connector	
	Optional accessories	
	Hybrid cable	
8CCH0001.11110-1	Hybrid cable, length 1 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 2x 15-pin female hybrid connector	
8CCH0002.11110-1	Hybrid cable, length 2 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 2x 15-pin female hybrid connector	
8CCH0005.11110-1	Hybrid cable, length 5 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 2x 15-pin female hybrid connector	
8CCH01X1.11110-1	Hybrid cable, length 1.10 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 2x 15-pin female hybrid connector	
8CCH01X2.11110-1	Hybrid cable, length 1.20 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 2x 15-pin female hybrid connector	
	8BVE/8CVI connection cables	
8CCH0002.11120-1	Hybrid cable for connecting 8BVE to 8CVI or 8DI, length 2 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 1x 15-pin female hybrid connector	
8CCH0005.11120-1	Hybrid cable for connecting 8BVE to 8CVI or 8DI, length 5 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 1x 15-pin female hybrid connector	
8CCH0007.11120-1	Hybrid cable for connecting 8BVE to 8CVI or 8DI, length 7 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 1x 15-pin female hybrid connector	
8CCH0010.11120-1	Hybrid cable for connecting 8BVE to 8CVI or 8DI, length 10 m, 2x 2x 0.34 mm² + 4x 0.75 mm² + 5x 2.5 mm², 1x 15-pin female hybrid connector	

Table 88: 8DIcde.ffggg0i00-1 - Order data

3.3.1.3 Technical data

3.3.1.3.1 General information

Product ID	
General information	
Module type	ACOPOSmotor module
Current-carrying capacity of the 19-pin hybrid connector	
Power contacts	Max. 20 A at 40°C
Certification	
CE	Yes
cULus	In preparation
FSC	In preparation
Support	
Software	
ACP10	V3.14 or higher
Thermal characteristics	
Methods of cooling in accordance with EN 60034-6 (IC code)	
Standard	Self-cooled; no separate surface cooling (IC4A0A0)
With 8ZBDF fan kit installed	Externally-cooled; surface cooling with independent cooling module attached (IC4A0A6)
Operating conditions	
Construction and mounting arrangement type in accordance with EN 60034-7 (IM code)	Horizontal (IM3001); Vertical, motor stands on the machine (IM3031)
Reduction of the nominal current and stall current at installation elevations over 500 m above sea level	10% per 1000 m
Reduction of the continuous power at installation elevations over 500 m above sea level	10% per 1000 m
Installation at elevations above sea level	
Nominal	0 to 500 m
Maximum [1]	4000 m
Pollution degree in accordance with EN 60664-1	2 (non-conductive pollution)
Overvoltage category in accordance with IEC 60364-4-443:1999	III
EN 60529 protection [2]	Without optional oil seal: IP64 With optional oil seal: IP65 With 8ZDFB fan kit installed: IP24

Table 89: General information - Technical data

Product ID	
Environmental conditions	
Temperature	
Operation	
Nominal	5 to 40°C
Maximum	55°C 3)
Storage	-25 to 55°C
Transport	-25 to 70°C
Max. flange temperature	65°C
Relative humidity	
Operation	5 to 85%, non-condensing
Storage	5 to 95%, non-condensing
Transport	Max. 95% at 40°C
Mechanical characteristics	
Motor coating	Water-based paint, RAL 9005 flat
Inverter coating	Electrophoretic deposition (EPD), black
Vibration severity in accordance with EN 60034-14	Vibration severity grade A 4)
Roller bearing, dynamic load ratings and nominal service life	Based on DIN ISO 281
Shaft end in accordance with DIN 748	Form E
Oil seal in accordance with DIN 3760	Form A
Key and keyway in accordance with DIN 6885-1	Keyway form N1; key form A
Balancing the shaft in accordance with DIN ISO 8821	Half-key arrangement
Mounting flange in accordance with DIN 42948	Form A
Smooth rotation of shaft end, coaxial properties and mounting flange plane in accordance with DIN 42955	Tolerance R

Table 89: General information - Technical data

1) Continuous operation at elevations ranging from 500 m to 4000 m above sea level is possible (taking the specified continuous current reductions into consideration). Requirements that go beyond this must be arranged with B&R.
2) The specified level of protection is only in place if all connectors on the module that are not being used are closed with suitable caps or covers. Suitable caps and covers are available as optional accessories (X67AC0M08, X67AC0M12, 8CXC000.0000-00). The module is rated at IP20 when delivered.
3) Continuous operation at ambient temperatures ranging from 40°C to max. 55°C is possible (taking the specified continuous torque reductions into consideration), but this will result in a shorter service life.
4) Vibration severity grade B on request.

3.3.1.3.2 Inverter module

Product ID	8DIcde.ffggg7i00-1	8DIcde.ffggg0i00-1
DC bus connection		
Voltage		
Nominal	750 VDC	
Continuous power consumption 1)	$(P_N/0.97) + P_{IM}$	
DC bus capacitance	Size 3 (8DI3x): 10 µF Size 4 (8DI4x): 15 µF Size 5 (8DI5x): 24 µF	
Design	19-pin hybrid connector 2)	
Cable length		
Maximum	30 m	
24 VDC supply		
Input voltage	24 VDC +20% / -25%	
Input capacitance	120 µF	
Max. power consumption	10 W + $P_{HoldingBrake}$ + $P_{24\ VDC\ Out\ 1}$[0 ... 96 W] + $P_{24\ VDC\ Out\ 2}$[0 ... 12 W]	
Design	19-pin hybrid connector 2)	
Cable length		
Maximum	30 m	
24 VDC Out 1		
Output voltage	Depends on the 24 VDC supply	-
Continuous current	Max. 4 A	-
Fuse protection	Electronic	-
Design		
24 VDC	M8 connector	-
COM	M8 connector	-
Cable length		
Maximum	30 m	
24 VDC Out 2		
Output voltage	Depends on the 24 VDC supply	-
Continuous current	Max. 0.5 A	-
Fuse protection	Electronic	-
Design		
24 VDC	M12 connector	-
COM	M12 connector	-

Table 90: 8DIcde.ffggg7i00-1, 8DIcde.ffggg0i00-1 - Technical data

Product ID	8DIcde.ffggg7i00-1	8DIcde.ffggg0i00-1
Cable length		
Maximum	30 m	
Motor connection		
Nominal switching frequency	5 kHz	
Possible switching frequencies 3)	5 / 10 / 20 kHz	
Max. output frequency	598 Hz 4)	
Motor holding brake connection		
Quantity	1	
Continuous current	1 A	
Max. switching frequency	0.5 Hz	
Response threshold for undervoltage monitoring	24 VDC -25%	
Fieldbus		
Type	POWERLINK V1/V2 100BASE-T (ANSI/IEE 802.3)	
Design	Internal 2-port hub, 2x 19-pin male hybrid connector	
Cable length	Max. 100 m between two stations (segment length) 5)	
Transfer rate	100 Mbit/s	
Enable inputs		
Quantity	2 6)	
Trigger inputs		
Quantity	2	-
Wiring	Sink	-
Electrical isolation		
Input - Inverter module	No	-
Input - Input	No	-
Input voltage		
Nominal	24 VDC	-
Maximum	30 VDC	-
Switching threshold		
Low	<5 V	-
High	>15 V	-
Input current at nominal voltage	5 mA	-
Switching delay		
Rising edge	In preparation	-
Falling edge	In preparation	-
Modulation compared to ground potential	Max. ±38 V	-
Design	M12 connector	-
Cable length		
Maximum	30 m	
Support		
Software		
ACP10	V3.14 and higher	

Table 90: 8DIcde.ffggg7i00-1, 8DIcde.ffggg0i00-1 - Technical data

1) Valid in the following conditions: 750 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
2) It is important to note that the 19-pin hybrid connector is designed for max. 5 connection cycles.
3) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
4) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output (power unit: limit speed exceeded).
5) Limited to 30 m when using hybrid cables.
6) The enable inputs are continuous. They have no function on SafeMOTION modules, however.

3.3.1.3.3 Encoder

<table>
<tr><th>Name</th><th></th><th></th><th></th><th></th></tr>
<tr><td>Order code (ff)</td><td>S8/D8</td><td>S9/D9</td><td>SA/DA</td><td>SB/DB</td></tr>
<tr><td>Can be used with</td><td>Size 3</td><td>Size 3</td><td>Motor sizes 4 and 5</td><td>Motor sizes 4 and 5</td></tr>
<tr><td>Encoder type</td><td>EnDat single-turn functional safety</td><td>EnDat multi-turn functional safety</td><td>EnDat single-turn functional safety</td><td>EnDat multi-turn functional safety</td></tr>
<tr><td>Operating principle</td><td colspan="4">Inductive</td></tr>
<tr><td>EnDat protocol</td><td colspan="4">EnDat 2.2</td></tr>
<tr><td>Position values per revolution</td><td colspan="4">524 288 (19-bit)</td></tr>
<tr><td>Distinguishable revolutions</td><td>---</td><td>4096 (12-bit)</td><td>---</td><td>4096 (12-bit)</td></tr>
<tr><td>Precision</td><td colspan="2">±120"</td><td colspan="2">±65"</td></tr>
<tr><td>Vibration during operation
55 to 2000 Hz</td><td colspan="2">Stator: ≤400 m/s², rotor: ≤600 m/s² (EN 60068-2-6) [1)]</td><td colspan="2">Stator: ≤200 m/s², rotor: ≤600 m/s² (IEC 60068-2-6) [2)]</td></tr>
<tr><td>Shock during operation
Duration 6 ms</td><td colspan="4">≤2.000 m/s² (EN 60068-2-27)</td></tr>
<tr><td>Manufacturer's website</td><td colspan="4">Dr. Johannes Heidenhain GmbH www.heidenhain.de</td></tr>
<tr><td>Manufacturer's product ID</td><td>ECI 1119</td><td>EQI 1131</td><td>ECI 1319</td><td>EQI 1331</td></tr>
</table>

1) Valid according to the standard at room temperature;
10 to 55 Hz, constant path, 4.9 mm peak to peak
10 to 55 Hz, constant lift, 4.9 mm peak to peak
10 to 55 Hz, constant amplitude, 4.9 mm peak to peak

2) In accordance with the standard at room temperature; the following values apply at a working temperature up to 100°C: ≤300 m/s², up to 115°C: ≤150 m/s².
10 to 55 Hz, constant path, 4.9 mm peak to peak
10 to 55 Hz, constant lift, 4.9 mm peak to peak
10 to 55 Hz, constant amplitude, 4.9 mm peak to peak

3.3.1.4 Size 3

3.3.1.4.1 Technical data

Model number	8DI33S.ff045hi00-1	8DI34S.ff045hi00-1
Motor		
Nominal speed n_N [rpm]	4500	
Number of pole pairs	4	
Nominal torque M_n [Nm]	1.17	1.52
Nominal power P_N [W]	551	716
Nominal current I_N [A]	1.08	1.39
Stall torque M_0 [Nm]	2.4	2.86
Stall current I_0 [A]	2.22	2.62
Maximum torque M_{max} [Nm]	6.12	9.81
Maximum current I_{max} [A]	5.67	9
Maximum speed n_{max} [rpm]	6600	
Torque constant K_T [Nm/A]	1.08	1.09
Voltage constant K_E [V/1000 rpm]	65.97	
Stator resistance R_{2ph} [Ω]	4.81	3.9
Stator inductance L_{2ph} [mH]	19.81	16.5
Thermal time constant t_{therm} [min]	34	38
Moment of inertia J [kgcm²]	0.95	1.2
Mass without brake m [kg]	4.7	5.6

Table 91: 8DI33S.ff045hi00-1, 8DI34S.ff045hi00-1 - Technical data

3.3.1.4.2 8DI33e.ffggghi00-I - Speed-torque characteristic curve

With 560 VDC DC bus voltage

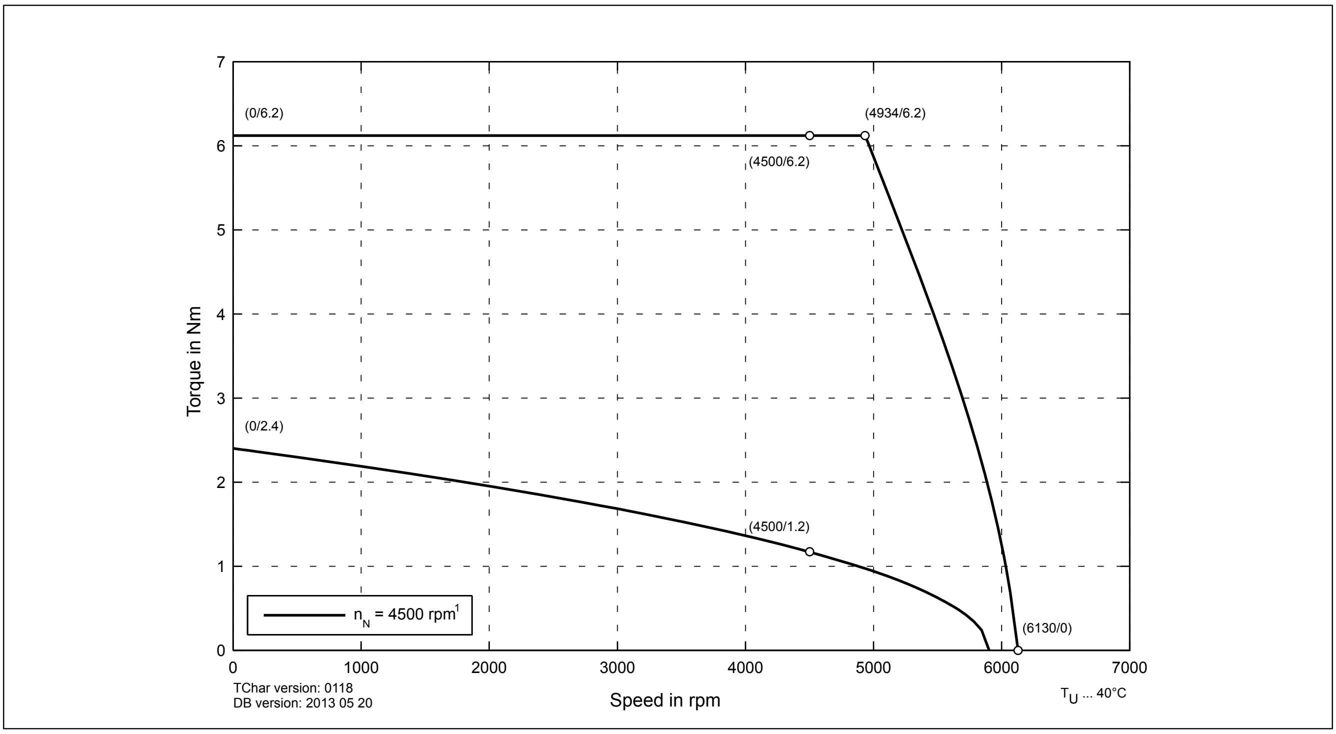


Figure 31: 8DI33e.ffggghi00-1 with 560 VDC DC bus voltage - Speed-torque characteristic curve

With 750 VDC DC bus voltage

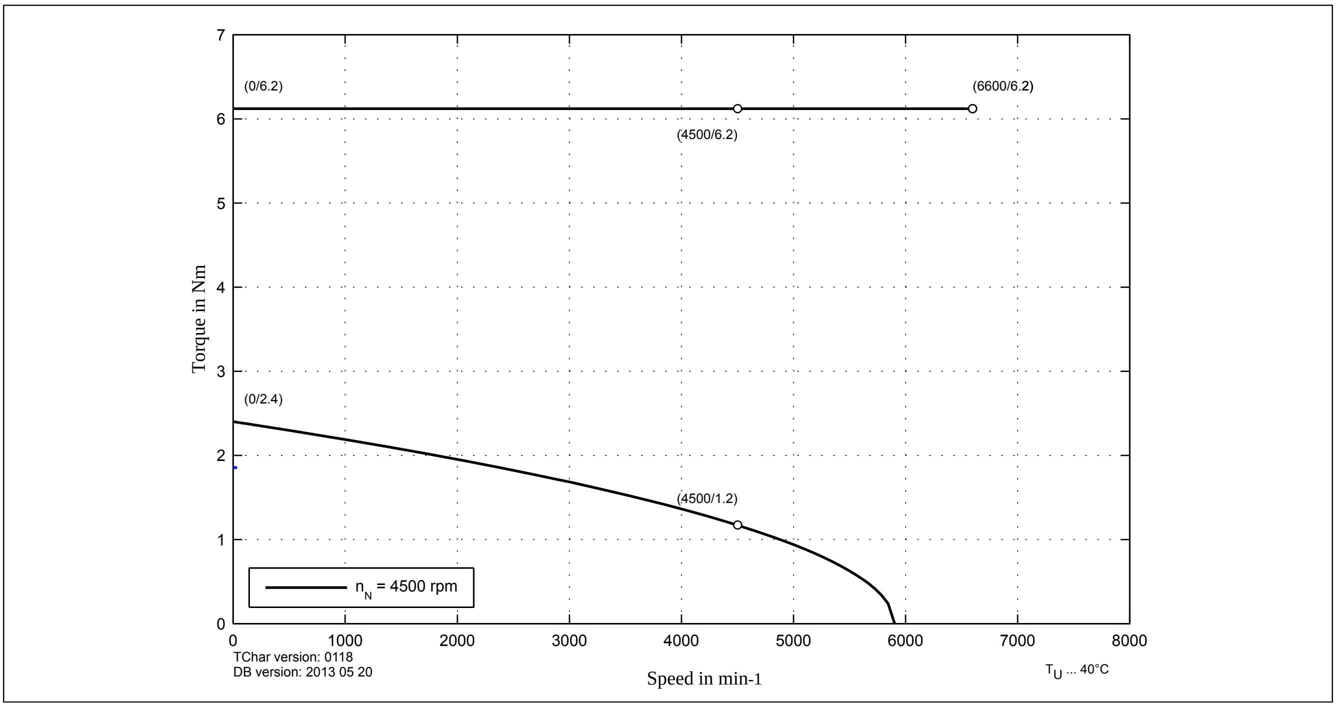


Figure 32: 8DI33e.ffggghi00-1 with 750 VDC DC bus voltage - Speed-torque characteristic curve

3.3.1.4.3 8DI34e.ffggghi00-I - Speed-torque characteristic curve

With 560 VDC DC bus voltage

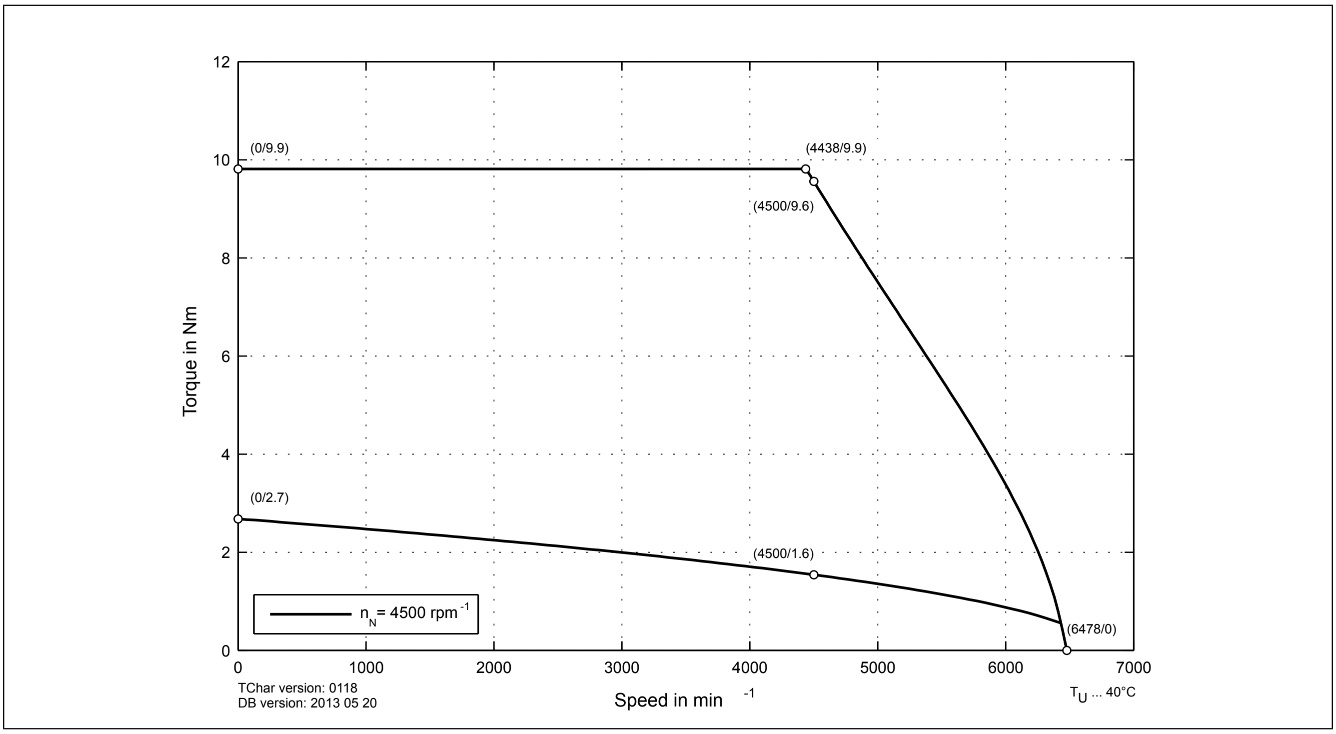


Figure 33: 8DI34e.ffggghi00-1 with 560 VDC DC bus voltage - Speed-torque characteristic curve

With 750 VDC DC bus voltage

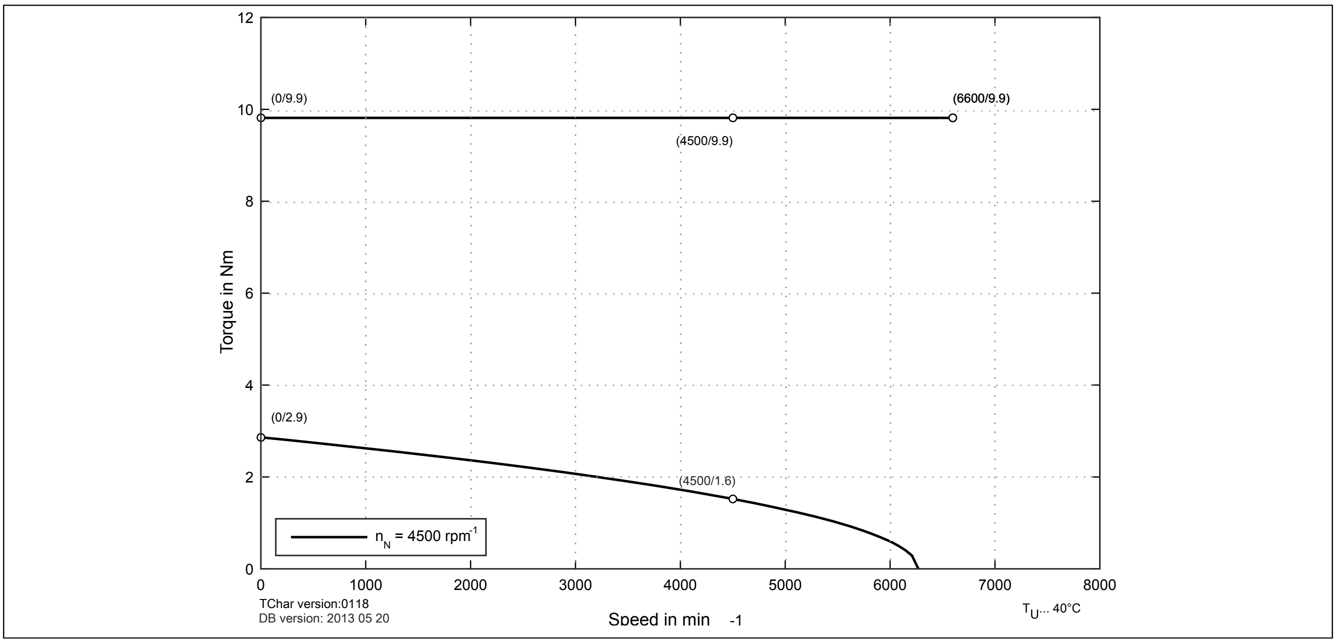
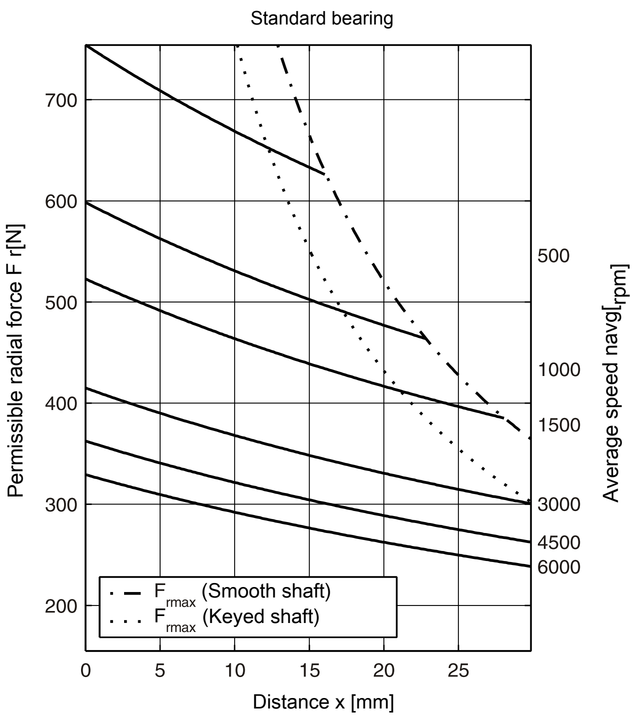


Figure 34: 8DI34e.ffggghi00-1 with 750 VDC DC bus voltage - Speed-torque characteristic curve

3.3.1.4.4 Maximum shaft load

The values in the diagram below are based on a mechanical service life of the bearings of 20,000 operating hours.



Maximum axial force: Famax = 66 N

3.3.1.5 Size 4

3.3.1.5.1 Technical data

Model number	8DI44S.ff022hi00-1	8DI45S.ff022hi00-1	8DI46S.ff022hi00-1
Motor			
Nominal speed n_N [rpm]	2200		
Number of pole pairs	5		
Nominal torque M_n [Nm]	5	5.1	5.2
Nominal power P_N [W]	1037	1175	1198
Nominal current I_N [A]	2.26	2.4	2.35
Stall torque M_0 [Nm]	5.7	6.7	7.7
Stall current I_0 [A]	2.57	3.02	3.49
Maximum torque M_{max} [Nm]	20.5	27.4	31.1
Maximum current I_{max} [A]	14.46	19.29	21
Maximum speed n_{max} [rpm]	12000		
Torque constant K_T [Nm/A]	2.22		
Voltage constant K_E [V/1000 rpm]	134.04		
Stator resistance R_{2ph} [Ω]	6.24	4.32	3.61
Stator inductance L_{2ph} [mH]	44.8	41	32
Electrical time constant t_{el} [ms]	In preparation	9.49	8.86
Thermal time constant t_{therm} [min]	30	35	40
Moment of inertia J [kgcm²]	2.73	3.58	4.39
Mass without brake m [kg]	5.26	6.7	8.1

Table 92: 8DI44S.ff022hi00-1, 8DI45S.ff022hi00-1, 8DI46S.ff022hi00-1 - Technical data

3.3.1.5.2 Speed-torque characteristic curve with 560 VDC DC bus voltage

8DI44e.ffggghi00-1

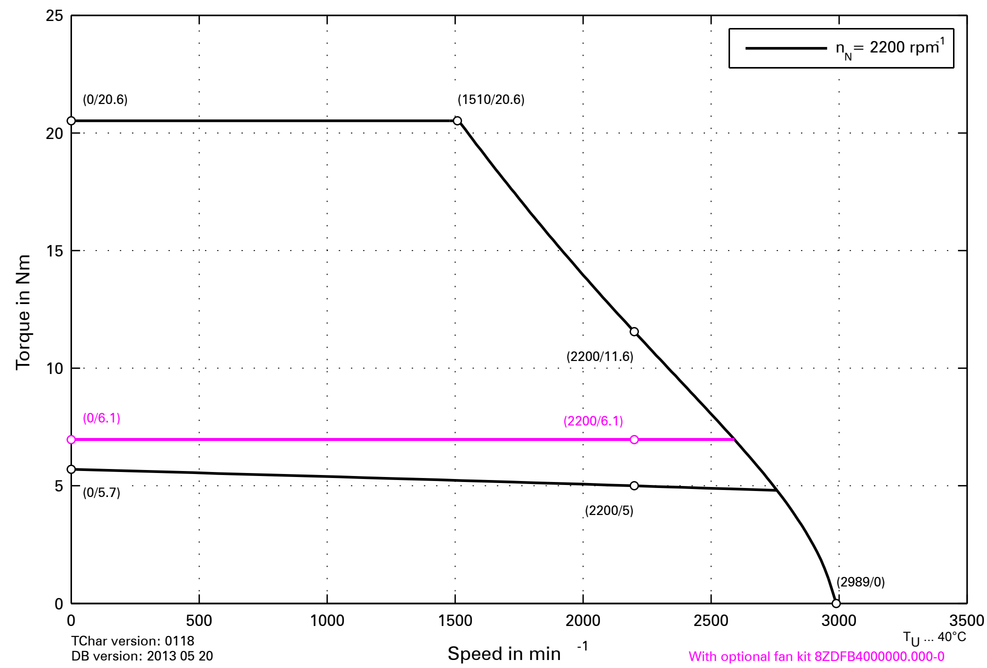


Figure 35: 8DI44e.ffggghi00-1 - Speed-torque characteristic curve

8DI45e.ffggghi00-1

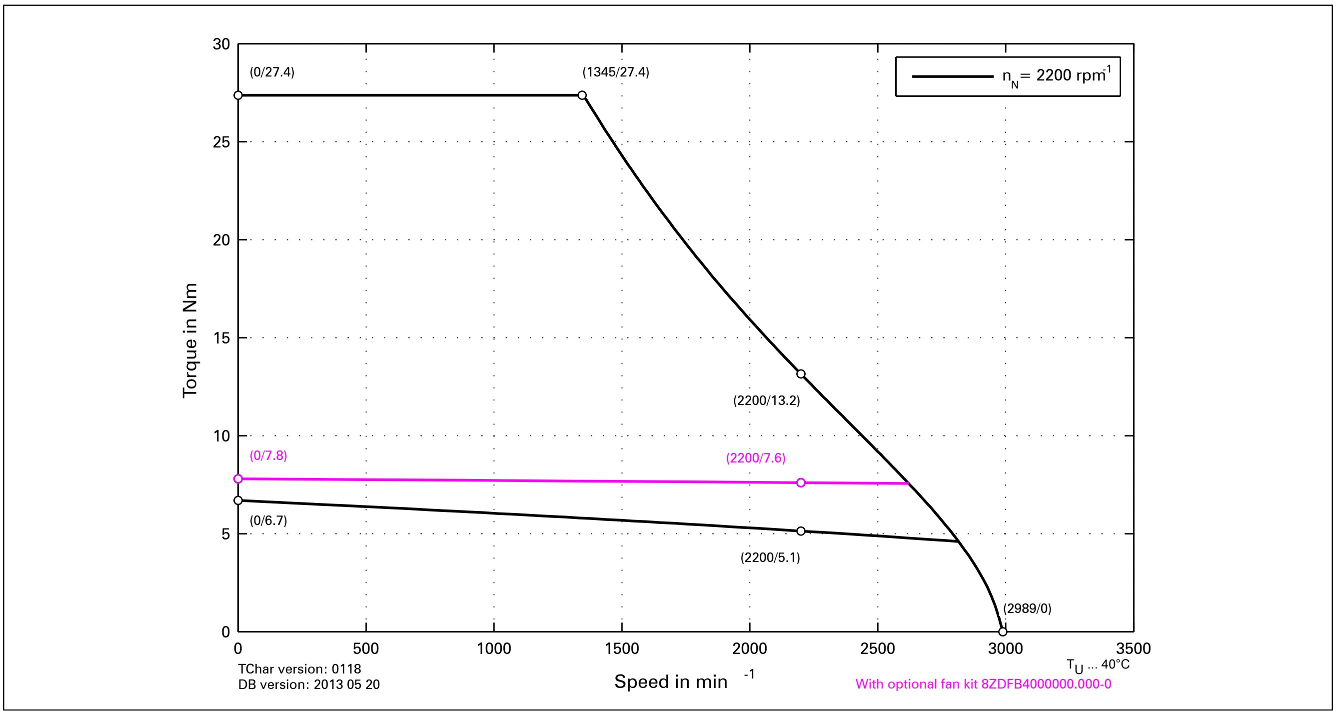


Figure 36: 8DI45e.ffggghi00-1 - Speed-torque characteristic curve

8DI46e.ffggghi00-1

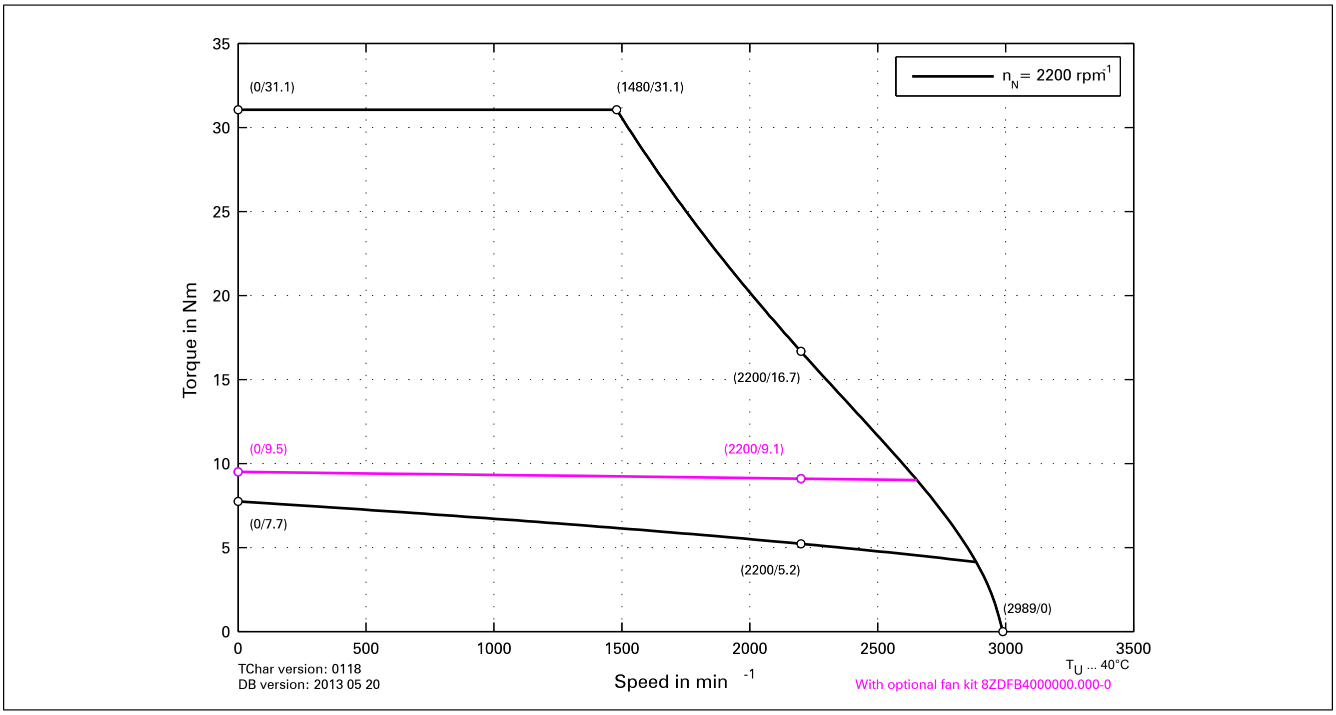


Figure 37: 8DI46e.ffggghi00-1 - Speed-torque characteristic curve

3.3.1.5.3 Speed-torque characteristic curve with 750 VDC DC bus voltage

8DI44e.ffggghi00-1

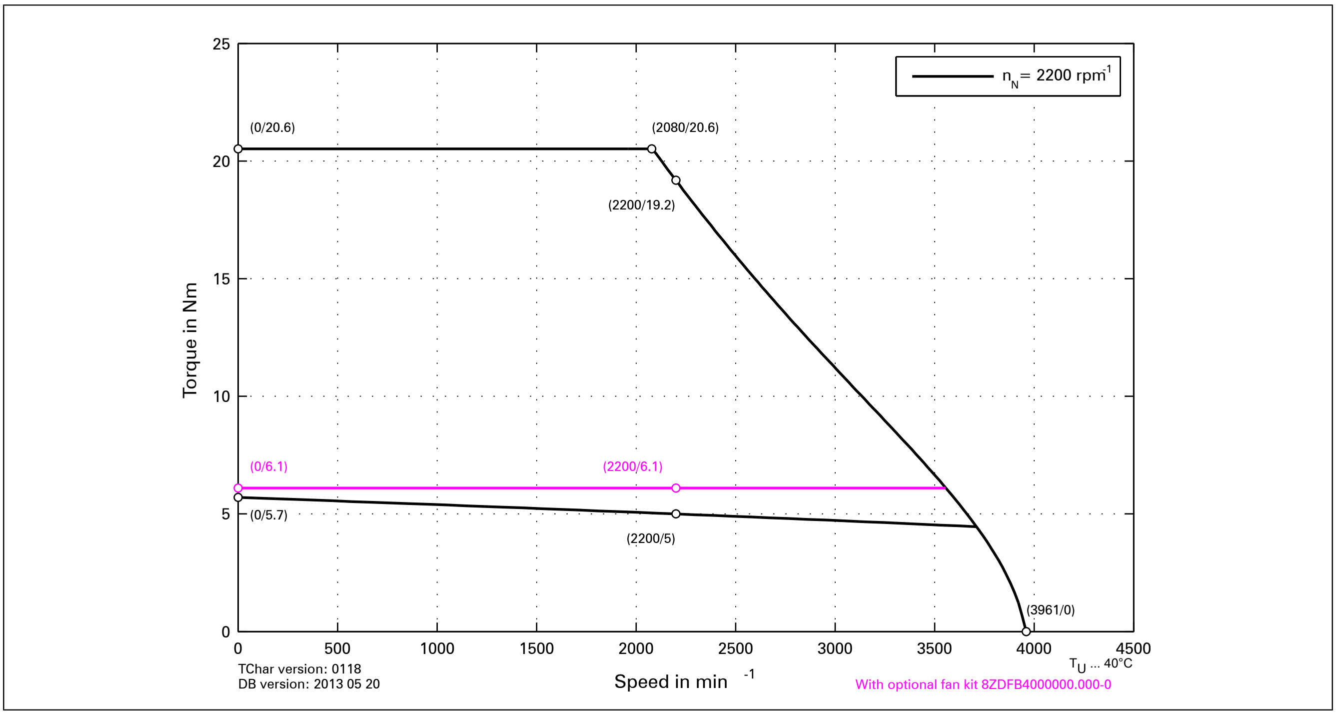


Figure 38: 8DI44e.ffggghi00-1 - Speed-torque characteristic curve

8DI45e.ffggghi00-1

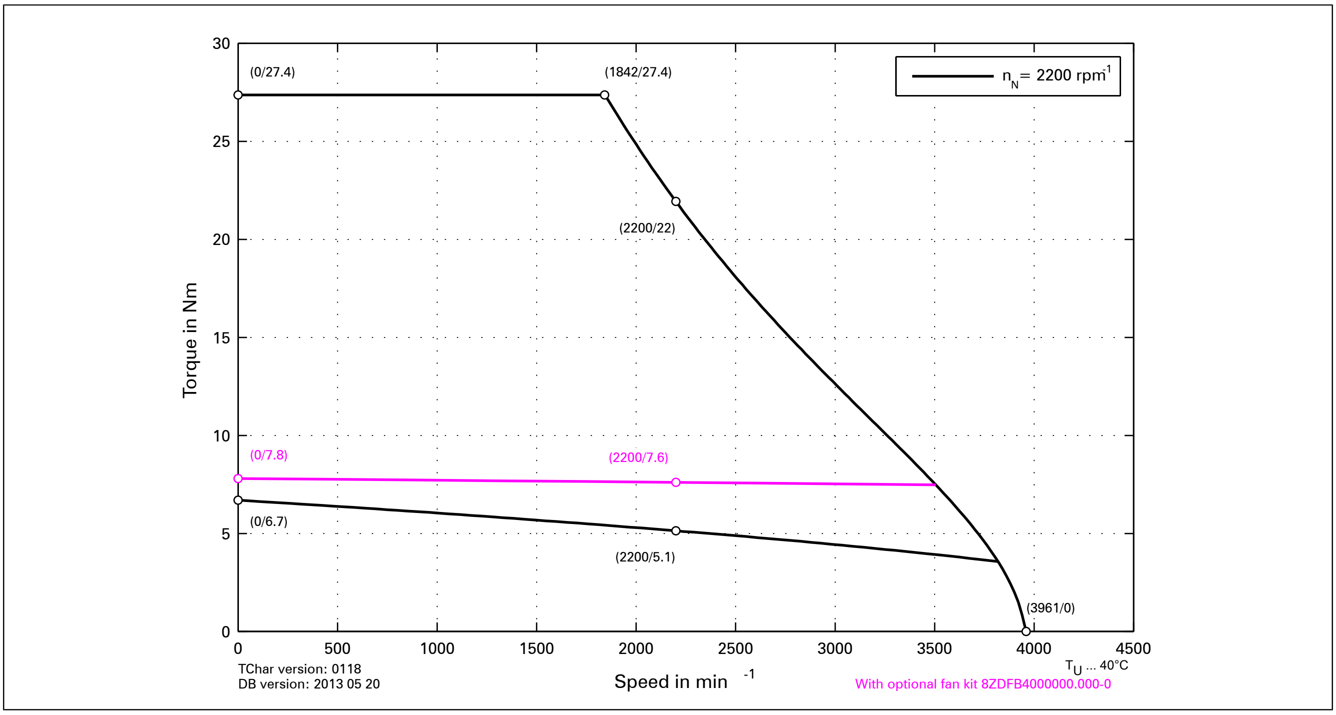


Figure 39: 8DI45e.ffggghi00-1 - Speed-torque characteristic curve

8DI46e.ffggghi00-1

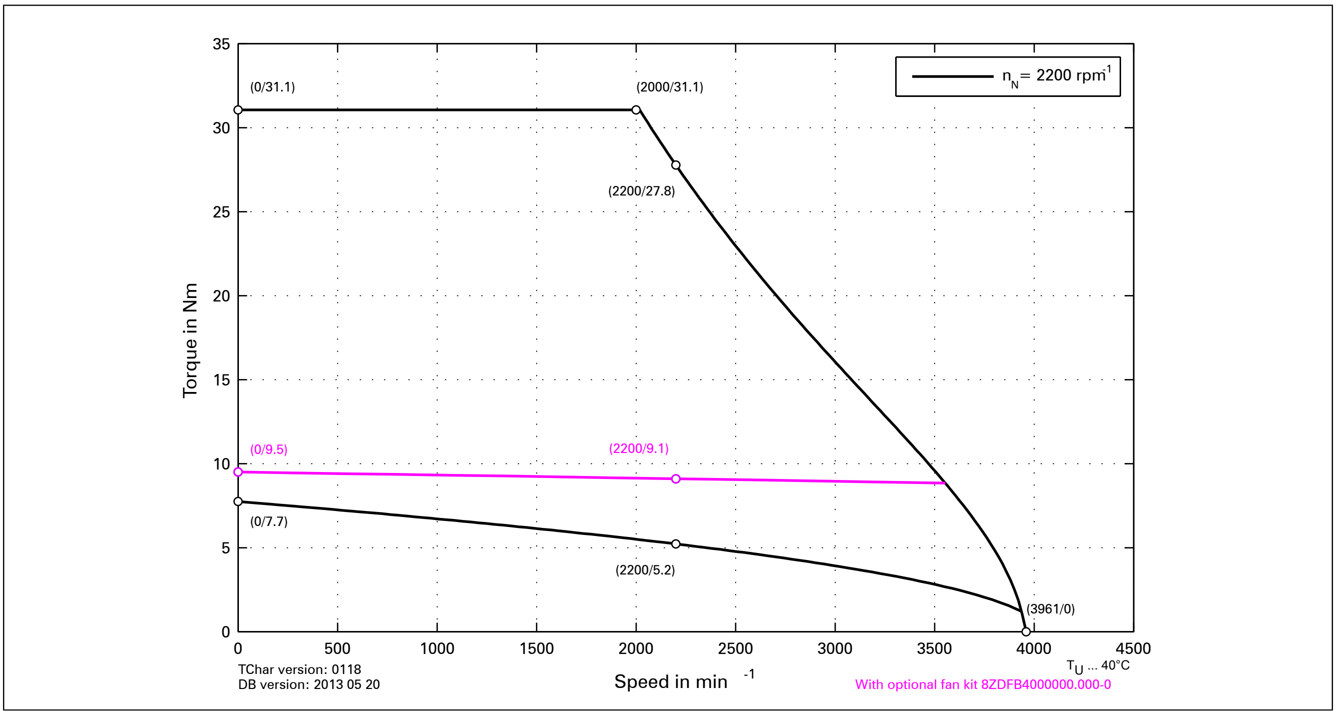
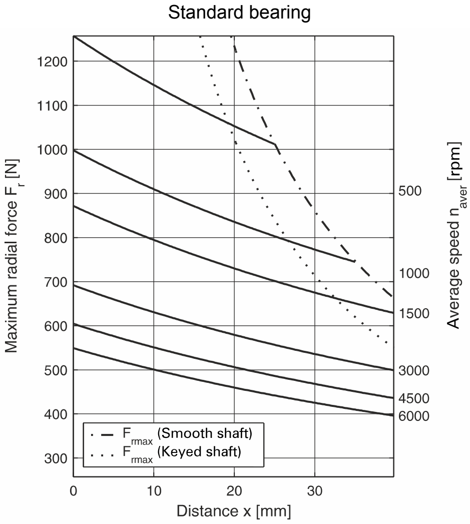


Figure 40: 8DI46e.ffggghi00-1 - Speed-torque characteristic curve

3.3.1.5.4 Maximum shaft load

The values in the diagram below are based on a mechanical service life of the bearings of 20,000 operating hours.



Maximum allowed axial force: F_{amax} = 110 N

3.3.1.6 Size 5

3.3.1.6.1 Technical data

Model number	8DI54S.ff022hi00-1	8DI55S.ff022hi00-1	8DI56S.ff022hi00-1
Motor			
Nominal speed n_N [rpm]	2200		
Number of pole pairs	4		
Nominal torque M_n [Nm]	7.1	8.4	10
Nominal power P_N [W]	1636	1935	2304
Nominal current I_N [A]	3.2	3.79	4.51
Stall torque M_0 [Nm]	8	10	12
Stall current I_0 [A]	3.61	4.51	5.42
Maximum torque M_{max} [Nm]	21.6	36.5	46.6
Maximum current I_{max} [A]	14.9	21	
Maximum speed n_{max} [rpm]	9000		
Torque constant K_T [Nm/A]	2.22		
Voltage constant K_E [V/1000 rpm]	134.04		
Stator resistance R_{2ph} [Ω]	3.44	2.265	1.51
Stator inductance L_{2ph} [mH]	34.5	24.29	17.6
Electrical time constant t_{el} [ms]	10	10.724	In preparation
Thermal time constant t_{therm} [min]	37	40	48
Moment of inertia J [kgcm²]	6.04	8.19	10
Mass without brake m [kg]	11.46	13.29	16.4

Table 93: 8DI54S.ff022hi00-1, 8DI55S.ff022hi00-1, 8DI56S.ff022hi00-1 - Technical data

3.3.1.6.2 Speed-torque characteristic curve with 560 VDC DC bus voltage

8DI54e.ffggghi00-1

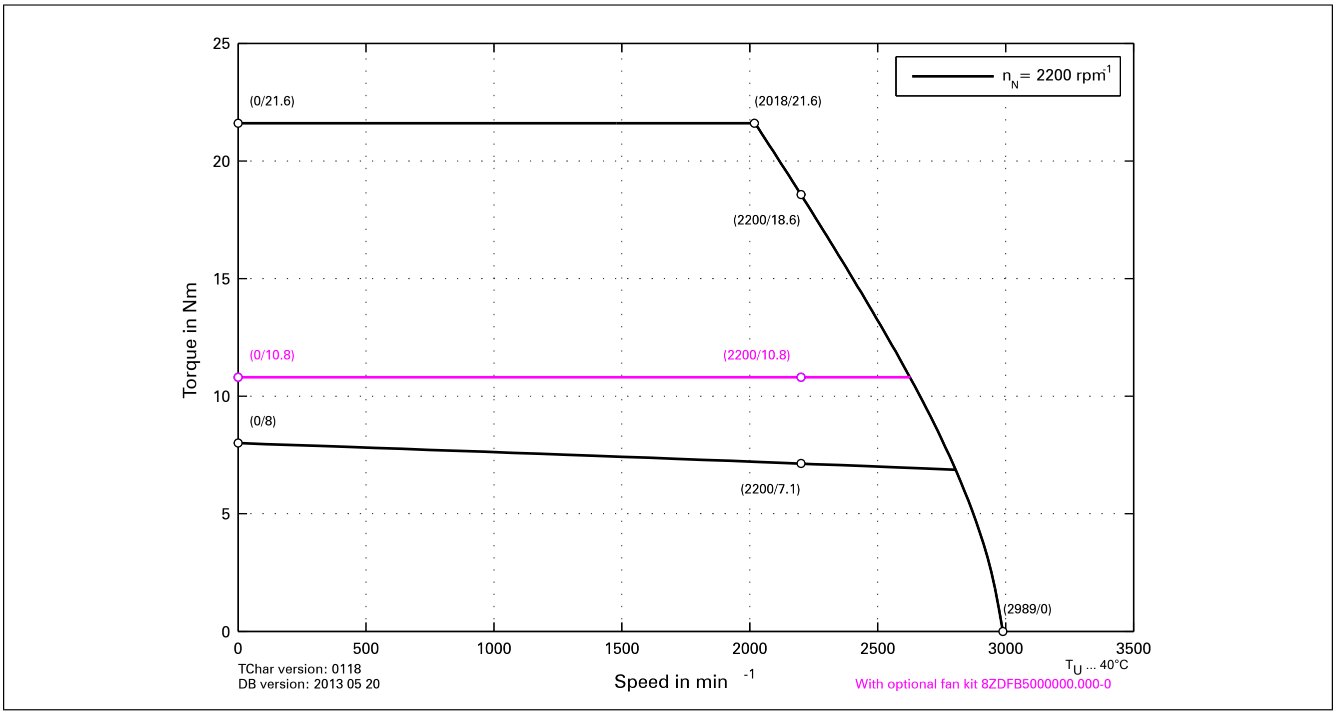


Figure 41: 8DI54e.ffggghi00-1 - Speed-torque characteristic curve

8DI55e.ffggghi00-1

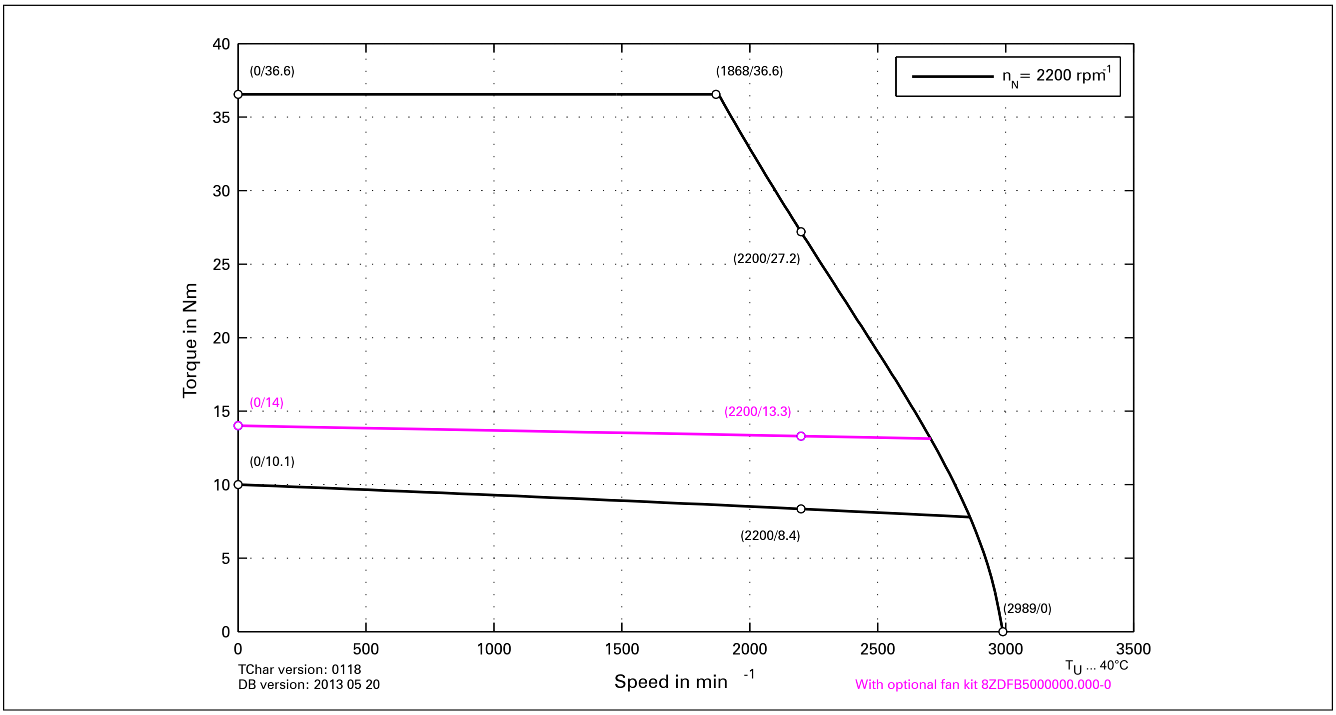


Figure 42: 8DI55e.ffggghi00-1 - Speed-torque characteristic curve

8DI56e.ffggghi00-1

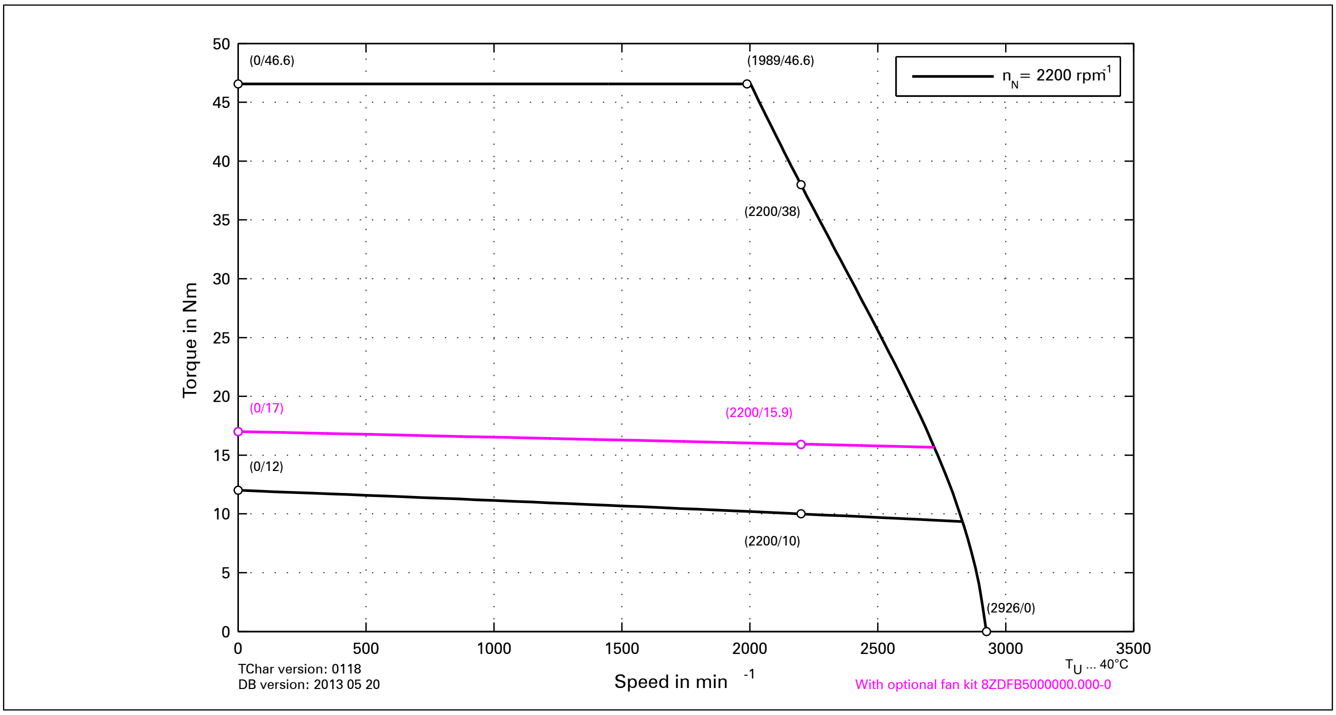


Figure 43: 8DI56e.ffggghi00-1 - Speed-torque characteristic curve

3.3.1.6.3 Speed-torque characteristic curve with 750 VDC DC bus voltage

8DI54e.ffggghi00-1

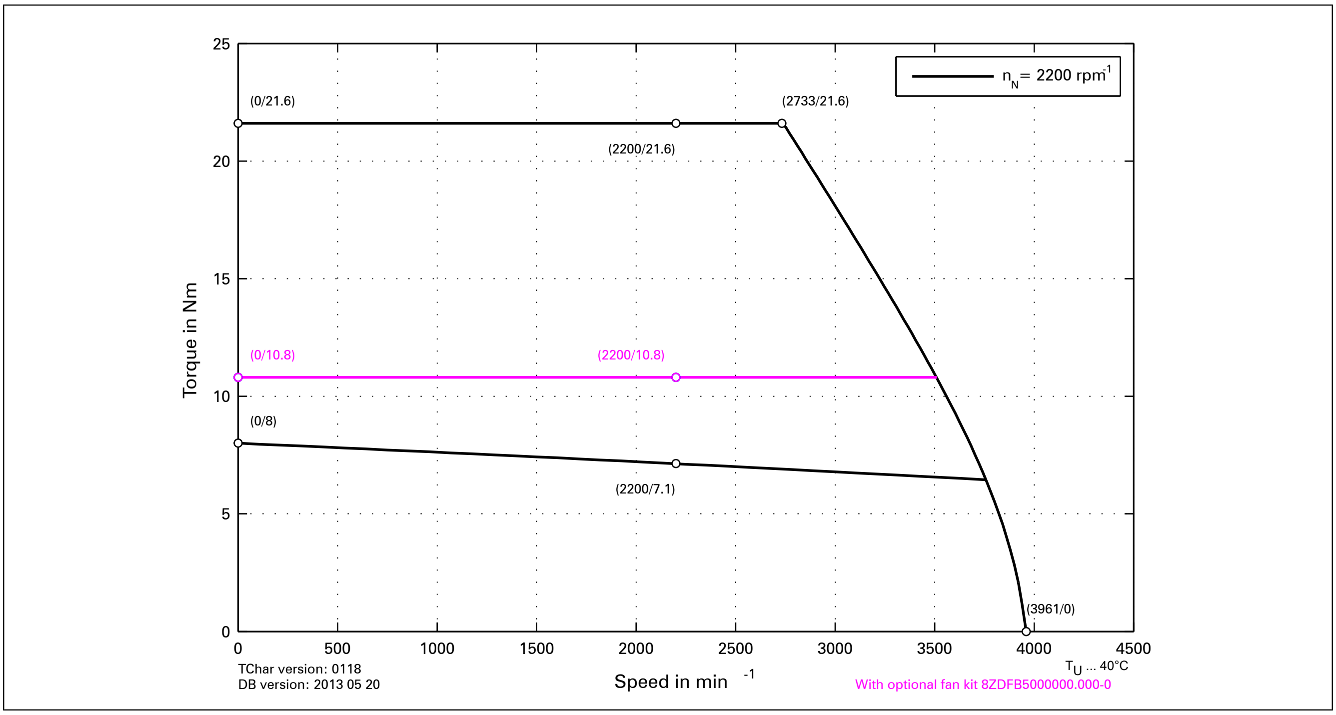


Figure 44: 8DI54e.ffggghi00-1 - Speed-torque characteristic curve

8DI55e.ffggghi00-1

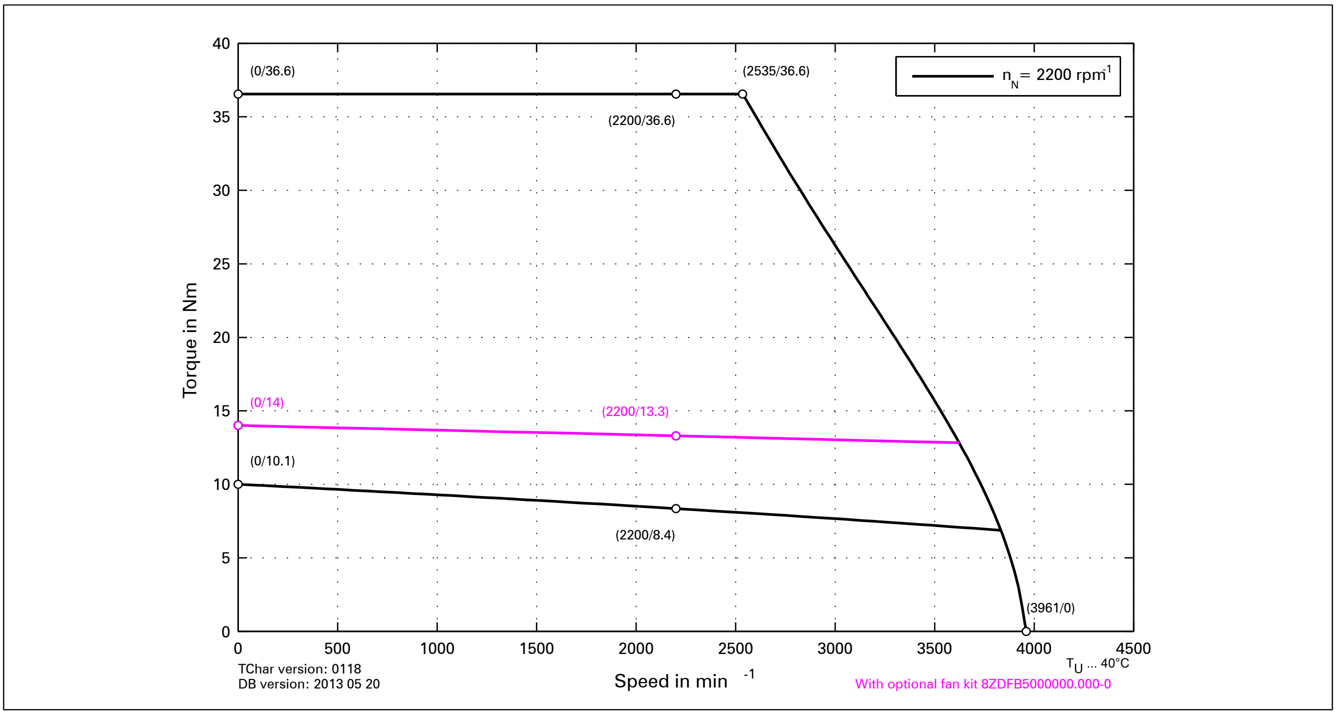


Figure 45: 8DI55e.ffggghi00-1 - Speed-torque characteristic curve

8DI56e.ffggghi00-1

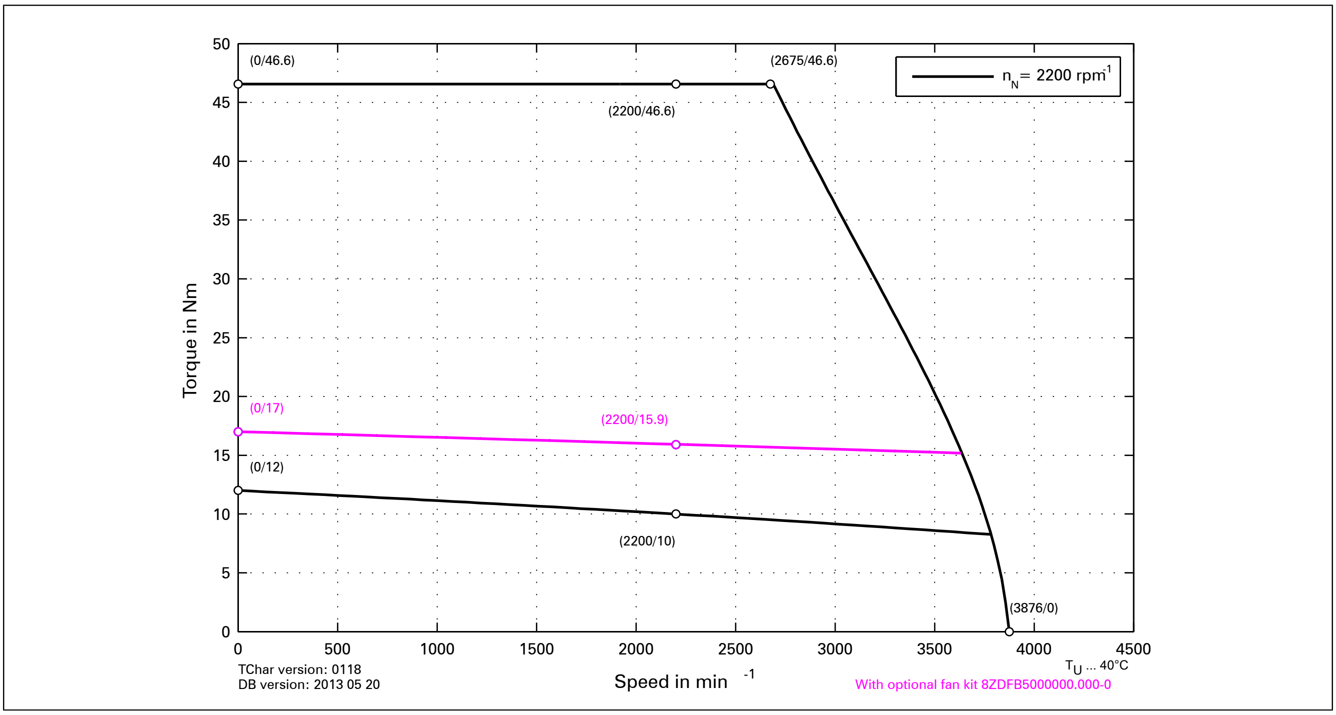
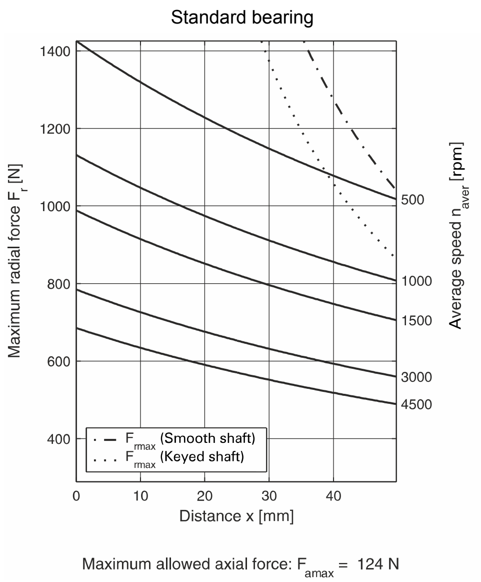


Figure 46: 8DI56e.ffggghi00-1 - Speed-torque characteristic curve

3.3.1.6.4 Maximum shaft load

The values in the diagram below are based on a mechanical service life of the bearings of 20,000 operating hours.



3.3.1.7 Pinouts

Danger!

Before performing service work, disconnect the power supply and wait 5 minutes to ensure that the DC bus of the drive system has discharged. Observe regulations!

Warning!

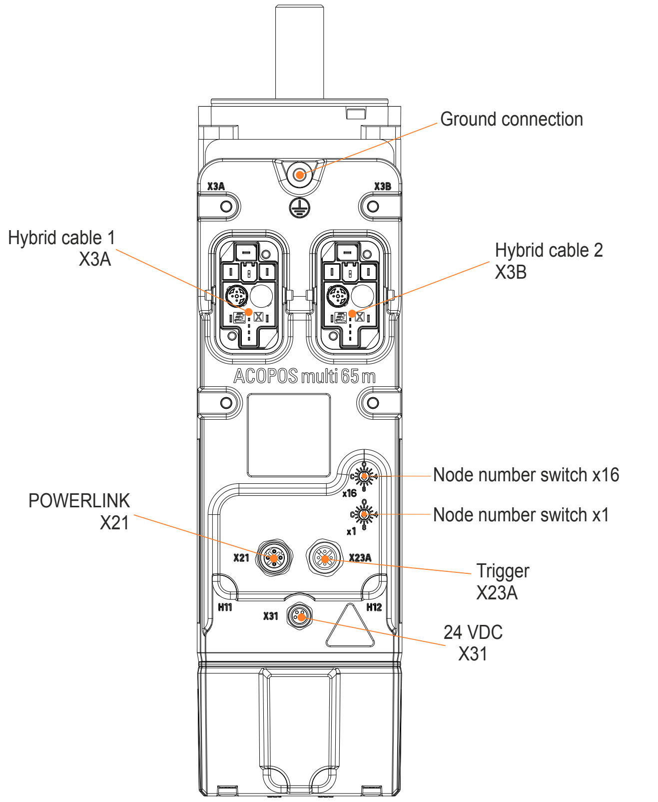
Drive systems can carry high levels of electrical voltage.
Never connect or disconnect the connector when voltage is present!

Information:

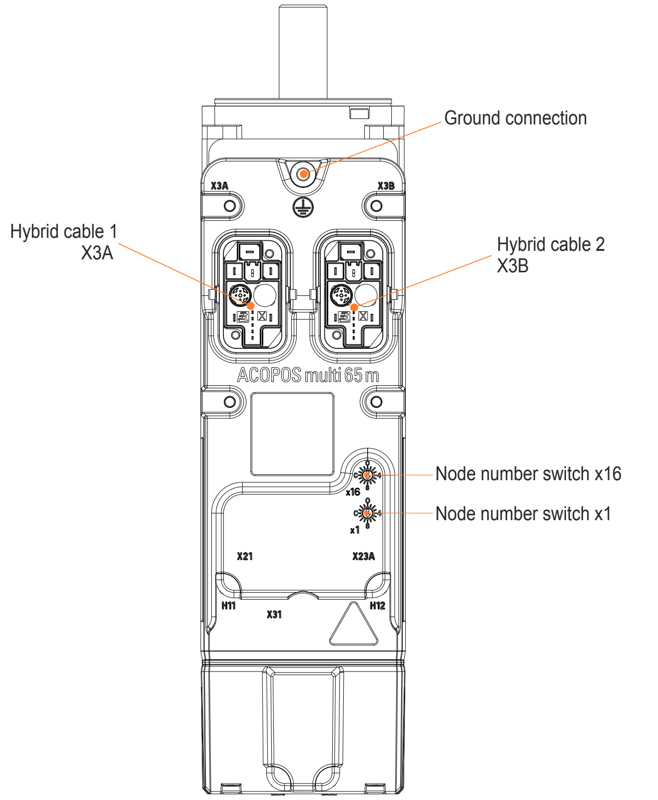
To satisfy UL/CSA requirements, components of B&R drive systems are only permitted to be wired with copper wires with a permitted wire temperature of at least 75°C.

3.3.1.7.1 Overview

8DIcde.ffggg7i00-1



8DIcde.ffggg0i00-1



3.3.1.7.1.1 X21 (POWERLINK)

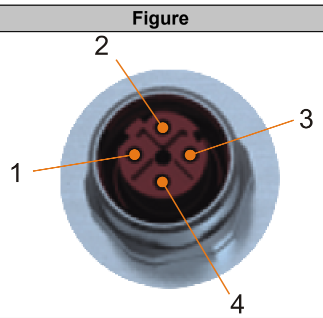
Figure	Pin	Description	Function
	1	TXD	Transmit data
	2	RXD	Receive data
	3	TXD\	Transmit data inverted
	4	RXD\	Receive data inverted

Table 94: Connector X21 - Pinout

3.3.1.7.1.2 X23A (trigger)

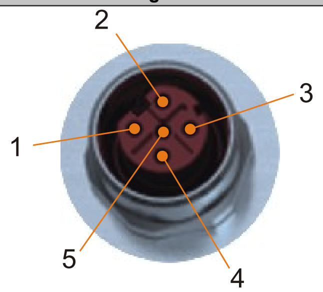
Figure	Pin	Description	Function
	1	+24 V	Sensor/actuator power supply 24 VDC 1)
	2	Trigger1	Trigger input 1
	3	GND	GND
	4	Trigger2	Trigger input 2
	5	---	---

Table 95: Connector X23A - Pinout

1) Sensor/Actuator power supply is not permitted to be external.

3.3.1.7.1.3 X31 (24 VDC routing)

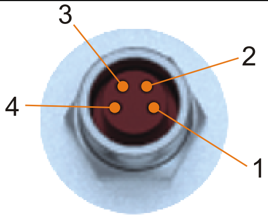
Figure	Pin	Description	Function
	1	24 VDC I/O	24 VDC I/O power supply
	2	24 VDC I/O	24 VDC I/O power supply
	3	GND	24 VDC I/O power supply 0 V
	4	GND	24 VDC I/O power supply 0 V

Table 96: Connector X31 - Pinout

3.3.1.7.1.4 Ground connection (PE)

The protective ground conductor is connected to the M5 threaded bolt provided using a cable lug.

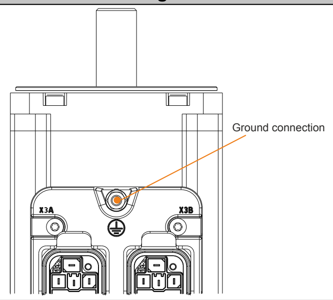
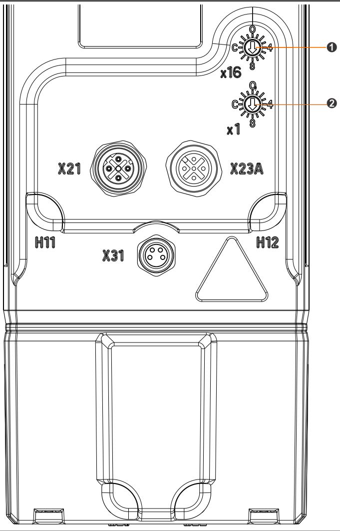
Figure	Pin	Name	Function
	---	PE	Protective ground conductor
Terminal cross sections	**[mm²]**		**AWG**
Cable lug for M5 threaded bolt	0.25 - 16		23 - 5

Table 97: Ground connection (PE)

3.3.1.8 POWERLINK node number setting

The POWERLINK station number can be set using the two coded hexadecimal rotary switches located on top of the module:

<table>
<tr><th>Figure</th><th>Coded rotary switches</th><th>POWERLINK node number</th></tr>
<tr><td rowspan="3">
</td><td>1</td><td>16s position (high)</td></tr>
<tr><td>2</td><td>1s position (low)</td></tr>
<tr><td colspan="2">Changed POWERLINK node numbers will not take effect until the drive system is restarted.

Information:

In principle, node numbers between $01 and $FD are permitted. However, node numbers between $F0 and $FD are intended for future system expansions. To ensure compatibility, these node numbers should be avoided.

Node numbers $00, $FE and $FF are reserved and may therefore not be set.</td></tr>
</table>

3.3.2 Accessories

3.3.2.1 Cables

3.3.2.1.1 Cable for 24 VDC routing

3.3.2.1.1.1 X67CA0P00.xxxx - Order data

Model number	Short description	Figure
	I/O supply cable	
X67CA0P00.0020	Power connection cable, 4-pin, straight, 2 m	
X67CA0P00.0050	Power connection cable, 4-pin, straight, 5 m	

Table 98: X67CA0P00.0020, X67CA0P00.0050 - Order data

3.3.2.1.1.2 X67CA0P00.xxxx - Technical data

Model number	X67CA0P00.0020	X67CA0P00.0050
Short description		
Accessories	Power connection cable, 4-pin, straight, 2 m	Power connection cable, 4-pin, straight, 5 m
General information		
Note	PVC- and silicone-free LABS- (PWIS-) and halogen-free	
Durability	Good chemical and oil resistance Flame-retardant Good UV and ozone resistance	
Cable cross section		
AWG	4x 22 AWG	
mm²	4x 0.34 mm²	
Cable construction		
Cable shield	Not shielded	
Outer jacket		
Material	Polyurethane (PUR)	
Color	Black	
Labeling	B&R X67CA0P00.0020 Rev. G0 ESCHA FC	B&R X67CA0P00.0050 Rev. G0 ESCHA FC
Lines		
Wire insulation	Polypropylene (PP) 9Y	
Wire colors	Brown, black, blue, white	
Type	Uncoated copper ETP1 Fine stranded wire (42x 0.1 mm / 42x 38 AWG), class 6	
Stranding	4-wire twisted pair	
Electrical properties		
Nominal current	Max. 4 A per EN / Contact at 40°C Max. 3 A per UL / Contact	
Operating voltage	Max. 60 V	
Degree of insulation	Category II in accordance with IEC 61076-2	
Conductor resistance	≤57 Ω/km	
Insulation resistance	≥100 MΩ	
Operating conditions		
Degree of protection per EN 60529		
Connector/Coupling	IP67, only when screwed in	
Ambient conditions		
Temperature		
Transport	-40 to 90°C	
Fixed installation	-30 to 90°C	
Flexible installation [1)]	-25 to 60°C	
Mechanical properties		
Dimensions		
Length	2 m	5 m
Diameter	4.7 mm ±0.2 mm	
Bend radius	≥10x outer diameter	
Drag chain data		
Acceleration	Max. 5 m/s²	
Flex cycles	5 million	
Velocity	Max. 3.3 m/s	

Table 99: X67CA0P00.0020, X67CA0P00.0050 - Technical data

1) In cable drag chain operation.

3.3.2.1.1.3 X67CA0P10.xxxx - Order data

Model number	Short description	Figure
	I/O supply cable	
X67CA0P10.0020	Power connection cable, 4-pin, angled, 2 m	
X67CA0P10.0050	Power connection cable, 4-pin, angled, 5 m	

Table 100: X67CA0P10.0020, X67CA0P10.0050 - Order data

3.3.2.1.1.4 X67CA0P10.xxxx - Technical data

Model number	X67CA0P10.0020	X67CA0P10.0050
Short description		
Accessories	Power connection cable, 4-pin, angled, 2 m	Power connection cable, 4-pin, angled, 5 m
General information		
Note	PVC- and silicone-free LABS- (PWIS-) and halogen-free	
Durability	Good chemical and oil resistance Flame-retardant Good UV and ozone resistance	
Cable cross section		
AWG	4x 22 AWG	
mm²	4x 0.34 mm²	
Cable construction		
Cable shield	Not shielded	
Outer jacket		
Material	Polyurethane (PUR)	
Color	Black	
Labeling	B&R X67CA0P10.0020 Rev. G0 ESCHA FC	B&R X67CA0P10.0050 Rev. G0 ESCHA FC
Lines		
Wire insulation	Polypropylene (PP) 9Y	
Wire colors	Brown, black, blue, white	
Type	Uncoated copper ETP1 Fine stranded wire (42x 0.1 mm / 42x 38 AWG), class 6	
Stranding	4-wire twisted pair	
Electrical properties		
Nominal current	Max. 4 A per EN / Contact at 40°C Max. 3 A per UL / Contact	
Operating voltage	Max. 60 V	
Degree of insulation	Category II in accordance with IEC 61076-2	
Conductor resistance	≤57 Ω/km	
Insulation resistance	≥100 MΩ	
Operating conditions		
Degree of protection per EN 60529		
Connector/Coupling	IP67, only when screwed in	
Ambient conditions		
Temperature		
Transport	-40 to 90°C	
Fixed installation	-30 to 90°C	
Flexible installation [1)]	-25 to 60°C	
Mechanical properties		
Dimensions		
Length	2 m	5 m
Diameter	4.7 mm ±0.2 mm	
Bend radius	≥10x outer diameter	
Drag chain data		
Acceleration	Max. 5 m/s²	
Flex cycles	5 million	
Velocity	Max. 3.3 m/s	

Table 101: X67CA0P10.0020, X67CA0P10.0050 - Technical data

1) In cable drag chain operation.

3.3.2.1.1.5 X67CA0P40.xxxx - Order data

Model number	Short description	Figure
	I/O supply cable	
X67CA0P40.0020	Power open-ended cable, 4-pin, straight, 2 m	
X67CA0P40.0050	Power open-ended cable, 4-pin, straight, 5 m	

Table 102: X67CA0P40.0020, X67CA0P40.0050 - Order data

3.3.2.1.1.6 X67CA0P40.xxxx - Technical data

Model number	X67CA0P40.0020	X67CA0P40.0050
Short description		
Accessories	Power open-ended cable, 4-pin, straight, 2 m	Power open-ended cable, 4-pin, straight, 5 m
General information		
Note	PVC- and silicone-free LABS- (PWIS-) and halogen-free	
Durability	Good chemical and oil resistance Flame-retardant Good UV and ozone resistance	
Cable cross section		
AWG	4x 22 AWG	
mm²	4x 0.34 mm²	
Cable construction		
Cable shield	Not shielded	
Outer jacket		
Material	Polyurethane (PUR)	
Color	Black	
Labeling	B&R X67CA0P40.0020 Rev. G0 ESCHA FC	B&R X67CA0P40.0050 Rev. G0 ESCHA FC
Lines		
Wire insulation	Polypropylene (PP) 9Y	
Wire colors	Brown, black, blue, white	
Type	Uncoated copper ETP1 Fine stranded wire (42x 0.1 mm / 42x 38 AWG), class 6	
Stranding	4-wire twisted pair	
Electrical properties		
Nominal current	Max. 4 A per EN / Contact at 40°C Max. 3 A per UL / Contact	
Operating voltage	Max. 60 V	
Degree of insulation	Category II in accordance with IEC 61076-2	
Conductor resistance	≤57 Ω/km	
Insulation resistance	≥100 MΩ	
Operating conditions		
Degree of protection per EN 60529		
Connector/Coupling	IP67, only when screwed in	
Ambient conditions		
Temperature		
Transport	-40 to 90°C	
Fixed installation	-30 to 90°C	
Flexible installation [1]	-25 to 60°C	
Mechanical properties		
Dimensions		
Length	2 m	5 m
Diameter	4.7 mm ±0.2 mm	
Bend radius	≥10x outer diameter	
Drag chain data		
Acceleration	Max. 5 m/s²	
Flex cycles	5 million	
Velocity	Max. 3.3 m/s	

Table 103: X67CA0P40.0020, X67CA0P40.0050 - Technical data

1) In cable drag chain operation.

3.3.2.1.2 POWERLINK cables

3.3.2.1.2.1 X67CA0E41.xxxx - Order data

Model number	Short description	Figure
	POWERLINK/Ethernet-Cable	
X67CA0E41.0010	POWERLINK/Ethernet connection cable, RJ45 to M12, 1 m	
X67CA0E41.0050	POWERLINK/Ethernet connection cable, RJ45 to M12, 5 m	

Table 104: X67CA0E41.0010, X67CA0E41.0050 - Order data

3.3.2.1.2.2 X67CA0E41.xxxx - Technical data

Model number	X67CA0E41.0010	X67CA0E41.0050
Short description		
Accessories	POWERLINK/Ethernet connection cable, RJ45 to M12, 4-pin, straight, 1 m	POWERLINK/Ethernet connection cable, RJ45 to M12, 4-pin, straight, 5 m
General information		
Note	Halogen-free	
Durability	Flame-retardant per IEC 60332-1-2	
Type	Connection cables	
Cable cross section		
AWG	4x 22 AWG	
mm²	4x 0.34 mm²	
Cable construction		
Cable shield	Overlapping aluminum-clad foil, tinned copper braiding, 85% coverage	
Outer jacket		
Material	Polyurethane (PUR) GN	
Color	Green	
Labeling	B&R X67CA0E41.0010	B&R X67CA0E41.0050
Lines		
Wire insulation	Polyethylene (PE)	
Wire colors	White, yellow, blue, orange	
Type	Tinned copper stranded wire Fine stranded wire (7x 0.25 mm / 7x 30 AWG)	
Stranding	4-wire twisted pair	
Electrical properties		
Conductor resistance	≤120 Ω/km at 20°C	
Transfer properties	Category 5 / Class D up to 100 MHz in accordance with ISO/IEC 11801 (EN 50173-1), ISO/IEC 24702 (EN 50173-3)	
Transfer rate	10/100 Mbit/s	
Insulation resistance	≥500 MΩ/km at 20°C	
Operating conditions		
Degree of protection per EN 60529		
Cables	IP67	
Male M12 connector	IP67, only when screwed in	
RJ45 connector	IP20, only when properly connected	
Ambient conditions		
Temperature		
Transport	-40 to 70°C	
Fixed installation	-25 to 60°C	
Flexible installation	-20 to 60°C	
Mechanical properties		
Dimensions		
Length	1 m	5 m
Diameter	6.5 mm ±0.2 mm	
Bend radius		
After installation	≥7x outer diameter	
During installation	≥3x outer diameter	
Weight	0.064 kg/m	

Table 105: X67CA0E41.0010, X67CA0E41.0050 - Technical data

3.3.2.1.2.3 X67CA0E61.xxxx - Order data

Model number	Short description	Figure
	POWERLINK/Ethernet-Cable	
X67CA0E61.0020	POWERLINK/Ethernet connection cable, M12 to M12, 2 m	
X67CA0E61.0050	POWERLINK/Ethernet connection cable, M12 to M12, 5 m	

Table 106: X67CA0E61.0020, X67CA0E61.0050 - Order data

3.3.2.1.2.4 X67CA0E61.xxxx - Technical data

Model number	X67CA0E61.0020	X67CA0E61.0050
Short description		
Accessories	POWERLINK/Ethernet connection cable, M12, 4-pin, straight, 2 m	POWERLINK/Ethernet connection cable, M12, 4-pin, straight, 5 m
General information		
Note	Halogen-free	
Durability	Flame-retardant per IEC 60332-1-2	
Type	Connection cables	
Cable cross section		
AWG	4x 22 AWG	
mm²	4x 0.34 mm²	
Cable construction		
Cable shield	Overlapping aluminum-clad foil, tinned copper braiding, 85% coverage	
Outer jacket		
Material	Polyurethane (PUR)	
Color	Green	
Labeling	B&R X67CA0E61.0020	B&R X67CA0E61.0050
Lines		
Wire insulation	Polyethylene (PE)	
Wire colors	White, yellow, blue, orange	
Type	Tinned copper stranded wire Fine stranded wire (7x 0.25 mm / 7x 30 AWG)	
Stranding	4-wire twisted pair	
Electrical properties		
Conductor resistance	≤120 Ω/km at 20°C	
Transfer properties	Category 5 / Class D up to 100 MHz in accordance with ISO/IEC 11801 (EN 50173-1), ISO/IEC 24702 (EN 50173-3)	
Transfer rate	10/100 Mbit/s	
Insulation resistance	≥500 MΩ/km at 20°C	
Operating conditions		
Degree of protection per EN 60529		
Cables	IP67	
Male M12 connector	IP67, only when screwed in	
RJ45 connector	IP20, only when properly connected	
Ambient conditions		
Temperature		
Transport	-40 to 70°C	
Fixed installation	-25 to 60°C	
Flexible installation	-20 to 60°C	
Mechanical properties		
Dimensions		
Length	2 m	5 m
Diameter	6.5 mm ±0.2 mm	
Bend radius		
After installation	≥7x outer diameter	
During installation	≥3x outer diameter	
Weight	0.062 kg/m	

Table 107: X67CA0E61.0020, X67CA0E61.0050 - Technical data

3.3.2.1.3 Sensor cables

3.3.2.1.3.1 X67CA0A41.xxxx - Order data

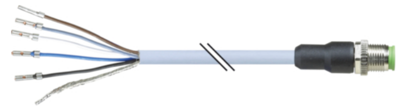
Model number	Short description	Figure
	Sensor cable	
X67CA0A41.0020	M12 sensor cable, 2 m	
X67CA0A41.0050	M12 sensor cable, 5 m	
X67CA0A41.0100	M12 sensor cable, 10 m	

Table 108: X67CA0A41.0020, X67CA0A41.0050, X67CA0A41.0100 - Order data

3.3.2.1.3.2 X67CA0A41.xxxx - Technical data

Model number	X67CA0A41.0020	X67CA0A41.0050	X67CA0A41.0100
Short description			
Accessories	M12 sensor cable, 5-pin, straight, 2 m	M12 sensor cable, 5-pin, straight, 5 m	M12 sensor cable, 5-pin, straight, 10 m
General information			
Note	PVC- and silicone-free PWIS- and halogen-free		PVC- and silicone-free LABS- (PWIS-) and halogen-free
Durability	Good chemical and oil resistance Flame-retardant Good UV and ozone resistance		
Cable cross section			
AWG	5x 22 AWG		
mm²	5x 0.34 mm²		
Cable construction			
Cable shield	Tinned copper braiding, coverage 84%, 0.25 mm² with filler		
Outer jacket			
Material	Polyurethane (PUR) UL		
Color	Gray		
Labeling	B&R X67CA0A41.0020 Rev. G0 ESCHA FC [1]	B&R X67CA0Axx.xxxx Rev. G0 ESCHA FC [1]	B&R X67CA0A41.0100 Rev. G0 ESCHA FC [1]
Lines			
Wire insulation	Polypropylene (PP) 9Y		
Wire colors	Brown, black, blue, white, gray		
Type	Uncoated copper ETP1 Fine stranded wire (42x 0.1 mm / 42x 38 AWG), class 5		
Stranding	5 wires stranded using filler		
Electrical properties			
Nominal current	Max. 4 A / contact at 40°C		
Operating voltage	Max. 60 V		
Degree of insulation	Category II in accordance with IEC 61076-2		
Conductor resistance	≤57 Ω/km		
Insulation resistance	≥100 MΩ		
Operating conditions			
Degree of protection per EN 60529			
Connector/Coupling	IP67, only when screwed in		
Ambient conditions			
Temperature			
Transport	-40 to 90°C		
Fixed installation	-30 to 90°C		
Flexible installation [2]	-25 to 60°C		
Mechanical properties			
Dimensions			
Length	2 m	5 m	10 m
Diameter	5.6 mm ±0.2 mm		
Bend radius	≥12x outer diameter		
Drag chain data			
Acceleration	Max. 5m/s²	Max. 5 m/s²	
Flex cycles	2 million		
Velocity	Max. 1.6 m/s		

Table 109: X67CA0A41.0020, X67CA0A41.0050, X67CA0A41.0100 - Technical data

1) xx.xxxx: Group number and cable length.
2) In cable drag chain operation

3.3.2.1.3.3 X67CA0A51.xxxx - Order data

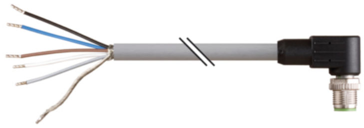
Model number	Short description	Figure
	Sensor cable	
X67CA0A51.0020	M12 sensor cable, angled, 2 m	
X67CA0A51.0050	M12 sensor cable, angled, 5 m	
X67CA0A51.0100	M12 sensor cable, angled, 10 m	

Table 110: X67CA0A51.0020, X67CA0A51.0050, X67CA0A51.0100 - Order data

3.3.2.1.3.4 X67CA0A51.xxxx - Technical data

Model number	X67CA0A51.0020	X67CA0A51.0050	X67CA0A51.0100
Short description			
Accessories	M12 sensor cable, 5-pin, angled, 2 m	M12 sensor cable, 5-pin, angled, 5 m	M12 sensor cable, 5-pin, angled, 10 m
General information			
Note	PVC- and silicone-free LABS- (PWIS-) and halogen-free		
Durability	Good chemical and oil resistance Flame-retardant Good UV and ozone resistance		
Cable cross section			
AWG	5x 22 AWG		
mm²	5x 0.34 mm²		
Cable construction			
Cable shield	Tinned copper braiding, coverage 84%, 0.25 mm² with filler		
Outer jacket			
Material	Polyurethane (PUR) UL		
Color	Gray		
Labeling	B&R X67CA0A51.0020 Rev. G0 ESCHA FC	B&R X67CA0A51.0050 Rev. G0 ESCHA FC	B&R X67CA0A51.0100 Rev. G0 ESCHA FC
Lines			
Wire insulation	Polypropylene (PP) 9Y		
Wire colors	Brown, black, blue, white, gray		
Type	Uncoated copper ETP1 Fine stranded wire (42x 0.1 mm / 42x 38 AWG), class 5		
Stranding	5 wires stranded using filler		
Electrical properties			
Nominal current	Max. 4 A / contact at 40°C		
Operating voltage	Max. 60 V		
Degree of insulation	Category II in accordance with IEC 61076-2		
Conductor resistance	≤57 Ω/km		
Insulation resistance	≥100 MΩ		
Operating conditions			
Degree of protection per EN 60529			
Connector/Coupling	IP67, only when screwed in		
Ambient conditions			
Temperature			
Transport	-40 to 90°C		
Fixed installation	-30 to 90°C		
Flexible installation 1)	-25 to 60°C		
Mechanical properties			
Dimensions			
Length	2 m	5 m	10 m
Diameter	5.6 mm ±0.2 mm		
Bend radius	≥12x outer diameter		
Drag chain data			
Acceleration	Max. 5 m/s²		
Flex cycles	2 million		
Velocity	Max. 1.6 m/s		

Table 111: X67CA0A51.0020, X67CA0A51.0050, X67CA0A51.0100 - Technical data

1) In cable drag chain operation.

3.3.2.2 Fan kits

8DI ACOPOSmotor modules can be optionally equipped with a fan kit depending on size. The fan kit considerably improves the nominal values of 8DI ACOPOSmotor modules (see speed-torque characteristic curve for the respective 8DI ACOPOSmotor module).

Information:

ACOPOSmotor 8DI modules automatically take into account the improvement of rated values with fan kit 8ZDFB via the evaluation of the module-internal temperature sensor. The motor parameters therefore do not need to be adjusted in Automation Studio.

A separate data set is available in SERVOsoft for ACOPOSmotor 8DI modules with and without fan kit 8ZDFB.

3.3.2.2.1 8ZDFB4000000.000-0

3.3.2.2.1.1 Order data

Model number	Short description	Figure
	Fan kits	
8ZDFB4000000.000-0	ACOPOSmotor fan kit for 8DI4xx modules	

Table 112: 8ZDFB4000000.000-0 - Order data

3.3.2.2.1.2 Technical data

Model number	8ZDFB4000000.000-0
General information	
Short description	ACOPOSmotor fan kit for 8DI4xx modules
24 VDC power supply	
Input voltage	24 VDC +10% / -50%
Max. power consumption	5.5 W
Variant	M8 4-pin male connector, 90° angled
Operating conditions	
Installation elevation above sea level	
Nominal	0 to 500 m
Maximum	4000 m
Degree of protection per EN 60529	IP24
Ambient conditions	
Temperature	
Operation	
Nominal	5 to 40°C
Maximum	55°C
Storage	-20 to 55°C
Transport	-20 to 70°C
Relative humidity	
Operation	15 to 90%, non-condensing
Storage	15 to 90%, non-condensing
Transport	In preparation
Mechanical properties	
Volumetric flow rate	2.486 m³/min
Operating noise	47 dB(A)
Service life	
At 40°C	80,000 h
Dimensions	
Width	125 mm
Height	131 mm
Depth	143.5 mm
Weight	0.43 kg

Table 113: 8ZDFB4000000.000-0 - Technical data

3.3.2.2.1.3 Dimension diagram

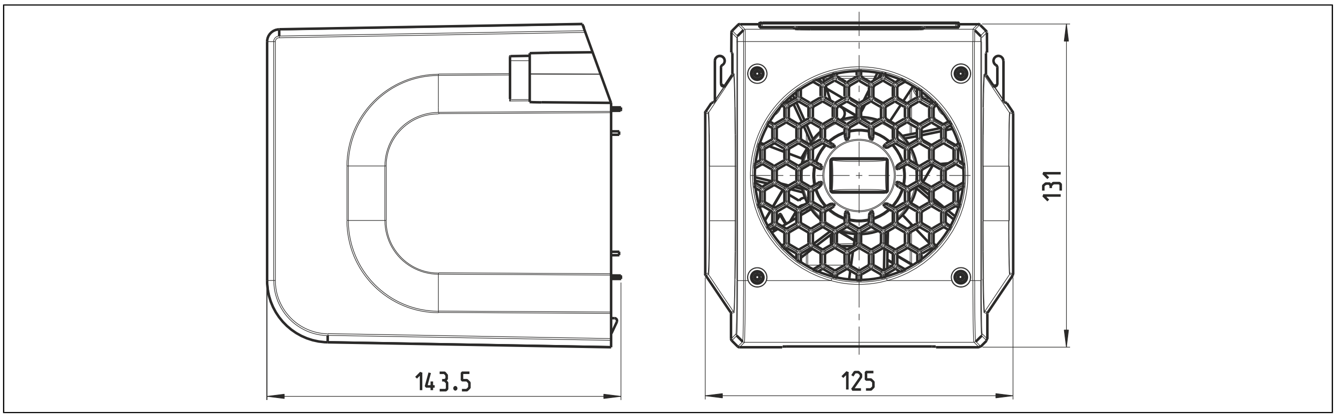


Figure 47: 8ZDFB4000000.000-0 - Dimensions

3.3.2.2.2 8ZDFB5000000.000-0

3.3.2.2.2.1 Order data

Model number	Short description	Figure
	Fan kits	
8ZDFB5000000.000-0	ACOPOSmotor fan kit for 8DI5xx modules	

Table 114: 8ZDFB5000000.000-0 - Order data

3.3.2.2.2.2 Technical data

Model number	8ZDFB5000000.000-0
General information	
Short description	ACOPOSmotor fan kit for 8DI5xx modules
24 VDC power supply	
Input voltage	24 VDC +10% / -50%
Max. power consumption	7.4 W
Variant	M8 4-pin male connector, 90° angled
Operating conditions	
Installation elevation above sea level	
Nominal	0 to 500 m
Maximum	4000 m
Degree of protection per EN 60529	IP24
Ambient conditions	
Temperature	
Operation	
Nominal	5 to 40°C
Maximum	55°C
Storage	-20 to 55°C
Transport	-20 to 75°C
Relative humidity	
Operation	15 to 90%, non-condensing
Storage	15 to 90%, non-condensing
Transport	In preparation
Mechanical properties	
Volumetric flow rate	3.256 m^3/min
Operating noise	47 dB(A)
Service life	
At 40°C	75,000 h
Dimensions	
Width	167 mm
Height	173.1 mm
Depth	143 mm
Weight	0.57 kg

Table 115: 8ZDFB5000000.000-0 - Technical data

3.3.2.2.2.3 Dimension diagram

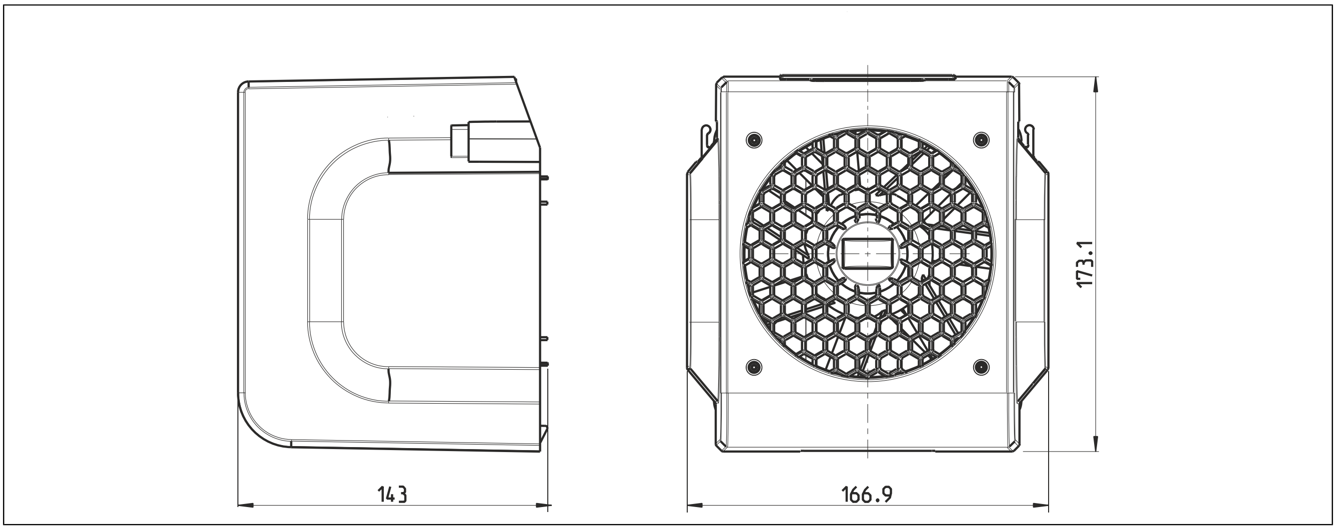


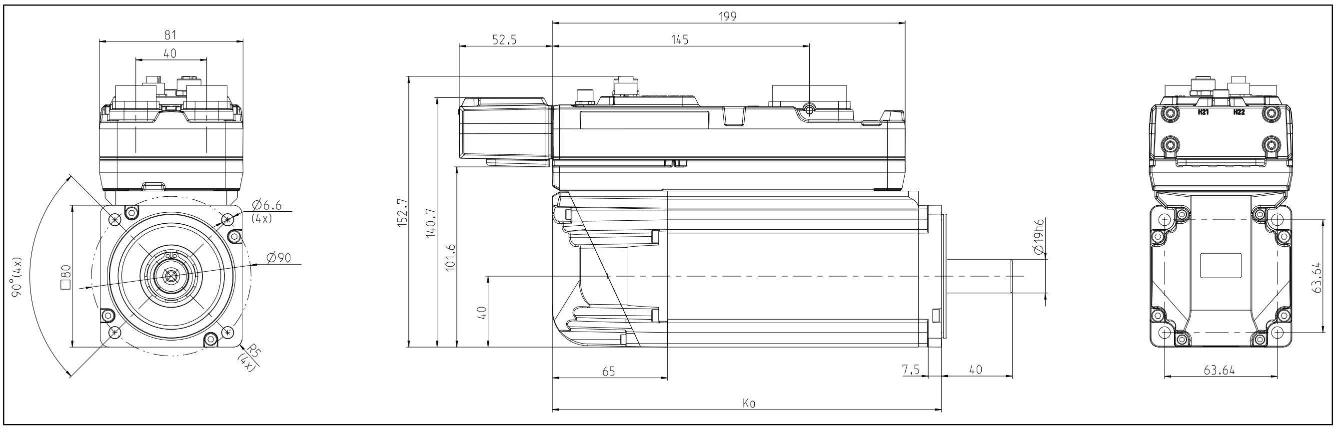
Figure 48: 8ZDFB5000000.000-0 - Dimensions

3.3.3 Installation

3.3.3.1 Dimension diagrams and installation dimensions

3.3.3.1.1 Size 3

8DI3dS.ffggghi00-1



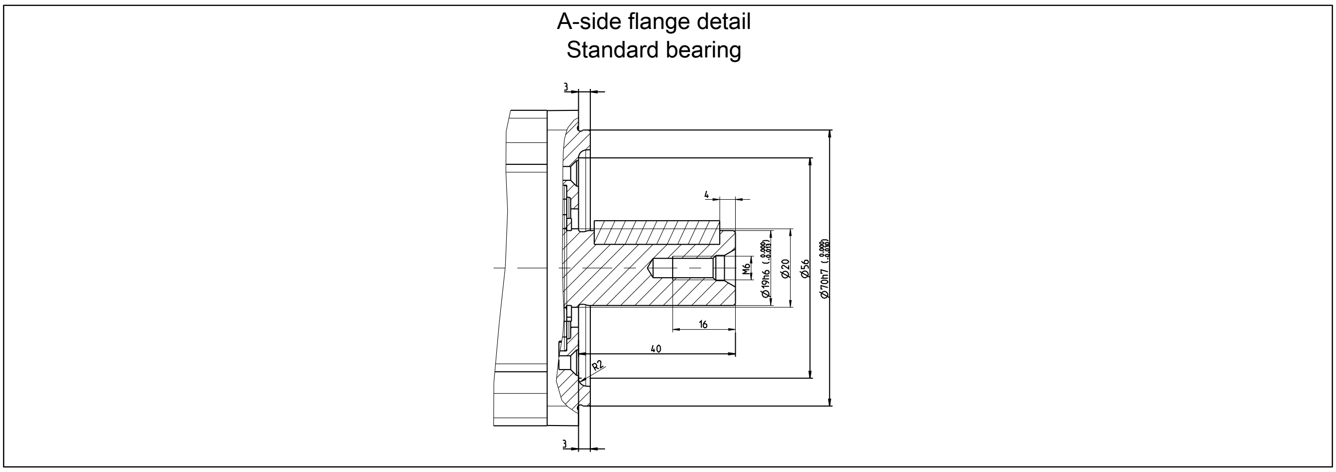
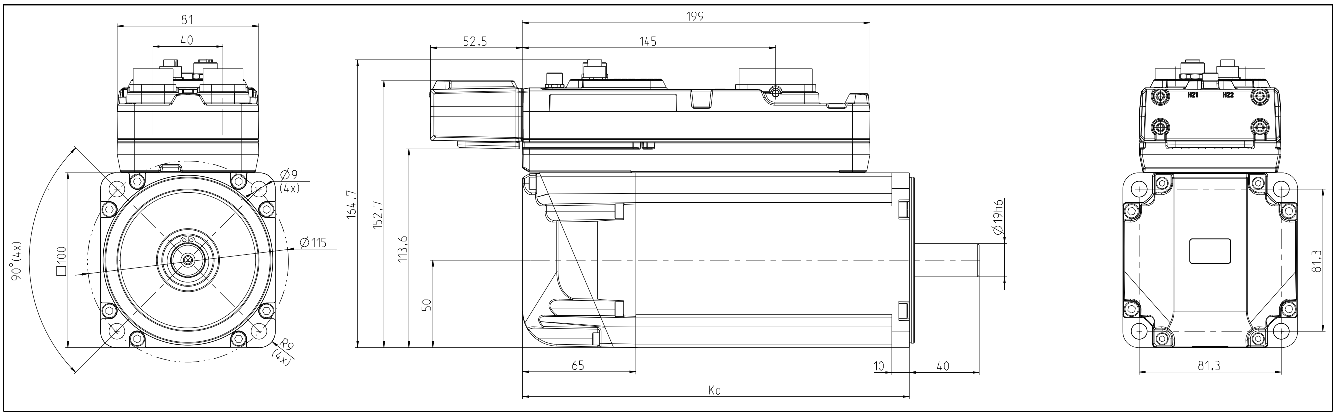


Figure 49: Flange details

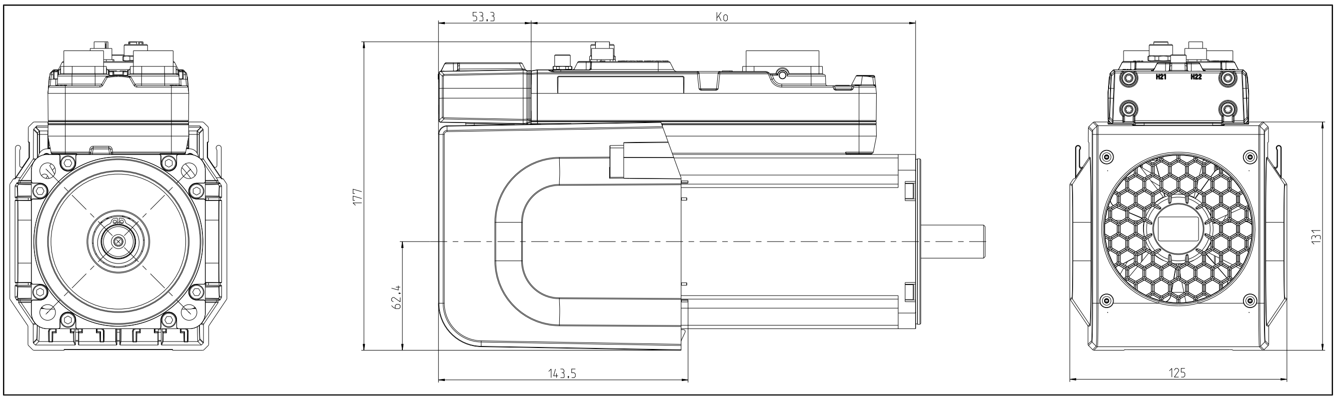
		Extension of K_0 depending on motor option [mm]	
ACOPOSmotor module	**Length K_0 [mm]**	**Holding brake**	**Oil seal**
8DI33x.xxxxxxxxx-x	203.5	27	5
8DI34x.xxxxxxxxx-x	214.5	31	5

3.3.3.1.2 Size 4

8DI4dS.ffggghi00-1



With optional fan kit 8ZDFB4000000.000-0



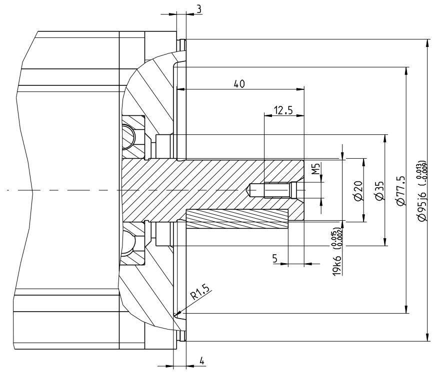
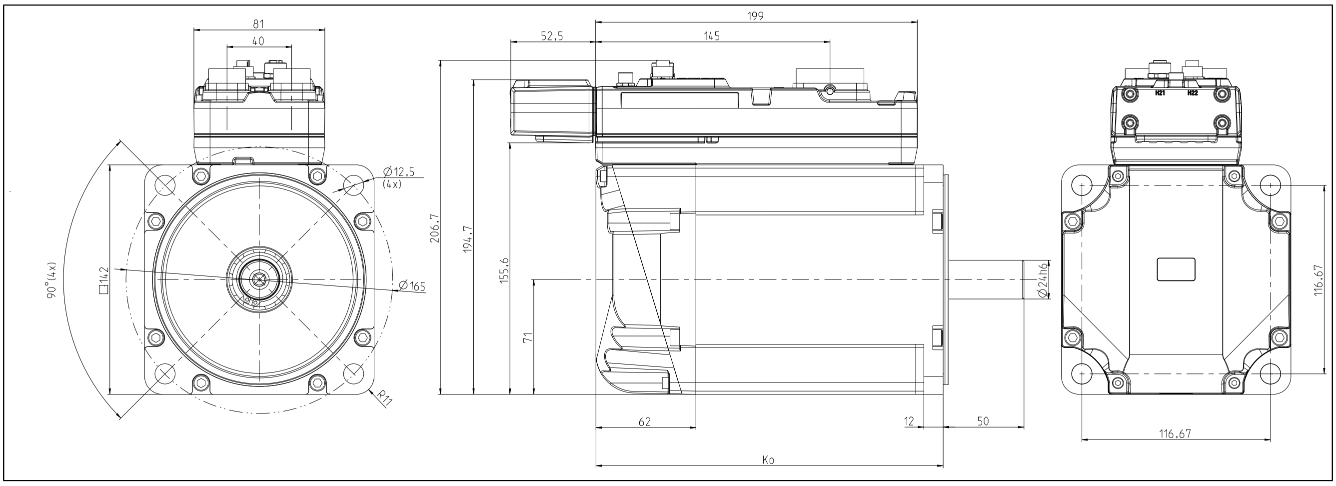


Figure 50: Flange details

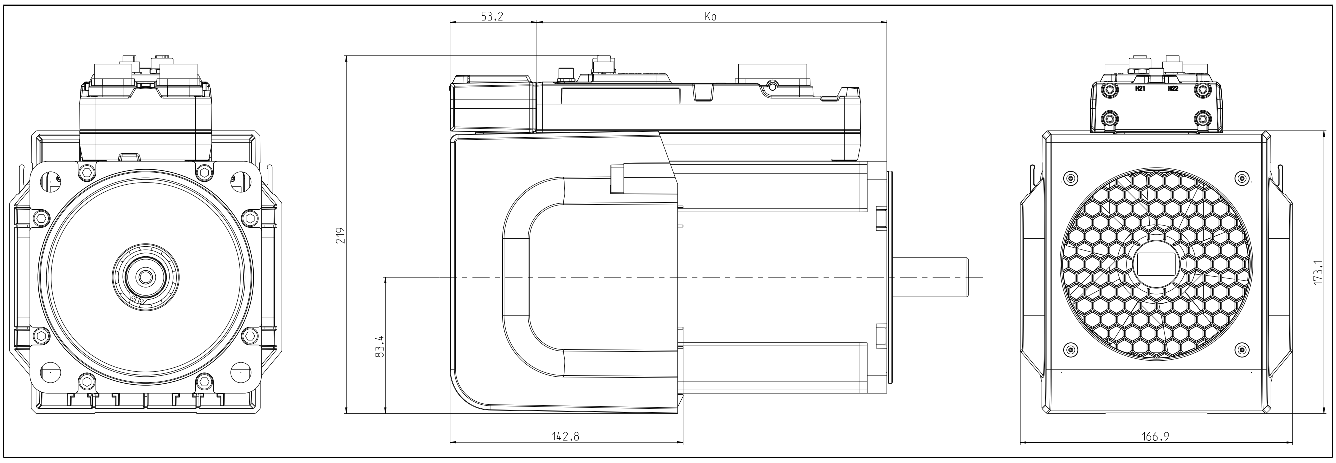
		Extension of K_0 depending on motor option [mm]	
Model number	**K_0**	**Holding brake**	**Oil seal**
8DI44x.Dxggghi00-1	222.5	32	---
8DI45x.Dxggghi00-1	246.5	32	---
8DI46x.Dxggghi00-1	266.5	32	---

3.3.3.1.3 Size 5

8DI5dS.ffggghi00-1



With optional fan kit 8ZDFB5000000.000-0



A-side flange detail
Standard bearing

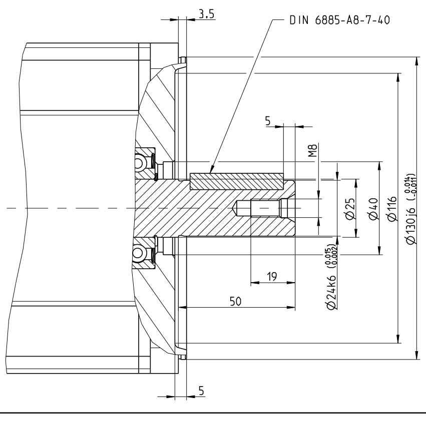


Figure 51: Flange details

		Extension of K_0 depending on motor option [mm]	
Model number	**K_0**	**Holding brake**	**Oil seal**
8DI54x.Dxggghi00-1	215	35	---
8DI55x.Dxggghi00-1	240	30	---
8DI56x.Dxggghi00-1	265	30	---

3.3.4 Dimensioning

See chapter "ACOPOSmotor SafeMOTION / Dimensioning" in user's manual "Decentralized motion control".

4 ACOPOS P3 SafeMOTION

4.1 Technical data

4.1.1 SafeMOTION - Order key

8EI	ccc	d	e	f	g	h	.	i	j	kk	-	1

	Symbol	Name
b	I	ACOPOS P3 servo drive
ccc	123	Continuous current A_{eff} e.g. 2X2 ... 2.2 A
d	H M	3x 200 - 480 VAC 3x 200 - 230 VAC or 1x 110 - 230 VAC
e	W	Wall mounting
f	S D T	1-axis module 2-axis module 3-axis module
g	S	SafeMOTION with encoder
h	x [1)] 0	Module-specific options Standard
i	x [1)] 0	Plug-in module included in delivery No plug-in module included in delivery
j	x [1)] 0	Configurable accessories included in delivery No configurable accessories included in delivery
kk	xx [1)] 00	Customized options No customized options

Table 116: ACOPOS P3 8EI servo drive - Order key

1) Placeholder for the respective option or configuration.

4.1.1.1 Continuous current A_{eff} (ccc)

The continuous current A_{eff} of the ACOPOS P3 8EI servo drive is listed in the form of a 3-digit code (ccc) as part of the model number.

Continuous current A_{eff}	Order code (ccc)	1-axis module	2-axis module	3-axis module
1.6 A	1X6	Yes	No	No
2.2 A	2X2	Yes	Yes	Yes
4.5 A	4X5	Yes	Yes	Yes
8.8 A	8X8	Yes	Yes	Yes

Table 117: Continuous current (ccc)

4.1.1.2 Plug-in modules (i)

ACOPOS P3 8EI servo drives can be configured with our without an included plug-in module. The selected plug-in module is added to the content of delivery and included in the package containing the servo drive.

Order code (i)	Plug-in module	
A	Resolver 1x interface	8EAC0122.001-1
C	Resolver 3x interface	8EAC0122.003-1
D	Digital I/O interface	8EAC0130.000-1
H	Digital multi-encoder interface, 1x interface	8EAC0150.001-1
J	Digital multi-encoder interface, 3x interface	8EAC0150.003-1
K	Incremental encoder with 1 interface	8EAC0151.001-1
L	Incremental encoder with 3 Interfaces	8EAC0151.003-1
M	Analog multi-encoder interface, 1x interface	8EAC0152.001-1
N	Analog multi-encoder interface, 3x interface	8EAC0152.003-1
P	Digital I/O Interface with terminal 8TB0230.221A-00	8EAC0130.000-1
0	No plug-in module included in delivery	

Table 118: Plug-in modules (i)

4.1.1.3 Configurable accessories (j)

ACOPOS P3 8EI servo drives can be configured to include accessories. The selected accessories are added to the content of delivery and included in the package containing the servo drive.

Order code (j)	Internal braking resistor	Front cover	Connector set 2 (2-row)	Connector set 1 (1-row)
0	No	No	No	Yes
1	No	No	Yes	No
2	No	Yes	No	Yes
3	No	Yes	Yes	No
4	Yes	No	No	Yes
5	Yes	No	Yes	No
6	Yes	Yes	No	Yes
7	Yes	Yes	Yes	No
A	No	No	No	No
B	No	Yes	No	No
C	Yes	No	No	No
D	Yes	Yes	No	No

Table 119: Configurable accessories (j)

4.1.2 8EI SafeMOTION servo drives

4.1.2.1 Status indicators

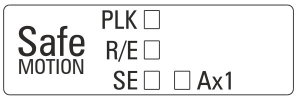
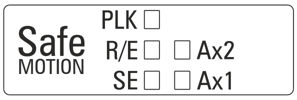
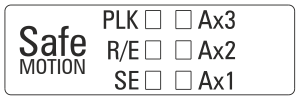
1-axis modules	2-axis modules	3-axis modules
		

Table 120: 8EI SafeMOTION servo drives - Status indicators

4.1.2.1.2 POWERLINK - LED status indicators

Label	Color	Description	
PLK	Green	Blinking green (1x)	The client detects a valid POWERLINK frame on the network.
		Blinking green (2x)	Cyclic operation on the network is taking place, but the client itself is not yet a participant.
		Blinking green (3x)	Cyclic operation of the client is in preparation.
		Solid green	The client is participating in cyclic operation.
		Flickering green	The client is not participating in cyclic operation and also does not detect any other stations on the network participating in cyclic operation.
	Red	Solid red	The POWERLINK node number of the module is 0.
		Blinking red/green	The client is in an error state (drops out of cyclic operation).
	Orange	Solid orange	Module booting

Table 121: POWERLINK - LED status indicators

4.1.2.1.3 Ax1/Ax2/Ax3 - LED status indicators

Label	Color	Function	Description	
Ax1 Ax2 Ax3	Green	Ready	Solid green	The module is operational and the power stage can be enabled (operating system present and booted, no permanent or temporary errors).
			Blinking green	The module is not ready for operation. **Examples:** • No signal on one or both enable inputs • DC bus voltage outside the tolerance range • Overtemperature on the motor (temperature sensor) • Motor feedback not connected or defective • Motor temperature sensor not connected or defective • Overtemperature on the module (IGBT junction, heat sink, etc.) • Disturbance on network
	Red	Error	Solid red	There is a permanent error on the module. **Examples:** • Permanent overcurrent • Invalid data in EPROM
			Blinking red	Burning ACOPOS P3 operating system
	Orange	Run	Solid orange	The module's power stage is enabled.
	---	---	LED off	No voltage being supplied to module

Table 122: Ax1/Ax2/Ax3 - LED status indicators

4.1.2.1.4 R/E and SE - LED status indicators

LED	Color		Description
R/E	Green	Red	
	Off	Off	Module not supplied with power, no communication
	Single flash		Mode "Unlink"
	Double flash		Updating firmware
	Blinking		Mode PREOPERATIONAL
	On		Mode RUN
	On	Single flash, inverse	Safety-related firmware invalid
		Triple flash, inverse	Updating safety-related firmware
		On	Communication error
	Off	On	Error

Table 123: R/E and SE - LED status indicators

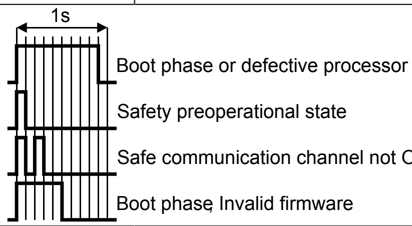
<table>
<tr><th>LED</th><th colspan="2">Color</th><th>Description</th></tr>
<tr><td rowspan="4">SE</td><td rowspan="3">Red</td><td>Off</td><td>Mode RUN</td></tr>
<tr><td colspan="2">
</td></tr>
<tr><td>On</td><td>Non-acknowledgeable error state, FAIL SAFE state</td></tr>
<tr><td colspan="3">The two "SE" indicators are two separate LEDs that show the states of safety processor 1 and safety processor 2. This is only distinguishable when the front cover is open, however.</td></tr>
</table>

Table 123: R/E and SE - LED status indicators

4.1.2.2 1-axis modules

4.1.2.2.1 Mains input voltage - 1x 110 to 230 VAC / 3x 200 to 230 VAC

4.1.2.2.1.1 Continuous power up to 2 kW (motor connection)

Order data

Model number	Short description	Figure
	1-axis modules SafeMOTION	
8EI1X6MWSS0.XXXX-1	ACOPOS P3 servo drive, 1x 110-230 VAC, 3x 200-230 VAC, 1.6 A, SafeMOTION EnDat 2.2, 1 axis, wall mounting	
8EI2X2MWSS0.XXXX-1	ACOPOS P3 servo drive, 1x 110-230 VAC, 3x 200-230 VAC, 2x 2.2 A, SafeMOTION EnDat 2.2, 1 axis, wall mounting	
8EI4X5MWSS0.XXXX-1	ACOPOS P3 servo drive, 1x 110-230 VAC, 3x 200-230 VAC, 2x 4.5 A, SafeMOTION EnDat 2.2, 1 axis, wall mounting	
8EI8X8MWSS0.XXXX-1	ACOPOS P3 servo drive, 1x 110-230 VAC, 3x 200-230 VAC, 2x 8.8 A, SafeMOTION EnDat 2.2, 1 axis, wall mounting	
	Optional accessories	
	Display modules	
8EAD0000.000-1	Display module, LCD, 128 x 64, black/white, 1x USB 3.0	
	Front covers	
8EXA100.0010-00	ACOPOS P3 cover, B&R orange, single-width, height 1	
8EXA100.0020-00	ACOPOS P3 cover, B&R dark gray, single-width, height 1	
	Plug-in modules	
8EAC0122.001-1	ACOPOS P3 plug-in module, resolver interface 10 kHz	
8EAC0130.000-1	ACOPOS P3 plug-in module, 8 digital I/O 24 V (4x 400 mA, 4x 100 mA) individually configurable as inputs or outputs, 2 digital I/O 24 V 2 A configurable in pairs as inputs or outputs, order terminal block 8TB0230.221A-00 separately!	
8EAC0150.001-1	ACOPOS P3 plug-in module, digital multi-encoder interface	
8EAC0151.001-1	ACOPOS P3 plug-in module, incremental encoder interface	
8EAC0152.001-1	ACOPOS P3 plug-in module, analog multi-encoder interface	
	Shield component sets	
8SCSE01.0100-00	ACOPOS P3 shield component set: 1x ACOPOS P3 shield mounting plate, 1x 2x M3x6 screws	
8SCSE02.0100-00	ACOPOS P3 shield component set: 1x shield component set, type SK14	
8SCSE02.0200-00	ACOPOS P3 shield component set: 1x shield component set, type SK20	
	Terminals	
8TB2104.2210-00	Push-in terminal block 4-pin, 1-row, pitch: 5.08 mm, label 1: numbered consecutively	
8TB3102.222C-20	Push-in terminal block, 2-pin, single row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3103.222A-20	Push-in terminal block, 3-pin, 1-row, spacing: 7.62 mm, label 2: PE RB- RB+, A keying: 000	
8TB3106.223C-20	Push-in terminal block, 6-pin, 1-row, with locking mechanism, spacing: 7.62 mm, label 3: PE L3 N(L2) L1 DC- DC+, C keying: 000010	
8TB3202.222C-40	Push-in terminal block, 2-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3206.223C-40	Push-in terminal block, 6-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 3: PE L3 N(L2) L1 DC- DC+, C keying: 000010	
8TB3308.222A-00	Push-in terminal block 4+4-pin 1-row/2-row, spacing: 7.62 mm, label 2: T- B- T+ B+ PE W V U A keying: 0000	

Table 124: 8EI1X6MWSS0.XXXX-1, 8EI2X2MWSS0.XXXX-1, 8EI4X5MWSS0.XXXX-1, 8EI8X8MWSS0.XXXX-1 - Order data

Connection	1-row connector	2-row connector
X1	8TB3106.223C-20	8TB3206.223C-40
X2	8TB3102.222C-20	8TB3202.222C-40
X5x	8TB3308.222A-00	
X6	8TB3103.222A-20	
X7	8TB2104.2210-50	8TB2204.2210-50
X8	8TB2104.2210-00	

Table 125: Terminal blocks - Model numbers

Information:

Connector X7 does not exist on ACOPOS P3 SafeMOTION servo drives.

Technical data

Model number	8EI1X6MWSS0.XXXX-1	8EI2X2MWSS0.XXXX-1	8EI4X5MWSS0.XXXX-1	8EI8X8MWSS0.XXXX-1
General information				
Slots for plug-in modules	1			
Certifications				
CE	Yes			
UL	cULus E225616 Power conversion equipment			
EAC	Yes			
KC	Yes			
Mains connection				
Network configurations	TN-S, TN-C-S with grounded neutral			
Mains input voltage	1x 110 VAC to 230 VAC ±10% 3x 200 VAC to 230 VAC ±10%			
Frequency	50/60 Hz ±4%			
Installed load	Max. 1 kVA	Max. 1.25 kVA	Max. 2.5 kVA	Max. 5 kVA
Inrush current	Max. 22 A			
Switch-on interval	Typ. 60 s			
Integrated line filter per EN 61800-3, category C3	No [1)]			
Terminal connection cross section				
Flexible and fine-stranded wires				
With wire end sleeves	0.25 to 4 mm²			
Approbation data				
UL/C-UL-US	24 to 8 AWG			
CSA	24 to 8 AWG			
Power dissipation at device nominal power without braking resistor	[(30 + 10 * P_{AVG} [kW] + 5.8 * I_{AX1} [A] + 0.25 * I_{BR1}^2 [A]) + P_{VSLOT}) * 1.1] [W] [2)]	[(30 + 10 * P_{AVG} [kW] + 5.8 * I_{AX1} [A] + 0.25 * I_{BR1}^2 [A]) + P_{VSLOT}) * 1.1] [W] [3)]		
Max. cable length	3 m [4)]			
DC bus connection				
Continuous power [5)]	0.4 kW [6)]	0.5 kW [6)]	1 kW [6)]	2 kW
Reduction of continuous power depending on mains input voltage				
Mains input voltage <230 VAC	0.4 kW * (Mains input voltage [V] / 230 V)	0.5 kW * (Mains input voltage [V] / 230 V)	1 kW * (Mains input voltage [V] / 230 V)	2 kW * (Mains input voltage [V] / 230 V)
DC bus capacitance	1880 µF			
Terminal connection cross sections				
Flexible and fine-stranded wires				
With wire end sleeves	0.25 to 4 mm²			
Approbation data				
UL/C-UL-US	24 to 8 AWG			
CSA	24 to 8 AWG			
Max. cable length	3 m [7)]			
24 VDC power supply				
Input voltage	24 VDC ±25%			
Input capacitance	5500 µF			
Current consumption	0.9 A + Current for motor holding brake [8)]			
Terminal connection cross sections				
Flexible and fine-stranded wires				
With wire end sleeves	0.25 to 4 mm²			
Approbation data				
UL/C-UL-US	24 to 8 AWG			
CSA	24 to 8 AWG			
Max. cable length	30 m			
Motor connection				
Quantity	1			
Continuous power per motor connection [9)]	0.4 kW	0.5 kW	1 kW	2 kW
Continuous current per motor connection [9)]	1.6 A_{eff}	2.2 A_{eff}	4.5 A_{eff}	8.8 A_{eff}
Reduction of continuous current depending on switching frequency [10)]				
Switching frequency 5 kHz	No reduction			
Switching frequency 10 kHz	No reduction			
Switching frequency 20 kHz	No reduction			0.109 A/K (starting at 33.7°C) [11)]
Reduction of continuous current depending on installation elevation				
Starting at 500 m above sea level	0.16 A_{eff} per 1000 m	0.22 A_{eff} per 1000 m	0.45 A_{eff} per 1000 m	0.88 A_{eff} per 1000 m
Peak current per motor connection	4.5 A_{eff}	6 A_{eff}	12.25 A_{eff}	24 A_{eff}
Peak power output	1 kW	1.25 kW	2.5 kW	5 kW
Nominal switching frequency	5 kHz			

Table 126: 8EI1X6MWSS0.XXXX-1, 8EI2X2MWSS0.XXXX-1, 8EI4X5MWSS0.XXXX-1, 8EI8X8MWSS0.XXXX-1 - Technical data

Model number	8EI1X6MWSS0.XXXX-1	8EI2X2MWSS0.XXXX-1	8EI4X5MWSS0.XXXX-1	8EI8X8MWSS0.XXXX-1
Possible switching frequencies [12]	5 / 10 / 20 kHz			
Electrical stress of connected motor per IEC TS 60034-25	Limit value curve A			
Protective measures				
Overload protection	Yes			
Short circuit and ground fault protection	Yes			
Max. output frequency	598 Hz [13]		598 Hz [14]	
Variant				
U, V, W, PE	Male connector			
Shield connection	Yes			
Terminal connection cross section				
Flexible and fine-stranded wires				
With wire end sleeves	1.5 to 6 mm²			
Approbation data				
UL/C-UL-US	24 to 8 AWG			
CSA	24 to 8 AWG			
Max. motor cable length depending on switching frequency				
Switching frequency 5 kHz	75 m [15]			
Switching frequency 10 kHz	38 m [15]			
Switching frequency 20 kHz	19 m [15]			
Motor holding brake connection				
Quantity	1			
Output voltage [16]	Depends on the input voltage on connector X2			
Continuous current	1.3 A			
Max. internal resistance	0.25 Ω			
Extinction potential	Approx. 30 V			
Max. extinction energy per switching operation	1.5 Ws			
Max. switching frequency	0.5 Hz			
Protective measures				
Overload and short-circuit protection	Yes			
Open circuit monitoring	Yes			
Undervoltage monitoring	Yes			
Response threshold for open circuit monitoring	Approx. 30 mA			
Response threshold for undervoltage monitoring	Approx. 23 V			
Max. breaking current SBC	60 mA			
Max. cable length	75 m [17]			
Braking resistor [18]				
Peak power int./ext.	1.5 kW / 11 kW			
Continuous power int./ext.	100 W / 970 W			
Minimum braking resistance (ext.)	12 Ω			
Terminal connection cross section				
Flexible and fine-stranded wires				
With wire end sleeves	0.25 to 4 mm²			
Approbation data				
UL/C-UL-US	24 to 8 AWG			
CSA	24 to 8 AWG			
Protective measures				
Overload protection	No			
Short circuit and ground fault protection	Short circuit protection: Yes Ground fault protection: No			
Max. cable length	3 m			
Fieldbus				
Type	POWERLINK V2 controlled node (CN)			
Variant	2x RJ45, shielded, 2-port hub			
Cable length	Max. 100 m between 2 stations (segment length)			
Transfer rate	100 Mbit/s			
Encoder interfaces				
Quantity	1			
Type	Digital multi-encoder interface, configurable [19]			
Connections	8-pin female mini I/O connector			
Status indicators	None [20]			
Electrical isolation				
Encoder - ACOPOS P3	No			
Max. encoder cable length	75 m Depends on the cross section of the power supply wires of the encoder cable [21]			

Table 126: 8EI1X6MWSS0.XXXX-1, 8EI2X2MWSS0.XXXX-1, 8EI4X5MWSS0.XXXX-1, 8EI8X8MWSS0.XXXX-1 - Technical data

Model number	8EI1X6MWSS0.XXXX-1	8EI2X2MWSS0.XXXX-1	8EI4X5MWSS0.XXXX-1	8EI8X8MWSS0.XXXX-1
Encoder power supply				
Output voltage	Configurable Typ. 11.45 V ± 0.1 V / 5.2 V ± 0.1 V [22][23]		Configurable Typ. 11.45 V ± 0.1 V / 5.2 V ± 0.1 V [23][24]	
Load capacity	Max. 300 mA			
Sense lines	2, compensation of max. 2x 0.7 V			
Protective measures				
Short-circuit proof	Yes			
Overload-proof	Yes			
Synchronous serial interface				
Signal transmission	RS485 [25]			
Data transfer rate	Depends on the configured encoder type			
Differential voltage [26]				
Minimum	2.0 V			
Maximum	6.0 V			
Max. power consumption per encoder interface	$P_{ENCODER}$ [W] = U_{24V} [V] * ($I_{ENCODER}$ [A] * 0.7) + 0.5 W [27]			
Trigger inputs				
Quantity	2			
Circuit	Sink			
Electrical isolation				
Input - ACOPOS P3	Yes			
Input - Input	Yes			
Input voltage				
Nominal	24 VDC			
Maximum	30 VDC			
Switching threshold				
Low	<5 V			
High	>15 V			
Input current at nominal voltage	7 mA			
Switching delay				
Rising edge	<51 µs			
Falling edge	<52 µs			
Modulation compared to ground potential	Max. ±38 V			
Terminal connection cross section				
Flexible and fine-stranded wires				
With wire end sleeves	0.25 to 2.5 mm²			
Approbation data				
UL/C-UL-US	26 to 12 AWG			
CSA	26 to 12 AWG			
Max. cable length	100 m			
Support				
Motion system				
mapp Motion	5.00.0 and higher			
ACP10/ARNC0	3.16.1 and higher			3.16.0 and higher
Operating conditions				
Permissible mounting orientations				
Hanging vertically	Yes			
Standing horizontally	Yes			
Installation elevation above sea level				
Nominal	0 to 500 m			
Maximum	4000 m			
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)			
Overvoltage category per EN 61800-5-1	III			
Degree of protection per EN 60529	IP20 [28]			
Ambient conditions				
Temperature				
Operation				
Nominal	5 to 40°C			
Maximum	55°C			
Storage	-25 to 55°C			
Transport	-25 to 70°C			
Relative humidity				
Operation	5 to 85%, non-condensing			
Storage	5 to 95%			
Transport	95% at 40°C			

Table 126: 8EI1X6MWSS0.XXXX-1, 8EI2X2MWSS0.XXXX-1, 8EI4X5MWSS0.XXXX-1, 8EI8X8MWSS0.XXXX-1 - Technical data

Model number	8EI1X6MWSS0.XXXX-1	8EI2X2MWSS0.XXXX-1	8EI4X5MWSS0.XXXX-1	8EI8X8MWSS0.XXXX-1
Mechanical properties				
Dimensions				
Width	66 mm			
Height	290 mm			
Depth				
Wall mounting	258.5 mm (with 8EXA front cover: 261 mm)			
Weight	3.2 kg			

Table 126: 8EI1X6MWSS0.XXXX-1, 8EI2X2MWSS0.XXXX-1, 8EI4X5MWSS0.XXXX-1, 8EI8X8MWSS0.XXXX-1 - Technical data

1) A line filter must be connected.
CE compliance can only be ensured by connecting a B&R line filter (8x0F...).
In extreme cases, using line filters from 3rd-party manufacturers can result in irreparable damage to the 8EI ACOPOS P3 servo drive.
2) P_{AVG} ... Average continuous power of the module
I_{AX1} ... RMS value of the current on axis 1
I_{BR1} ... Nominal current of the motor holding brake on axis 1
P_{VSLOT} ... Power dissipation of the 8EAC plug-in module
3) P_{AVG} ... Average continuous power of the module
I_{AX1} ... RMS value of the current on axis 1
I_{BR1} ... Nominal current of the motor holding brake for axis 1
P_{VSLOT} ... Power dissipation of the 8EAC plug-in module
4) Maximum cable length between line filter and mains connection on the module.
5) Valid for a mains input voltage of 230 VAC.
The sum of the continuous power values on all motor connections and the power of the DC bus connector is not permitted to exceed this value.
6) The value can be higher under certain conditions.
7) This value applies to unshielded wiring inside a control cabinet.
Maximum length of the DC bus wiring inside a control cabinet.
8) Current consumption depends on the configuration of the ACOPOS P3 8EI servo drive.
The inrush current of the 24 VDC power supply is not limited by the module.
9) Valid under the following conditions: 325 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
10) The temperature specifications refer to the ambient temperature.
11) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
12) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
13) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
14) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use per Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
15) The sum of the length of all motor cables connected to this module is not permitted to exceed this value.
16) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified input voltage and wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
17) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified cable length. For the permissible operating voltage range of the holding brake, see the user documentation for the motor being used.
18) There is a connection for external braking resistors. An internal braking resistor is available as an option.
19) The encoder type is not predefined from the factory. The encoder type necessary in each case must be configured in Automation Studio.
20) The direction of rotation of the encoder can be displayed on the 8EAD0000.000-1 display module.
21) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 75 m is not permitted to exceeded):

$l_{max} = f / I_G * A * 1/(2*\rho)$

f ... (Output voltage of encoder interface [V] - Min. permissible supply voltage of connected encoder [V]) * 1.1
I_G ... Max. current consumption of connected encoder [A]
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
22) The output voltage is not predefined from the factory (with the exception of encoder types EnDat 2.2 and HIPERFACE DSL). It must be configured in Automation Studio based on the encoder type. If no output voltage is configured, then the encoder will not be supplied by digital multi-encoder interface X4x. Power to the encoder can then be supplied externally.
23) Output voltage 5.2 V is only available under the following conditions:
- 8EI servo drive with 8ZECxxx revision D0 and higher - see the device information on the left side cover of the 8EI servo drive
- ACOPOS operating system 3.15.0 and higher (for 8EIxxxxxD... 2-axis modules and 8EIxxxxxT... 3-axis modules)
- ACOPOS operating system 3.17.0 and higher (for 8EIxxxxxS... 1-axis modules)
24) The output voltage is not predefined from the factory (with the exception of encoder types EnDat 2.2 and HIPERFACE DSL) . It must be configured in Automation Studio based on the encoder type. If no output voltage is configured, then the encoder will not be supplied by digital multi-encoder interface X4x. Power to the encoder can then be supplied externally.
25) Except encoder type HIPERFACE DSL.
26) Values valid for clock output and data input. Except encoder type HIPERFACE DSL.
27) $I_{ENCODER}$ ... Current consumption of the encoder
U_{24V} ... Input voltage on the +24 VDC input of the module
28) The specified degree of protection is only met if either the slot cover is installed on the module or an 8EAC plug-in module is installed and suitable terminals are connected to all connectors and all fans are installed.

4.1.2.2.2 Mains input voltage - 3x 200 to 480 VAC

4.1.2.2.2.1 Continuous power up to 4 kW (motor connection)

Order data

Model number	Short description	Figure
	1-axis modules SafeMOTION	
8EI1X6HWSS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 1.6 A, SafeMOTION EnDat 2.2, 1 axis, wall mounting	
8EI2X2HWSS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 2.2 A, SafeMOTION EnDat 2.2, 1 axis, wall mounting	
8EI4X5HWSS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 4.5 A, SafeMOTION EnDat 2.2, 1 axis, wall mounting	
8EI8X8HWSS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 8.8 A, SafeMOTION EnDat 2.2, 1 axis, wall mounting	
	Optional accessories	
	Display modules	
8EAD0000.000-1	Display module, LCD, 128 x 64, black/white, 1x USB 3.0	
	Front covers	
8EXA100.0010-00	ACOPOS P3 cover, B&R orange, single-width, height 1	
8EXA100.0020-00	ACOPOS P3 cover, B&R dark gray, single-width, height 1	
	Plug-in modules	
8EAC0122.001-1	ACOPOS P3 plug-in module, resolver interface 10 kHz	
8EAC0130.000-1	ACOPOS P3 plug-in module, 8 digital I/O 24 V (4x 400 mA, 4x 100 mA) individually configurable as inputs or outputs, 2 digital I/O 24 V 2 A configurable in pairs as inputs or outputs, order terminal block 8TB0230.221A-00 separately!	
8EAC0150.001-1	ACOPOS P3 plug-in module, digital multi-encoder interface	
8EAC0151.001-1	ACOPOS P3 plug-in module, incremental encoder interface	
8EAC0152.001-1	ACOPOS P3 plug-in module, analog multi-encoder interface	
	Shield component sets	
8SCSE01.0100-00	ACOPOS P3 shield component set: 1x ACOPOS P3 shield mounting plate, 1x 2x M3x6 screws	
8SCSE02.0100-00	ACOPOS P3 shield component set: 1x shield component set, type SK14	
8SCSE02.0200-00	ACOPOS P3 shield component set: 1x shield component set, type SK20	
	Terminals	
8TB2104.2210-00	Push-in terminal block 4-pin, 1-row, pitch: 5.08 mm, label 1: numbered consecutively	
8TB3102.222C-20	Push-in terminal block, 2-pin, single row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3103.222A-20	Push-in terminal block, 3-pin, 1-row, spacing: 7.62 mm, label 2: PE RB- RB+, A keying: 000	
8TB3106.222B-20	Push-in terminal block, 6-pin, single row, with locking mechanism, spacing: 7.62 mm, label 2: PE L3 L2 L1 DC- DC+, B keying: 000001	
8TB3202.222C-40	Push-in terminal block, 2-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3206.222B-40	Push-in terminal block, 6-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 2: PE L3 L2 L1 DC- DC+, C keying: 000001	
8TB3308.222A-00	Push-in terminal block 4+4-pin 1-row/2-row, spacing: 7.62 mm, label 2: T- B- T+ B+ PE W V U A keying: 0000	

Table 127: 8EI1X6HWSS0.XXXX-1, 8EI2X2HWSS0.XXXX-1, 8EI4X5HWSS0.XXXX-1, 8EI8X8HWSS0.XXXX-1 - Order data

Connection	1-row connector	2-row connector
X1	8TB3106.222B-20	8TB3206.222B-40
X2	8TB3102.222C-20	8TB3202.222C-40
X5x	8TB3308.222A-00	
X6	8TB3103.222A-20	
X7	8TB2104.2210-50	8TB2204.2210-50
X8	8TB2104.2210-00	

Table 128: Terminal blocks - Model numbers

Information:

Connector X7 does <u>not</u> exist on ACOPOS P3 SafeMOTION servo drives.

Technical data

Model number	8EI1X6HWSS0.XXXX-1	8EI2X2HWSS0.XXXX-1	8EI4X5HWSS0.XXXX-1	8EI8X8HWSS0.XXXX-1
General information				
Slots for plug-in modules	1			
Certifications				
CE	Yes			
UL	cULus E225616 Power conversion equipment			
EAC	Yes			
KC	Yes			
Mains connection				
Network configurations	TN-S, TN-C-S with grounded neutral			
Mains input voltage	3x 200 VAC to 480 VAC ±10%			
Frequency	50/60 Hz ±4%			
Installed load	Max. 1.75 kVA	Max. 2.5 kVA	Max. 5 kVA	Max. 10 kVA
Inrush current	Max. 45 A			
Switch-on interval	Typ. 60 s			
Integrated line filter per EN 61800-3, category C3	No 1)			
Terminal connection cross section				
Flexible and fine-stranded wires				
With wire end sleeves	0.25 to 4 mm²			
Approbation data				
UL/C-UL-US	24 to 8 AWG			
CSA	24 to 8 AWG			
Power dissipation at device nominal power without braking resistor	[(40 + 6.9 * P_{AVG} [kW] + 7.5 * I_{AX1} [A] + 0.25 * I_{BR1}^2 [A] + P_{VSLOT}) * 1.1] [W] 2)	[(40 + 6.9 * P_{AVG} [kW] + 7.5 * I_{AX1} [A] + 0.25 * I_{BR1}^2 [A] + P_{VSLOT}) * 1.1] [W] 3)	[(40 + 6.9 * P_{AVG} [kW] + 7.5 * I_{AX1} [A] + 0.25 * I_{BR1}^2 [A] + P_{VSLOT}) * 1.1] [W] 2)	
Max. cable length	3 m 4)			
DC bus connection				
Continuous power 5)	0.7 kW 6)	1 kW 6)	2 kW 6)	4 kW
Reduction of continuous power depending on mains input voltage				
Mains input voltage <3x 400 VAC	0.7 kW * (Mains input voltage [V] / 400 V)	1 kW * (Mains input voltage [V] / 400 V)	2 kW * (Mains input voltage [V] / 400 V)	4 kW * (Mains input voltage [V] / 400 V)
DC bus capacitance	470 µF			
Terminal connection cross sections				
Flexible and fine-stranded wires				
With wire end sleeves	0.25 to 4 mm²			
Approbation data				
UL/C-UL-US	24 to 8 AWG			
CSA	24 to 8 AWG			
Max. cable length	3 m 7)			
24 VDC power supply				
Input voltage	24 VDC ±25%			
Input capacitance	5500 µF			
Current consumption	0.9 A + Current for motor holding brake 8)			
Terminal connection cross sections				
Flexible and fine-stranded wires				
With wire end sleeves	0.25 to 4 mm²			
Approbation data				
UL/C-UL-US	24 to 8 AWG			
CSA	24 to 8 AWG			
Max. cable length	30 m			
Motor connection				
Quantity	1			
Continuous power per motor connection 9)	0.7 kW	1 kW	2 kW	4 kW
Continuous current per motor connection 9)	1.6 A_{eff}	2.2 A_{eff}	4.5 A_{eff}	8.8 A_{eff}
Reduction of continuous current depending on switching frequency 10)				
Switching frequency 5 kHz	No reduction			
Switching frequency 10 kHz	No reduction			
Switching frequency 20 kHz	No reduction			0.105 A/K (starting at 11.2°C) 11)
Reduction of continuous current depending on installation elevation				
Starting at 500 m above sea level	0.16 A_{eff} per 1000 m	0.22 A_{eff} per 1000 m	0.45 A_{eff} per 1000 m	0.88 A_{eff} per 1000 m
Peak current per motor connection	4.5 A_{eff}	6 A_{eff}	12.25 A_{eff}	24 A_{eff}
Peak power output	1.75 kW	2.5 kW	5 kW	10 kW
Nominal switching frequency	5 kHz			
Possible switching frequencies 12)	5 / 10 / 20 kHz			

Table 129: 8EI1X6HWSS0.XXXX-1, 8EI2X2HWSS0.XXXX-1, 8EI4X5HWSS0.XXXX-1, 8EI8X8HWSS0.XXXX-1 - Technical data

Model number	8EI1X6HWSS0.XXXX-1	8EI2X2HWSS0.XXXX-1	8EI4X5HWSS0.XXXX-1	8EI8X8HWSS0.XXXX-1
Electrical stress of connected motor per IEC TS 60034-25	Limit value curve A			
Protective measures				
Overload protection	Yes			
Short circuit and ground fault protection	Yes			
Max. output frequency	598 Hz [13]			598 Hz [14]
Variant				
U, V, W, PE	Male connector			
Shield connection	Yes			
Terminal connection cross section				
Flexible and fine-stranded wires				
With wire end sleeves	1.5 to 6 mm²			
Approbation data				
UL/C-UL-US	24 to 8 AWG			
CSA	24 to 8 AWG			
Max. motor cable length depending on switching frequency				
Switching frequency 5 kHz	75 m [15]			
Switching frequency 10 kHz	38 m [15]			
Switching frequency 20 kHz	19 m [15]			
Motor holding brake connection				
Quantity	1			
Output voltage [16]	Depends on the input voltage on connector X2			
Continuous current	1.3 A			
Max. internal resistance	0.25 Ω			
Extinction potential	Approx. 30 V			
Max. extinction energy per switching operation	1.5 Ws			
Max. switching frequency	0.5 Hz			
Protective measures				
Overload and short-circuit protection	Yes			
Open circuit monitoring	Yes			
Undervoltage monitoring	Yes			
Response threshold for open circuit monitoring	Approx. 30 mA			
Response threshold for undervoltage monitoring	Approx. 23 V			
Max. breaking current SBC	60 mA			
Max. cable length	75 m [17]			
Braking resistor [18]				
Peak power int./ext.	7 kW / 25 kW			
Continuous power int./ext.	100 W / 2 kW			
Minimum braking resistance (ext.)	25 Ω			
Terminal connection cross section				
Flexible and fine-stranded wires				
With wire end sleeves	0.25 to 4 mm²			
Approbation data				
UL/C-UL-US	24 to 8 AWG			
CSA	24 to 8 AWG			
Protective measures				
Overload protection	No			
Short circuit and ground fault protection	Short circuit protection: Yes Ground fault protection: No			
Max. cable length	3 m			
Fieldbus				
Type	POWERLINK V2 controlled node (CN)			
Variant	2x RJ45, shielded, 2-port hub			
Cable length	Max. 100 m between 2 stations (segment length)			
Transfer rate	100 Mbit/s			
Encoder interfaces				
Quantity	1			
Type	Digital multi-encoder interface, configurable [19]			
Connections	8-pin female mini I/O connector			
Status indicators	None [20]			
Electrical isolation				
Encoder - ACOPOS P3	No			
Max. encoder cable length	75 m Depends on the cross section of the power supply wires of the encoder cable [21]			

Table 129: 8EI1X6HWSS0.XXXX-1, 8EI2X2HWSS0.XXXX-1, 8EI4X5HWSS0.XXXX-1, 8EI8X8HWSS0.XXXX-1 - Technical data

Model number	8EI1X6HWSS0.XXXX-1	8EI2X2HWSS0.XXXX-1	8EI4X5HWSS0.XXXX-1	8EI8X8HWSS0.XXXX-1
Encoder power supply				
Output voltage	Configurable Typ. 11.45 V ± 0.1 V / 5.2 V ± 0.1 V [22)23)]	Configurable Typ. 11.45 V ± 0.1 V / 5.2 V ± 0.1 V [23)24)]	Configurable Typ. 11.45 V ± 0.1 V / 5.2 V ± 0.1 V [22)23)]	
Load capacity	Max. 300 mA			
Sense lines	2, compensation of max. 2x 0.7 V			
Protective measures				
Short-circuit proof	Yes			
Overload-proof	Yes			
Synchronous serial interface				
Signal transmission	RS485 [25)]			
Data transfer rate	Depends on the configured encoder type			
Differential voltage [26)]				
Minimum	2.0 V			
Maximum	6.0 V			
Max. power consumption per encoder interface	$P_{ENCODER}$ [W] = U_{24V} [V] * ($I_{ENCODER}$ [A] * 0.7) + 0.5 W [27)]			
Trigger inputs				
Quantity	2			
Circuit	Sink			
Electrical isolation				
Input - ACOPOS P3	Yes			
Input - Input	Yes			
Input voltage				
Nominal	24 VDC			
Maximum	30 VDC			
Switching threshold				
Low	<5 V			
High	>15 V			
Input current at nominal voltage	7 mA			
Switching delay				
Rising edge	<51 µs			
Falling edge	<52 µs			
Modulation compared to ground potential	Max. ±38 V			
Terminal connection cross section				
Flexible and fine-stranded wires				
With wire end sleeves	0.25 to 2.5 mm²			
Approbation data				
UL/C-UL-US	26 to 12 AWG			
CSA	26 to 12 AWG			
Max. cable length	100 m			
Support				
Motion system				
mapp Motion	5.00.0 and higher			
ACP10/ARNC0	3.16.1 and higher			3.16.0 and higher
Operating conditions				
Permissible mounting orientations				
Hanging vertically	Yes			
Standing horizontally	Yes			
Installation elevation above sea level				
Nominal	0 to 500 m			
Maximum	4000 m			
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)			
Overvoltage category per EN 61800-5-1	III			
Degree of protection per EN 60529	IP20 [28)]			
Ambient conditions				
Temperature				
Operation				
Nominal	5 to 40°C			
Maximum	55°C			
Storage	-25 to 55°C			
Transport	-25 to 70°C			
Relative humidity				
Operation	5 to 85%, non-condensing			
Storage	5 to 95%			
Transport	95% at 40°C			

Table 129: 8EI1X6HWSS0.XXXX-1, 8EI2X2HWSS0.XXXX-1, 8EI4X5HWSS0.XXXX-1, 8EI8X8HWSS0.XXXX-1 - Technical data

Model number	8EI1X6HWSS0.XXXX-1	8EI2X2HWSS0.XXXX-1	8EI4X5HWSS0.XXXX-1	8EI8X8HWSS0.XXXX-1
Mechanical properties				
Dimensions				
Width	66 mm			
Height	290 mm			
Depth				
Wall mounting	258.5 mm (with 8EXA front cover: 261 mm)			
Weight	3.2 kg			

Table 129: 8EI1X6HWSS0.XXXX-1, 8EI2X2HWSS0.XXXX-1, 8EI4X5HWSS0.XXXX-1, 8EI8X8HWSS0.XXXX-1 - Technical data

1) A line filter must be connected.
CE compliance can only be ensured by connecting a B&R line filter (8x0F...).
In extreme cases, using line filters from 3rd-party manufacturers can result in irreparable damage to the 8EI ACOPOS P3 servo drive.
2) P_{AVG} ... Average continuous power of the module
I_{AX1} ... RMS value of the current on axis 1
I_{BR1} ... Nominal current of the motor holding brake for axis 1
P_{VSLOT} ... Power dissipation of the 8EAC plug-in module
3) P_{AVG} ... Average continuous power of the module
I_{AX1} ... RMS value of the current on axis 1
I_{BR1} ... Nominal current of the motor holding brake on axis 1
P_{VSLOT} ... Power dissipation of the 8EAC plug-in module
4) Maximum cable length between line filter and mains connection on the module.
5) Valid for a mains input voltage of ≥3x 400 VAC.
The sum of the continuous power values on all motor connections and the power of the DC bus connector is not permitted to exceed this value.
6) The value can be higher under certain conditions.
7) This value applies to unshielded wiring inside a control cabinet.
Maximum length of the DC bus wiring inside a control cabinet.
8) Current consumption depends on the configuration of the ACOPOS P3 8EI servo drive.
The inrush current of the 24 VDC power supply is not limited by the module.
9) Valid under the following conditions: 560 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
10) The temperature specifications refer to the ambient temperature.
11) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
12) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
13) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
14) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use per Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
15) The sum of the length of all motor cables connected to this module is not permitted to exceed this value.
16) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified input voltage and wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
17) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified cable length. For the permissible operating voltage range of the holding brake, see the user documentation for the motor being used.
18) There is a connection for external braking resistors. An internal braking resistor is available as an option.
19) The encoder type is not predefined from the factory. The encoder type necessary in each case must be configured in Automation Studio.
20) The direction of rotation of the encoder can be displayed on the 8EAD0000.000-1 display module.
21) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 75 m is not permitted to exceeded):

$l_{max} = f / I_G * A * 1/(2*\rho)$

f ... (Output voltage of encoder interface [V] - Min. permissible supply voltage of connected encoder [V]) * 1.1
I_G ... Max. current consumption of connected encoder [A]
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
22) The output voltage is not predefined from the factory (with the exception of encoder types EnDat 2.2 and HIPERFACE DSL) . It must be configured in Automation Studio based on the encoder type. If no output voltage is configured, then the encoder will not be supplied by digital multi-encoder interface X4x. Power to the encoder can then be supplied externally.
23) Output voltage 5.2 V is only available under the following conditions:
- 8EI servo drive with 8ZECxxx revision D0 and higher - see the device information on the left side cover of the 8EI servo drive
- ACOPOS operating system 3.15.0 and higher (for 8EIxxxxxD... 2-axis modules and 8EIxxxxxT... 3-axis modules)
- ACOPOS operating system 3.17.0 and higher (for 8EIxxxxxS... 1-axis modules)
24) The output voltage is not predefined from the factory (with the exception of encoder types EnDat 2.2 and HIPERFACE DSL). It must be configured in Automation Studio based on the encoder type. If no output voltage is configured, then the encoder will not be supplied by digital multi-encoder interface X4x. Power to the encoder can then be supplied externally.
25) Except encoder type HIPERFACE DSL.
26) Values valid for clock output and data input. Except encoder type HIPERFACE DSL.
27) $I_{ENCODER}$ ... Current consumption of the encoder
U_{24V} ... Input voltage on the +24 VDC input of the module
28) The specified degree of protection is only met if either the slot cover is installed on the module or an 8EAC plug-in module is installed and suitable terminals are connected to all connectors and all fans are installed.

4.1.2.2.2.2 Continuous power 6.5 kW to 8.5 kW (motor connection)

Order data

Model number	Short description	Figure
	1-axis modules SafeMOTION	
8EI013HWSS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 13 A, SafeMOTION EnDat 2.2, 1 axis, wall mounting	
8EI017HWSS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 17 A, SafeMOTION EnDat 2.2, 1 axis, wall mounting	
	Optional accessories	
	Display modules	
8EAD0000.000-1	Display module, LCD, 128 x 64, black/white, 1x USB 3.0	
	Front covers	
8EXA200.0010-00	ACOPOS P3 cover, B&R orange, single-width, height 2	
8EXA200.0020-00	ACOPOS P3 cover, B&R dark gray, single-width, height 2	
	Plug-in modules	
8EAC0122.001-1	ACOPOS P3 plug-in module, resolver interface 10 kHz	
8EAC0130.000-1	ACOPOS P3 plug-in module, 8 digital I/O 24 V (4x 400 mA, 4x 100 mA) individually configurable as inputs or outputs, 2 digital I/O 24 V 2 A configurable in pairs as inputs or outputs, order terminal block 8TB0230.221A-00 separately!	
8EAC0150.001-1	ACOPOS P3 plug-in module, digital multi-encoder interface	
8EAC0151.001-1	ACOPOS P3 plug-in module, incremental encoder interface	
8EAC0152.001-1	ACOPOS P3 plug-in module, analog multi-encoder interface	
	Shield component sets	
8SCSE01.0100-00	ACOPOS P3 shield component set: 1x ACOPOS P3 shield mounting plate, 1x 2x M3x6 screws	
8SCSE02.0100-00	ACOPOS P3 shield component set: 1x shield component set, type SK14	
8SCSE02.0200-00	ACOPOS P3 shield component set: 1x shield component set, type SK20	
	Terminals	
8TB2104.2210-00	Push-in terminal block 4-pin, 1-row, pitch: 5.08 mm, label 1: numbered consecutively	
8TB3102.222C-20	Push-in terminal block, 2-pin, single row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3103.222A-20	Push-in terminal block, 3-pin, 1-row, spacing: 7.62 mm, label 2: PE RB- RB+, A keying: 000	
8TB3106.222B-20	Push-in terminal block, 6-pin, single row, with locking mechanism, spacing: 7.62 mm, label 2: PE L3 L2 L1 DC- DC+, B keying: 000001	
8TB3202.222C-40	Push-in terminal block, 2-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3206.222B-40	Push-in terminal block, 6-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 2: PE L3 L2 L1 DC- DC+, C keying: 000001	
8TB3308.222A-00	Push-in terminal block 4+4-pin 1-row/2-row, spacing: 7.62 mm, label 2: T- B- T+ B+ PE W V U A keying: 0000	

Table 130: 8EI013HWSS0.XXXX-1, 8EI017HWSS0.XXXX-1 - Order data

Connection	1-row connector	2-row connector
X1	8TB3106.222B-20	8TB3206.222B-40
X2	8TB3102.222C-20	8TB3202.222C-40
X5x	8TB3308.222A-00	
X6	8TB3103.222A-20	
X7	8TB2104.2210-50	8TB2204.2210-50
X8	8TB2104.2210-00	

Table 131: Terminal blocks - Model numbers

Information:

Connector X7 does not exist on ACOPOS P3 SafeMOTION servo drives.

Technical data

Model number	8EI013HWSS0.XXXX-1	8EI017HWSS0.XXXX-1
General information		
Slots for plug-in modules	1	
Certifications		
CE	Yes	
UL	cULus E225616 Power conversion equipment	
EAC	Yes	
KC	In preparation	
Mains connection		
Network configurations	TN-S, TN-C-S with grounded neutral	
Mains input voltage	3x 200 VAC to 480 VAC ±10%	
Frequency	50 / 60 Hz ±4%	
Installed load	Max. 13.5 kVA	Max. 18 kVA
Inrush current	Max. 50 A	
Switch-on interval	Typically 60 s	
Integrated line filter per EN 61800-3, category C3	No [1]	
Terminal connection cross section		
Flexible and fine-stranded wires		
With wire end sleeves	0.25 to 4 mm²	
Approbation data		
UL/C-UL-US	24 to 8 AWG	
CSA	24 to 8 AWG	
Power dissipation at device nominal power without braking resistor	In preparation	
Max. cable length	3 m [2]	
DC bus connection		
Continuous power [3]	6.5 kW [4]	8.5 kW
Reduction of continuous power depending on mains input voltage		
Mains input voltage <3x 400 VAC	6.5 kW * (Mains input voltage [V] / 400 V)	8.5 kW * (Mains input voltage [V] / 400 V)
DC bus capacitance	940 µF	
Terminal connection cross sections		
Flexible and fine-stranded wires		
With wire end sleeves	0.25 to 4 mm²	
Approbation data		
UL/C-UL-US	24 to 8 AWG	
CSA	24 to 8 AWG	
Max. cable length	3 m [5]	
24 VDC power supply		
Input voltage	24 VDC ±25%	
Input capacitance	5500 µF	
Current consumption	1.2 A + Current for motor holding brake [6]	
Terminal connection cross sections		
Flexible and fine-stranded wires		
With wire end sleeves	0.25 to 4 mm²	
Approbation data		
UL/C-UL-US	24 to 8 AWG	
CSA	24 to 8 AWG	
Max. cable length	30 m	
Motor connection		
Quantity	1	
Continuous power per motor connection [7]	6.5 kW	8.5 kW
Continuous current per motor connection [7]	13 A_{eff}	17 A_{eff}
Reduction of continuous current depending on switching frequency		
Switching frequency 5 kHz	No reduction	0.2 A/K (starting at 40°C) [8]
Switching frequency 10 kHz	0.2 A/K (starting at 30°C) [8]	0.2 A/K (starting at 10°C) [8]
Switching frequency 20 kHz	0.16 A/K (starting at -23°C) [8]	0.16 A/K (starting at -48°C) [8]
Reduction of continuous current depending on installation elevation		
Starting at 500 m above sea level	1.3 A_{eff} per 1000 m	1.7 A_{eff} per 1000 m
Peak current per motor connection	32.5 A_{eff}	42.5 A_{eff}
Peak power output	16.25 kW	21.25 kW
Nominal switching frequency	5 kHz	
Possible switching frequencies [9]	5 / 10 / 20 kHz	
Electrical stress of connected motor per IEC TS 60034-25	Limit value curve A	
Protective measures		
Overload protection	Yes	
Short circuit and ground fault protection	Yes	
Max. output frequency	598 Hz [10]	

Table 132: 8EI013HWSS0.XXXX-1, 8EI017HWSS0.XXXX-1 - Technical data

Model number	8EI013HWSS0.XXXX-1	8EI017HWSS0.XXXX-1
Variant		
U, V, W, PE	Connector	
Shield connection	Yes	
Terminal connection cross section		
Flexible and fine-stranded wires		
With wire end sleeves	1.5 to 6 mm²	
Approbation data		
UL/C-UL-US	24 to 8 AWG	
CSA	24 to 8 AWG	
Max. motor cable length depending on switching frequency		
Switching frequency 5 kHz	75 m	
Switching frequency 10 kHz	38 m	
Switching frequency 20 kHz	19 m	
Motor holding brake connection		
Quantity	1	
Output voltage [11]	Depends on the input voltage on connector X2	
Continuous current	4 A	
Max. internal resistance	100 mΩ	
Extinction potential	33 V	
Max. extinction energy per switching operation	15 Ws	
Max. switching frequency	0.5 Hz	
Protective measures		
Overload and short-circuit protection	Yes	
Open circuit monitoring	Yes	
Undervoltage monitoring	Yes	
Response threshold for open circuit monitoring	In preparation	
Response threshold for undervoltage monitoring	Approx. 23 V	
Max. breaking current SBC	80 mA	
Max. cable length	75 m [12]	
Braking resistor [13]		
Peak power int./ext.	14 kW / In preparation	
Continuous power int./ext.	150 W / 4 kW	
Minimum braking resistance (ext.)	25 Ω	
Terminal connection cross section		
Flexible and fine-stranded wires		
With wire end sleeves	0.25 to 4 mm²	
Approbation data		
UL/C-UL-US	24 to 8 AWG	
CSA	24 to 8 AWG	
Protective measures		
Overload protection	No	
Short circuit and ground fault protection	Short-circuit protection: Yes Ground fault protection: No	
Max. cable length	3 m	
Fieldbus		
Type	POWERLINK V2 controlled node (CN)	
Variant	2x RJ45, shielded, 2-port hub	
Cable length	Max. 100 m between 2 stations (segment length)	
Transfer rate	100 Mbit/s	
Encoder interfaces		
Quantity	1	
Type	Digital multi-encoder interface, configurable [14]	
Connections	8-pin female Mini I/O connector	
Status indicators	None [15]	
Electrical isolation		
Encoder - ACOPOS P3	No	
Max. encoder cable length	75 m Depends on the cross section of the power supply wires in the encoder cable [16]	
Encoder power supply		
Output voltage	Configurable Typ. 11.45 V ±0.1 V / 5.2 V ± 0.1 V [17][18]	
Load capacity	Max. 300 mA	
Sense lines	2, compensation of max. 2x 0.7 V	
Protective measures		
Short-circuit proof	Yes	
Overload-proof	Yes	
Synchronous serial interface		
Signal transmission	RS485 [19]	
Data transfer rate	Depends on the configured encoder type	
Differential voltage [20]		
Minimum	2.0 V	
Maximum	6.0 V	

Table 132: 8EI013HWSS0.XXXX-1, 8EI017HWSS0.XXXX-1 - Technical data

Model number	8EI013HWSS0.XXXX-1	8EI017HWSS0.XXXX-1
Max. power consumption per encoder interface	$P_{ENCODER}$ [W] = U_{24V} [V] * ($I_{ENCODER}$ [A] * 0.7) + 0.5 W [21]	
Trigger inputs		
Quantity	2	
Circuit	Sink	
Electrical isolation		
Input - ACOPOS P3	Yes	
Input - Input	Yes	
Input voltage		
Nominal	24 VDC	
Maximum	30 VDC	
Switching threshold		
Low	<5 V	
High	>15 V	
Input current at nominal voltage	7 mA	
Switching delay		
Rising edge	<51 µs	
Falling edge	<52 µs	
Modulation compared to ground potential	Max. ±38 V	
Terminal connection cross section		
Flexible and fine-stranded wires		
With wire end sleeves	0.25 to 2.5 mm²	
Approbation data		
UL/C-UL-US	26 to 12 AWG	
CSA	26 to 12 AWG	
Max. cable length	100 m	
Support		
Motion system		
mapp Motion	5.03.0 and higher	
ACP10/ARNC0	5.03.0 and higher	
Operating conditions		
Permissible mounting orientations		
Hanging vertically	Yes	
Standing horizontally	Yes	
Installation elevation above sea level		
Nominal	0 to 500 m	
Maximum	4000 m	
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)	
Overvoltage category per EN 61800-5-1	III	
Degree of protection per EN 60529	IP20 [22]	
Ambient conditions		
Temperature		
Operation		
Nominal	5 to 40°C	
Maximum	55°C	
Storage	-25 to 55°C	
Transport	-25 to 70°C	
Relative humidity		
Operation	5 to 85%, non-condensing	
Storage	5 to 95%	
Transport	95% at 40°C	
Mechanical properties		
Dimensions		
Width	66 mm	
Height	374 mm	
Depth		
Wall mounting	258.5 mm (with 8EXA front cover: 261 mm)	
Weight	4 kg	

Table 132: 8EI013HWSS0.XXXX-1, 8EI017HWSS0.XXXX-1 - Technical data

1) A line filter must be connected.
CE compliance can only be ensured by connecting a B&R line filter (8x0F...).
In extreme cases, using line filters from 3rd-party manufacturers can result in irreparable damage to the 8EI ACOPOS P3 servo drive.
2) Maximum line length between line filter and mains connection on the module.
3) Valid for a mains input voltage of ≥3x 400 VAC.
The sum of the continuous power values on all motor connections and the power of the DC bus connector is not permitted to exceed this value.
4) The value can be higher under certain conditions.
5) This value applies to unshielded wiring inside a control cabinet.
Maximum length of the DC bus wiring inside a control cabinet.
6) Current consumption depends on the configuration of the ACOPOS P3 8EI servo drive.
The inrush current of the 24 VDC power supply is not limited by the module.
7) Valid under the following conditions: 560 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
8) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.

9) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
10) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
11) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified input voltage and wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
12) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified line length. For the permissible operating voltage range of the holding brake, see the user documentation for the motor being used.
13) There is a connection for external braking resistors. An internal braking resistor is available as an option.
14) The encoder type is not predefined from the factory. The encoder type necessary in each case must be configured in Automation Studio.
15) The direction of rotation of the encoder can be displayed on the 8EAD0000.000-1 display module.
16) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 75 m is not permitted to exceeded):

    $l_{max} = f / I_G * A * 1/(2*\rho)$

    f ... (Output voltage of encoder interface [V] - Min. permissible supply voltage of connected encoder [V]) * 1.1
    I_G ... Max. current consumption of connected encoder [A]
    A ... Cross section of the power supply wires [mm²]
    ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
17) The output voltage is not predefined from the factory (with the exception of encoder types EnDat 2.2 and HIPERFACE DSL) . It must be configured in Automation Studio based on the encoder type. If no output voltage is configured, then the encoder will not be supplied by digital multi-encoder interface X4x. Power to the encoder can then be supplied externally.
18) Output voltage 5.2 V is only available under the following conditions:
    - 8EI servo drive with 8ZECxxx revision D0 and higher - see the device information on the left side cover of the 8EI servo drive
    - ACOPOS operating system 3.15.0 and higher (for 8EIxxxxxD... 2-axis modules and 8EIxxxxxT... 3-axis modules)
    - ACOPOS operating system 3.17.0 and higher (for 8EIxxxxxS... 1-axis modules)
19) Except encoder type HIPERFACE DSL.
20) Values valid for clock output and data input. Except encoder type HIPERFACE DSL.
21) $I_{ENCODER}$ ... Current consumption of the encoder
    U_{24V} ... Input voltage on the +24 VDC input of the module
22) The specified degree of protection is only met if either the slot cover is installed on the module or an 8EAC plug-in module is installed and suitable terminals are connected to all connectors and all fans are installed.

4.1.2.2.2.3 Continuous power 10 kW to 18 kW (motor connection)

Order data

Model number	Short description	Figure
	1-axis modules SafeMOTION	
8EI024HWSS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 24 A, SafeMOTION EnDat 2.2, 1 axis, wall mounting	
8EI034HWSS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 34 A, SafeMOTION EnDat 2.2, 1 axis, wall mounting	
8EI044HWSS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 44 A, SafeMOTION EnDat 2.2, 1 axis, wall mounting	
	Optional accessories	
	Display modules	
8EAD0000.000-1	Display module, LCD, 128 x 64, black/white, 1x USB 3.0	
	Front covers	
8EXA300.0010-00	ACOPOS P3 cover, B&R orange, double-width, height 2	
8EXA300.0020-00	ACOPOS P3 cover, B&R dark gray, double-width, height 2	
	Plug-in modules	
8EAC0122.001-1	ACOPOS P3 plug-in module, resolver interface 10 kHz	
8EAC0130.000-1	ACOPOS P3 plug-in module, 8 digital I/O 24 V (4x 400 mA, 4x 100 mA) individually configurable as inputs or outputs, 2 digital I/O 24 V 2 A configurable in pairs as inputs or outputs, order terminal block 8TB0230.221A-00 separately!	
8EAC0150.001-1	ACOPOS P3 plug-in module, digital multi-encoder interface	
8EAC0151.001-1	ACOPOS P3 plug-in module, incremental encoder interface	
8EAC0152.001-1	ACOPOS P3 plug-in module, analog multi-encoder interface	
	Shield component sets	
8SCSE01.0200-00	ACOPOS P3 shield component set: 1x ACOPOS P3 shield mounting plate, 2x 2x M3x6 screws	
8SCSE02.0100-00	ACOPOS P3 shield component set: 1x shield component set, type SK14	
8SCSE02.0200-00	ACOPOS P3 shield component set: 1x shield component set, type SK20	
	Terminals	
8TB2104.2210-00	Push-in terminal block 4-pin, 1-row, pitch: 5.08 mm, label 1: numbered consecutively	
8TB2104.223L-00	Push-in terminal block, 4-pin, 1-row, spacing: 5.08 mm, label 3: T- T+ B- B+, L keying: 1010	
8TB3102.222C-20	Push-in terminal block, 2-pin, single row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3202.222C-40	Push-in terminal block, 2-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB4103.222A-10	Push-in terminal block, 3-pin, 1-row, spacing: 10.16 mm, label 2: PE RB- RB+, A keying: 000	
8TB4104.222L-10	Push-in terminal block, 4-pin, 1-row, spacing: 10.16 mm, label 2: PE L3 L2 L1, L keying: 1010	
8TB4104.224G-10	Push-in terminal block, 4-pin, 1-row, spacing: 10.16 mm, label 4: PE W V U, G keying: 0110	
8TB4104.227F-10	Push-in terminal block, 4-pin, 1-row, spacing: 10.16 mm, label 4: DC-, DC-, DC+, DC+ F keying: 0101	
8TB4204.202L-10	4-pin push-in screw terminal block, 2-row, pitch: 10.16 mm, label 2: PE L3 L2 L1, coding L: 1010	

Table 133: 8EI024HWSS0.XXXX-1, 8EI034HWSS0.XXXX-1, 8EI044HWSS0.XXXX-1 - Order data

Connection	1-row connector	2-row connector
X1	8TB4104.222L-10	8TB4204.202L-10
X2	8TB3102.222C-20	8TB3202.222C-40
X51A	8TB4104.224G-10	
X51B	8TB2104.223L-00	
X6	8TB4103.222A-10	
X7	8TB2104.2210-50	8TB2204.2210-50
X8	8TB2104.2210-00	
X11	8TB4104.227F-10	

Table 134: Terminal blocks - Model numbers

Information:

Connector X7 does not exist on ACOPOS P3 SafeMOTION servo drives.

Technical data

Model number	8EI024HWSS0.XXXX-1	8EI034HWSS0.XXXX-1	8EI044HWSS0.XXXX-1
General information			
Slots for plug-in modules	1		
Certifications			
CE	Yes		
UL	cULus E225616 Power conversion equipment		
EAC	Yes		
KC	In preparation		
Mains connection			
Network configurations	TN-S, TN-C-S with grounded neutral		
Mains input voltage	3x 200 VAC to 480 VAC ±10%		
Frequency	50 / 60 Hz ±4%		
Installed load	Max. 18.7 kVA	Max. 26.4 kVA	Max. 30.5 kVA
Inrush current	Max. 100 A		
Switch-on interval	60 s		
Integrated line filter per EN 61800-3, category C3	No [1]		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	0.75 to 16 mm²		
Approbation data			
UL/C-UL-US	20 to 4 AWG		
CSA	20 to 4 AWG		
Power dissipation at device nominal power without braking resistor	In preparation		
Max. cable length	3 m [2]		
DC bus connection			
Continuous power [3]	10 kW [4]	14 kW [4]	18 kW
Reduction of continuous power depending on mains input voltage			
Mains input voltage <3x 400 VAC	10 kW * (Mains input voltage [V] / 400 V)	14 kW * (Mains input voltage [V] / 400 V)	18 kW * (Mains input voltage [V] / 400 V)
DC bus capacitance	1680 µF		
Terminal connection cross sections			
Flexible and fine-stranded wires			
With wire end sleeves	0.75 to 16 mm²		
Approbation data			
UL/C-UL-US	20 to 4 AWG		
CSA	20 to 4 AWG		
Max. cable length	3 m [5]		
24 VDC power supply			
Input voltage	24 VDC ±25%		
Input capacitance	5500 µF		
Current consumption	3 A + Current for motor holding brake [6]		
Terminal connection cross sections			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Max. cable length	30 m		
Motor connection			
Quantity	1		
Continuous power per motor connection [7]	10 kW	14 kW	18 kW
Continuous current per motor connection [7]	24 A_{eff}	34 A_{eff}	44 A_{eff}
Reduction of continuous current depending on switching frequency			
Switching frequency 5 kHz	1.6 A/K (starting at 52°C) [8]	1.6 A/K (starting at 46°C) [8]	1.6 A/K (starting at 40°C) [8]
Switching frequency 10 kHz	0.45 A/K (starting at 35°C) [8]	0.45 A/K (starting at 13°C) [8]	0.45 A/K (starting at -9°C) [8]
Switching frequency 20 kHz	0.233 A/K (starting at -26°C) [8]	0.233 A/K (starting at -68°C) [8]	0.233 A/K (starting at -110°C) [8]
Reduction of continuous current depending on installation elevation			
Starting at 500 m above sea level	2.4 A_{eff} per 1000 m	3.4 A_{eff} per 1000 m	4.4 A_{eff} per 1000 m
Peak current per motor connection	60 A_{eff}	85 A_{eff}	110 A_{eff}
Peak power output	25 kW	35 kW	45 kW
Nominal switching frequency	5 kHz		
Possible switching frequencies [9]	5 / 10 / 20 kHz		
Electrical stress of connected motor per IEC TS 60034-25	Limit value curve A		
Protective measures			
Overload protection	Yes		
Short circuit and ground fault protection	Yes		

Table 135: 8EI024HWSS0.XXXX-1, 8EI034HWSS0.XXXX-1, 8EI044HWSS0.XXXX-1 - Technical data

Model number	8EI024HWSS0.XXXX-1	8EI034HWSS0.XXXX-1	8EI044HWSS0.XXXX-1
Max. output frequency	598 Hz [10)		
Variant			
U, V, W, PE	Connector		
Shield connection	Yes		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	1.5 to 16 mm²		
Approbation data			
UL/C-UL-US	In preparation		
CSA	In preparation		
Max. motor cable length depending on switching frequency			
Switching frequency 5 kHz	75 m		
Switching frequency 10 kHz	35 m		
Switching frequency 20 kHz	20 m		
Motor holding brake connection			
Quantity	1		
Output voltage [11)	Depends on the input voltage on connector X2		
Continuous current	6.5 A		
Max. internal resistance	0.25 Ω		
Extinction potential	30 V		
Max. extinction energy per switching operation	In preparation		
Max. switching frequency	0.5 Hz		
Protective measures			
Overload and short-circuit protection	Yes		
Open circuit monitoring	Yes		
Undervoltage monitoring	Yes		
Response threshold for open circuit monitoring	In preparation		
Response threshold for undervoltage monitoring	Approx. 23 V		
Max. breaking current SBC	200 mA		
Max. cable length	75 m [12)		
Braking resistor [13)			
Peak power output	45 kW		
Continuous power	4 kW		
Minimum braking resistance (ext.)	16 Ω		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	0.75 to 16 mm²		
Approbation data			
UL/C-UL-US	20 to 4 AWG		
CSA	20 to 4 AWG		
Protective measures			
Overload protection	No		
Short circuit and ground fault protection	Short-circuit protection: Yes Ground fault protection: No		
Max. cable length	3 m		
Fieldbus			
Type	POWERLINK V2 controlled node (CN)		
Variant	2x RJ45, shielded, 2-port hub		
Cable length	Max. 100 m between 2 stations (segment length)		
Transfer rate	100 Mbit/s		
Encoder interfaces			
Quantity	1		
Type	Digital multi-encoder interface, configurable [14)		
Connections	8-pin female Mini I/O connector		
Status indicators	None [15)		
Electrical isolation			
Encoder - ACOPOS P3	No		
Max. encoder cable length	75 m Depends on the cross section of the power supply wires in the encoder cable [16)		
Encoder power supply			
Output voltage	Configurable Typ. 11.45 V ±0.1 V / 5.2 V ± 0.1 V [17)18)		
Load capacity	Max. 300 mA		
Sense lines	2, compensation of max. 2x 0.7 V		
Protective measures			
Short-circuit proof	Yes		
Overload-proof	Yes		

Table 135: 8EI024HWSS0.XXXX-1, 8EI034HWSS0.XXXX-1, 8EI044HWSS0.XXXX-1 - Technical data

Model number	8EI024HWSS0.XXXX-1	8EI034HWSS0.XXXX-1	8EI044HWSS0.XXXX-1
Synchronous serial interface			
Signal transmission	RS485 [19]		
Data transfer rate	Depends on the configured encoder type		
Differential voltage [20]			
Minimum	2.0 V		
Maximum	6.0 V		
Max. power consumption per encoder interface	$P_{ENCODER}$ [W] = U_{24V} [V] * ($I_{ENCODER}$ [A] * 0.7) + 0.5 W [21]		
Trigger inputs			
Quantity	2		
Circuit	Sink		
Electrical isolation			
Input - ACOPOS P3	Yes		
Input - Input	Yes		
Input voltage			
Nominal	24 VDC		
Maximum	30 VDC		
Switching threshold			
Low	<5 V		
High	>15 V		
Input current at nominal voltage	7 mA		
Switching delay			
Rising edge	<51 µs		
Falling edge	<52 µs		
Modulation compared to ground potential	Max. ±38 V		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 2.5 mm²		
Approbation data			
UL/C-UL-US	26 to 12 AWG		
CSA	26 to 12 AWG		
Max. cable length	100 m		
Support			
Motion system			
mapp Motion	5.03.0 and higher		
ACP10/ARNC0	5.03.0 and higher		
Operating conditions			
Permissible mounting orientations			
Hanging vertically	Yes		
Standing horizontally	Yes		
Installation elevation above sea level			
Nominal	0 to 500 m		
Maximum	4000 m		
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)		
Overvoltage category per EN 61800-5-1	III		
Degree of protection per EN 60529	IP20 [22]		
Ambient conditions			
Temperature			
Operation			
Nominal	5 to 40°C		
Maximum	55°C		
Storage	-25 to 55°C		
Transport	-25 to 70°C		
Relative humidity			
Operation	5 to 85%, non-condensing		
Storage	5 to 95%		
Transport	95% at 40°C		
Mechanical properties			
Dimensions			
Width	133 mm		
Height	374 mm		
Depth			
Wall mounting	258.5 mm (with 8EXA front cover: 261 mm)		
Weight	8 kg		

Table 135: 8EI024HWSS0.XXXX-1, 8EI034HWSS0.XXXX-1, 8EI044HWSS0.XXXX-1 - Technical data

1) A line filter must be connected.
CE compliance can only be ensured by connecting a B&R line filter (8x0F...).
In extreme cases, using line filters from 3rd-party manufacturers can result in irreparable damage to the 8EI ACOPOS P3 servo drive.
2) Maximum line length between line filter and mains connection on the module.
3) Valid for a mains input voltage of ≥3x 400 VAC.
The sum of the continuous power values on all motor connections and the power of the DC bus connector is not permitted to exceed this value.
4) The value can be higher under certain conditions.
5) This value applies to unshielded wiring inside a control cabinet.
Maximum length of the DC bus wiring inside a control cabinet.

6) Current consumption depends on the configuration of the ACOPOS P3 8EI servo drive.
The inrush current of the 24 VDC power supply is not limited by the module.
7) Valid under the following conditions: 560 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
8) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
9) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
10) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
11) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified input voltage and wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
12) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified line length. For the permissible operating voltage range of the holding brake, see the user documentation for the motor being used.
13) This values apply to an external braking resistor. This module is not equipped with an internal braking resistor.
14) The encoder type is not predefined from the factory. The encoder type necessary in each case must be configured in Automation Studio.
15) The direction of rotation of the encoder can be displayed on the 8EAD0000.000-1 display module.
16) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 75 m is not permitted to exceeded):

l_{max} = f / I_G * A * 1/(2*ρ)

f ... (Output voltage of encoder interface [V] - Min. permissible supply voltage of connected encoder [V]) * 1.1
I_G ... Max. current consumption of connected encoder [A]
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
17) The output voltage is not predefined from the factory (with the exception of encoder types EnDat 2.2 and HIPERFACE DSL) . It must be configured in Automation Studio based on the encoder type. If no output voltage is configured, then the encoder will not be supplied by digital multi-encoder interface X4x. Power to the encoder can then be supplied externally.
18) Output voltage 5.2 V is only available under the following conditions:
- 8EI servo drive with 8ZECxxx revision D0 and higher - see the device information on the left side cover of the 8EI servo drive
- ACOPOS operating system 3.15.0 and higher (for 8EIxxxxxD... 2-axis modules and 8EIxxxxxT... 3-axis modules)
- ACOPOS operating system 3.17.0 and higher (for 8EIxxxxxS... 1-axis modules)
19) Except encoder type HIPERFACE DSL.
20) Values valid for clock output and data input. Except encoder type HIPERFACE DSL.
21) $I_{ENCODER}$ ... Current consumption of the encoder
U_{24V} ... Input voltage on the +24 VDC input of the module
22) The specified degree of protection is only met if either the slot cover is installed on the module or an 8EAC plug-in module is installed and suitable terminals are connected to all connectors and all fans are installed.

4.1.2.3 2-axis modules

4.1.2.3.1 Mains input voltage - 1x 110 to 230 VAC / 3x 200 to 230 VAC

4.1.2.3.1.1 Continuous power up to 2 kW (motor connection)

Order data

Model number	Short description	Figure
	2-axis modules SafeMOTION	
8EI2X2MWDS0.XXXX-1	ACOPOS P3 servo drive, 1x 110-230 VAC, 3x 200-230 VAC, 2x 2.2 A, SafeMOTION EnDat 2.2, 2 axes, wall mounting	
8EI4X5MWDS0.XXXX-1	ACOPOS P3 servo drive, 1x 110-230 VAC, 3x 200-230 VAC, 2x 4.5 A, SafeMOTION EnDat 2.2, 2 axes, wall mounting	
8EI8X8MWDS0.XXXX-1	ACOPOS P3 servo drive, 1x 110-230 VAC, 3x 200-230 VAC, 2x 8.8 A, SafeMOTION EnDat 2.2, 2 axes, wall mounting	
	Optional accessories	
	Display modules	
8EAD0000.000-1	Display module, LCD, 128 x 64, black/white, 1x USB 3.0	
	Front covers	
8EXA200.0010-00	ACOPOS P3 cover, B&R orange, single-width, height 2	
8EXA200.0020-00	ACOPOS P3 cover, B&R dark gray, single-width, height 2	
	Plug-in modules	
8EAC0122.001-1	ACOPOS P3 plug-in module, resolver interface 10 kHz	
8EAC0122.003-1	ACOPOS P3 plug-in module, 3 resolver interfaces 10 kHz	
8EAC0130.000-1	ACOPOS P3 plug-in module, 8 digital I/O 24 V (4x 400 mA, 4x 100 mA) individually configurable as inputs or outputs, 2 digital I/O 24 V 2 A configurable in pairs as inputs or outputs, order terminal block 8TB0230.221A-00 separately!	
8EAC0150.001-1	ACOPOS P3 plug-in module, digital multi-encoder interface	
8EAC0150.003-1	ACOPOS P3 plug-in module, 3 digital multi-encoder interfaces	
8EAC0151.001-1	ACOPOS P3 plug-in module, incremental encoder interface	
8EAC0151.003-1	ACOPOS P3 plug-in module, 3 incremental encoder interfaces	
8EAC0152.001-1	ACOPOS P3 plug-in module, analog multi-encoder interface	
8EAC0152.003-1	ACOPOS P3 plug-in module, 3 analog multi-encoder interfaces	
	Shield component sets	
8SCSE01.0100-00	ACOPOS P3 shield component set: 1x ACOPOS P3 shield mounting plate, 1x 2x M3x6 screws	
8SCSE02.0100-00	ACOPOS P3 shield component set: 1x shield component set, type SK14	
8SCSE02.0200-00	ACOPOS P3 shield component set: 1x shield component set, type SK20	
	Terminals	
8TB2104.2210-00	Push-in terminal block 4-pin, 1-row, pitch: 5.08 mm, label 1: numbered consecutively	
8TB3102.222C-20	Push-in terminal block, 2-pin, single row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3103.222A-20	Push-in terminal block, 3-pin, 1-row, spacing: 7.62 mm, label 2: PE RB- RB+, A keying: 000	
8TB3106.223C-20	Push-in terminal block, 6-pin, 1-row, with locking mechanism, spacing: 7.62 mm, label 3: PE L3 N(L2) L1 DC- DC+, C keying: 000010	
8TB3202.222C-40	Push-in terminal block, 2-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3206.223C-40	Push-in terminal block, 6-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 3: PE L3 N(L2) L1 DC- DC+, C keying: 000010	
8TB3308.222A-00	Push-in terminal block 4+4-pin 1-row/2-row, spacing: 7.62 mm, label 2: T- B- T+ B+ PE W V U A keying: 0000	

Table 136: 8EI2X2MWDS0.XXXX-1, 8EI4X5MWDS0.XXXX-1, 8EI8X8MWDS0.XXXX-1 - Order data

Connection	1-row connector	2-row connector
X1	8TB3106.223C-20	8TB3206.223C-40
X2	8TB3102.222C-20	8TB3202.222C-40
X5x	8TB3308.222A-00	
X6	8TB3103.222A-20	
X7	8TB2104.2210-50	8TB2204.2210-50
X8	8TB2104.2210-00	

Table 137: Terminal blocks - Model numbers

Information:

Connector X7 does not exist on ACOPOS P3 SafeMOTION servo drives.

Technical data

Model number	8EI2X2MWDS0.XXXX-1	8EI4X5MWDS0.XXXX-1	8EI8X8MWDS0.XXXX-1
General information			
Slots for plug-in modules	1		
Certifications			
CE	Yes		
UL	cULus E225616 Power conversion equipment		
EAC	Yes		
KC	Yes		
Mains connection			
Network configurations	TN-S, TN-C-S with grounded neutral		
Mains input voltage	1x 110 VAC to 230 VAC ±10% 3x 200 VAC to 230 VAC ±10%		
Frequency	50/60 Hz ±4%		
Installed load	Max. 2.5 kVA	Max. 5 kVA	
Inrush current	Max. 22 A		
Switch-on interval	Typ. 60 s		
Integrated line filter per EN 61800-3, category C3	No [1]		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Power dissipation at device nominal power without braking resistor	$[(35 + 10 * P_{AVG}$ [kW] + 5.8 * (I_{AX1} [A] + I_{AX2} [A]) + 0.25 * (I_{BR1}^2 [A] + I_{BR2}^2 [A]) + P_{VSLOT}) * 1.1] [W] [2]	$[(35 + 10 * P_{AVG}$ [kW] + 5.8 * (I_{AX1} [A] + I_{AX2} [A]) + 0.25 * (I_{BR1}^2 [A] + I_{BR2}^2 [A]) + P_{VSLOT}) * 1.1] [W] [3]	
Max. cable length	3 m [4]		
DC bus connection			
Continuous power [5]	1 kW [6]	2 kW [6]	
Reduction of continuous power depending on mains input voltage			
Mains input voltage <230 VAC	1 kW * (Mains input voltage [V] / 230 V)	2 kW * (Mains input voltage [V] / 230 V)	
DC bus capacitance	1880 µF		
Terminal connection cross sections			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Max. cable length	3 m [7]		
24 VDC power supply			
Input voltage	24 VDC ±25%		
Input capacitance	5500 µF		
Current consumption	1.2 A + Current for motor holding brake [8]		
Terminal connection cross sections			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Max. cable length	30 m		
Motor connection			
Quantity	2		
Continuous power per motor connection [9]	0.5 / 0.5 kW [10]	1 / 1 kW [11]	2 / 2 kW [11]
Continuous current per motor connection [9]	2.2 / 2.2 A_{eff}	4.5 / 4.5 A_{eff}	8.8 / 8.8 A_{eff}
Accuracy of the safe current [12]			
Safety function SLT			
SIL 2 / PL d / Cat. 3	Hardware upgrade 1.10.2.x: 1.545 A Hardware upgrade 1.10.3.0 or later: 1.244 A [13]	Hardware upgrade 1.10.2.x: 1.714 A Hardware upgrade 1.10.3.0 or later: 1.421 A [13]	Hardware upgrade 1.10.2.x: 2.035 A Hardware upgrade 1.10.3.0 or later: 1.754 A [13]
Safety function SBT			
SIL 2 / PL d / Cat. 3	Hardware upgrade 1.10.2.x: 1.441 A Hardware upgrade 1.10.3.0 or later: 1.136 A [13]	Hardware upgrade 1.10.2.x: 1.501 A Hardware upgrade 1.10.3.0 or later: 1.199 A [13]	Hardware upgrade 1.10.2.x: 1.613 A Hardware upgrade 1.10.3.0 or later: 1.317 A [13]
Reduction of continuous current depending on switching frequency [14]			
Switching frequency 5 kHz	No reduction		
Switching frequency 10 kHz	No reduction		
Switching frequency 20 kHz	No reduction	0.144 A/K (starting at 53.6°C) [15]	0.144 A/K (starting at 23.7°C) [15]

Table 138: 8EI2X2MWDS0.XXXX-1, 8EI4X5MWDS0.XXXX-1, 8EI8X8MWDS0.XXXX-1 - Technical data

Model number	8EI2X2MWDS0.XXXX-1	8EI4X5MWDS0.XXXX-1	8EI8X8MWDS0.XXXX-1
Reduction of continuous current depending on installation elevation			
Starting at 500 m above sea level	0.22 A_{eff} per 1000 m	0.45 A_{eff} per 1000 m	0.88 A_{eff} per 1000 m
Peak current per motor connection	6 / 6 A_{eff}	12.25 / 12.25 A_{eff}	24 / 24 A_{eff}
Peak power output	1.25 kW	2.5 kW	5 kW [16]
Nominal switching frequency	5 kHz		
Possible switching frequencies [17]	5 / 10 / 20 kHz [18]		
Electrical stress of connected motor per IEC TS 60034-25	Limit value curve A		
Protective measures			
Overload protection	Yes		
Short circuit and ground fault protection	Yes		
Max. output frequency	598 Hz [19]	598 Hz [20]	
Variant			
U, V, W, PE	Male connector		
Shield connection	Yes		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	1.5 to 6 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Max. motor cable length depending on switching frequency			
Switching frequency 5 kHz	75 m [21]		
Switching frequency 10 kHz	38 m [21]		
Switching frequency 20 kHz	19 m [21]		
Motor holding brake connection			
Quantity	2		
Output voltage [22]	Depends on the input voltage on connector X2		
Continuous current	1.3 A		
Max. internal resistance	0.25 Ω		
Extinction potential	Approx. 30 V		
Max. extinction energy per switching operation	1.5 Ws		
Max. switching frequency	0.5 Hz		
Protective measures			
Overload and short-circuit protection	Yes		
Open circuit monitoring	Yes		
Undervoltage monitoring	Yes		
Response threshold for open circuit monitoring	Approx. 30 mA		
Response threshold for undervoltage monitoring	Approx. 23 V		
Max. cable length	75 m [23]		
Braking resistor [24]			
Peak power int./ext.	1.5 kW / 11 kW		
Continuous power int./ext.	150 W / 970 W		
Minimum braking resistance (ext.)	12 Ω		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Protective measures			
Overload protection	No		
Short circuit and ground fault protection	Short circuit protection: Yes Ground fault protection: No		
Max. cable length	3 m		
Fieldbus			
Type	POWERLINK V2 controlled node (CN)		
Variant	2x RJ45, shielded, 2-port hub		
Cable length	Max. 100 m between 2 stations (segment length)		
Transfer rate	100 Mbit/s		
Encoder interfaces			
Quantity	2		
Type	Digital multi-encoder interface, configurable [25]		
Connections	8-pin female mini I/O connector		
Status indicators	None [26]		
Electrical isolation			
Encoder - ACOPOS P3	No		
Max. encoder cable length	75 m Depends on the cross section of the power supply wires of the encoder cable [27]		

Table 138: 8EI2X2MWDS0.XXXX-1, 8EI4X5MWDS0.XXXX-1, 8EI8X8MWDS0.XXXX-1 - Technical data

Model number	8EI2X2MWDS0.XXXX-1	8EI4X5MWDS0.XXXX-1	8EI8X8MWDS0.XXXX-1
Encoder power supply			
Output voltage	Configurable Typ. 11.45 V ± 0.1 V / 5.2 V ± 0.1 V [28][29]		
Load capacity	Max. 300 mA		
Sense lines	2, compensation of max. 2x 0.7 V		
Protective measures			
Short-circuit proof	Yes		
Overload-proof	Yes		
Synchronous serial interface			
Signal transmission	RS485 [30]		
Data transfer rate	Depends on the configured encoder type		
Differential voltage [31]			
Minimum	2.0 V		
Maximum	6.0 V		
Max. power consumption per encoder interface	$P_{ENCODER}$ [W] = U_{24V} [V] * ($I_{ENCODER}$ [A] * 0.7) + 0.5 W [32]		
Trigger inputs			
Quantity	2		
Circuit	Sink		
Electrical isolation			
Input - ACOPOS P3	Yes		
Input - Input	Yes		
Input voltage			
Nominal	24 VDC		
Maximum	30 VDC		
Switching threshold			
Low	<5 V		
High	>15 V		
Input current at nominal voltage	7 mA		
Switching delay			
Rising edge	<51 µs		
Falling edge	<52 µs		
Modulation compared to ground potential	Max. ±38 V		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 2.5 mm²		
Approbation data			
UL/C-UL-US	26 to 12 AWG		
CSA	26 to 12 AWG		
Max. cable length	100 m		
Support			
Motion system			
mapp Motion	5.00.0 and higher		
ACP10/ARNC0	3.14.1 and higher		
Operating conditions			
Permissible mounting orientations			
Hanging vertically	Yes		
Standing horizontally	Yes		
Installation elevation above sea level			
Nominal	0 to 500 m		
Maximum	4000 m		
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)		
Overvoltage category per EN 61800-5-1	III		
Degree of protection per EN 60529	IP20 [33]		
Ambient conditions			
Temperature			
Operation			
Nominal	5 to 40°C		
Maximum	55°C		
Storage	-25 to 55°C		
Transport	-25 to 70°C		
Relative humidity			
Operation	5 to 85%, non-condensing		
Storage	5 to 95%		
Transport	95% at 40°C		

Table 138: 8EI2X2MWDS0.XXXX-1, 8EI4X5MWDS0.XXXX-1, 8EI8X8MWDS0.XXXX-1 - Technical data

Model number	8EI2X2MWDS0.XXXX-1	8EI4X5MWDS0.XXXX-1	8EI8X8MWDS0.XXXX-1
Mechanical properties			
Dimensions			
Width	66 mm		
Height	374 mm		
Depth			
Wall mounting	258.5 mm (with 8EXA front cover: 261 mm)		
Weight	4 kg		

Table 138: 8EI2X2MWDS0.XXXX-1, 8EI4X5MWDS0.XXXX-1, 8EI8X8MWDS0.XXXX-1 - Technical data

1) A line filter must be connected.
CE compliance can only be ensured by connecting a B&R line filter (8x0F...).
In extreme cases, using line filters from 3rd-party manufacturers can result in irreparable damage to the 8EI ACOPOS P3 servo drive.
2) P_{AVG} ... Average continuous power of the module
I_{AX1}, I_{AX2} ... RMS value of the current on axis 1 and axis 2
I_{BR1}, I_{BR2} ... Nominal current of the motor holding brake on axis 1 and axis 2
P_{VSLOT} ... Power dissipation of the 8EAC plug-in module
3) P_{AVG} ... Average continuous power of the module
I_{AX1}, I_{AX2} ... RMS value of the current on axis 1, axis 2
I_{BR1}, I_{BR2} ... Nominal current of the motor holding brake on axis 1, axis 2
P_{VSLOT} ... Power dissipation of the 8EAC plug-in module
4) Maximum cable length between line filter and mains connection on the module.
5) Valid for a mains input voltage of 230 VAC.
The sum of the continuous power values on all motor connections and the power of the DC bus connector is not permitted to exceed this value.
6) The continuous power is reduced as a percentage of the continuous current if the continuous current is subject to derating.
7) This value applies to unshielded wiring inside a control cabinet.
Maximum length of the DC bus wiring inside a control cabinet.
8) Current consumption depends on the configuration of the ACOPOS P3 8EI servo drive.
The inrush current of the 24 VDC power supply is not limited by the module.
9) Valid under the following conditions: 325 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
10) The total continuous power of all motor connections is not permitted to exceed 1 kW. The continuous power is reduced as a percentage of the continuous current if the continuous current is subject to derating.
11) The total continuous power of all motor connections is not permitted to exceed 2 kW. The continuous power is reduced as a percentage of the continuous current if the continuous current is subject to derating.
12) The accuracy of the safe current is relevant for safety functions SLT and SBT, which are based on the safe current measurement. Safety functions SBT, SLT and SSO are available starting with hardware upgrade 1.10.2.0 and only for 8EI servo drives with 8ZELxxxx revision D0 or later. See the device information on the left side cover of the servo drive.
13) These values apply up to the continuous current specified in the technical data (taking into account the respective derating specifications).
14) The temperature specifications refer to the ambient temperature.
15) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
16) The total peak power of all motor connections is not permitted to exceed 5 kW.
17) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
18) A switching frequency of 20 kHz is not recommended when using safety function SLT, SBT or SSO since availability problems may occur.
19) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
20) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use per Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
21) The sum of the length of all motor cables connected to this module is not permitted to exceed this value.
22) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified input voltage and wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
23) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified cable length. For the permissible operating voltage range of the holding brake, see the user documentation for the motor being used.
24) There is a connection for external braking resistors. An internal braking resistor is available as an option.
25) The encoder type is not predefined from the factory. The encoder type necessary in each case must be configured in Automation Studio.
26) The direction of rotation of the encoder can be displayed on the 8EAD0000.000-1 display module.
27) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 75 m is not permitted to exceeded):

$l_{max} = f / I_G * A * 1/(2*\rho)$

f ... (Output voltage of encoder interface [V] - Min. permissible supply voltage of connected encoder [V]) * 1.1
I_G ... Max. current consumption of connected encoder [A]
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
28) The output voltage is not predefined from the factory (with the exception of encoder types EnDat 2.2 and HIPERFACE DSL). It must be configured in Automation Studio based on the encoder type. If no output voltage is configured, then the encoder will not be supplied by digital multi-encoder interface X4x. Power to the encoder can then be supplied externally.
29) Output voltage 5.2 V is only available under the following conditions:
- 8EI servo drive with 8ZECxxx revision D0 and higher - see the device information on the left side cover of the 8EI servo drive
- ACOPOS operating system 3.15.0 and higher (for 8EIxxxxxD... 2-axis modules and 8EIxxxxxT... 3-axis modules)
- ACOPOS operating system 3.17.0 and higher (for 8EIxxxxxS... 1-axis modules)
30) Except encoder type HIPERFACE DSL.
31) Values valid for clock output and data input. Except encoder type HIPERFACE DSL.

32) $I_{ENCODER}$ ... Current consumption of the encoder
U_{24V} ... Input voltage on the +24 VDC input of the module

33) The specified degree of protection is only met if either the slot cover is installed on the module or an 8EAC plug-in module is installed and suitable terminals are connected to all connectors and all fans are installed.

4.1.2.3.2 Mains input voltage - 3x 200 to 480 VAC

4.1.2.3.2.1 Continuous power up to 4 kW (motor connection)

Order data

Model number	Short description	Figure
	2-axis modules SafeMOTION	
8EI2X2HWDS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 2x 2.2 A, SafeMOTION EnDat 2.2, 2 axes, wall mounting	
8EI4X5HWDS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 2x 4.5 A, SafeMOTION EnDat 2.2, 2 axes, wall mounting	
8EI8X8HWDS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 2x 8.8 A, SafeMOTION EnDat 2.2, 2 axes, wall mounting	
	Optional accessories	
	Display modules	
8EAD0000.000-1	Display module, LCD, 128 x 64, black/white, 1x USB 3.0	
	Front covers	
8EXA200.0010-00	ACOPOS P3 cover, B&R orange, single-width, height 2	
8EXA200.0020-00	ACOPOS P3 cover, B&R dark gray, single-width, height 2	
	Plug-in modules	
8EAC0122.001-1	ACOPOS P3 plug-in module, resolver interface 10 kHz	
8EAC0122.003-1	ACOPOS P3 plug-in module, 3 resolver interfaces 10 kHz	
8EAC0130.000-1	ACOPOS P3 plug-in module, 8 digital I/O 24 V (4x 400 mA, 4x 100 mA) individually configurable as inputs or outputs, 2 digital I/O 24 V 2 A configurable in pairs as inputs or outputs, order terminal block 8TB0230.221A-00 separately!	
8EAC0150.001-1	ACOPOS P3 plug-in module, digital multi-encoder interface	
8EAC0150.003-1	ACOPOS P3 plug-in module, 3 digital multi-encoder interfaces	
8EAC0151.001-1	ACOPOS P3 plug-in module, incremental encoder interface	
8EAC0151.003-1	ACOPOS P3 plug-in module, 3 incremental encoder interfaces	
8EAC0152.001-1	ACOPOS P3 plug-in module, analog multi-encoder interface	
8EAC0152.003-1	ACOPOS P3 plug-in module, 3 analog multi-encoder interfaces	
	Shield component sets	
8SCSE01.0100-00	ACOPOS P3 shield component set: 1x ACOPOS P3 shield mounting plate, 1x 2x M3x6 screws	
8SCSE02.0100-00	ACOPOS P3 shield component set: 1x shield component set, type SK14	
8SCSE02.0200-00	ACOPOS P3 shield component set: 1x shield component set, type SK20	
	Terminals	
8TB2104.2210-00	Push-in terminal block 4-pin, 1-row, pitch: 5.08 mm, label 1: numbered consecutively	
8TB3102.222C-20	Push-in terminal block, 2-pin, single row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3103.222A-20	Push-in terminal block, 3-pin, 1-row, spacing: 7.62 mm, label 2: PE RB- RB+, A keying: 000	
8TB3106.222B-20	Push-in terminal block, 6-pin, single row, with locking mechanism, spacing: 7.62 mm, label 2: PE L3 L2 L1 DC- DC+, B keying: 000001	
8TB3202.222C-40	Push-in terminal block, 2-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3206.222B-40	Push-in terminal block, 6-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 2: PE L3 L2 L1 DC- DC+, C keying: 000001	
8TB3308.222A-00	Push-in terminal block 4+4-pin 1-row/2-row, spacing: 7.62 mm, label 2: T- B- T+ B+ PE W V U A keying: 0000	

Table 139: 8EI2X2HWDS0.XXXX-1, 8EI4X5HWDS0.XXXX-1, 8EI8X8HWDS0.XXXX-1 - Order data

Connection	1-row connector	2-row connector
X1	8TB3106.222B-20	8TB3206.222B-40
X2	8TB3102.222C-20	8TB3202.222C-40
X5x	8TB3308.222A-00	
X6	8TB3103.222A-20	
X7	8TB2104.2210-50	8TB2204.2210-50
X8	8TB2104.2210-00	

Table 140: Terminal blocks - Model numbers

Information:

Connector X7 does not exist on ACOPOS P3 SafeMOTION servo drives.

Technical data

Model number	8EI2X2HWDS0.XXXX-1	8EI4X5HWDS0.XXXX-1	8EI8X8HWDS0.XXXX-1
General information			
Slots for plug-in modules	1		
Certifications			
CE	Yes		
UL	cULus E225616 Power conversion equipment		
EAC	Yes		
KC	Yes		
Mains connection			
Network configurations	TN-S, TN-C-S with grounded neutral		
Mains input voltage	3x 200 VAC to 480 VAC ±10%		
Frequency	50/60 Hz ±4%		
Installed load	Max. 5 kVA	Max. 10 kVA	
Inrush current	Max. 45 A		
Switch-on interval	Typ. 60 s		
Integrated line filter per EN 61800-3, category C3	No [1]		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Power dissipation at device nominal power without braking resistor	[(50 + 6.9 * P_{AVG} [kW] + 7.5 * (I_{AX1} [A] + I_{AX2} [A]) + 0.25 * (I_{BR1}^2 [A] + I_{BR2}^2 [A]) + P_{VSLOT}) * 1.1] [W] [2]	[(50 + 6.9 * P_{AVG} [kW] + 7.5 * (I_{AX1} [A] + I_{AX2} [A]) + 0.25 * (I_{BR1}^2 [A] + I_{BR2}^2 [A]) + P_{VSLOT}) * 1.1] [W] [3]	
Max. cable length	3 m [4]		
DC bus connection			
Continuous power [5]	2 kW [6]	4 kW [6]	
Reduction of continuous power depending on mains input voltage			
Mains input voltage <3x 400 VAC	2 kW * (Mains input voltage [V] / 400 V)	4 kW * (Mains input voltage [V] / 400 V)	
DC bus capacitance	470 µF		
Terminal connection cross sections			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Max. cable length	3 m [7]		
24 VDC power supply			
Input voltage	24 VDC ±25%		
Input capacitance	5500 µF		
Current consumption	1.2 A + Current for motor holding brake [8]		
Terminal connection cross sections			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Max. cable length	30 m		
Motor connection			
Quantity	2		
Continuous power per motor connection [9]	1 / 1 kW [10]	2 / 2 kW [11]	4 / 4 kW [11]
Continuous current per motor connection [9]	2.2 / 2.2 A_{eff}	4.5 / 4.5 A_{eff}	8.8 / 8.8 A_{eff}
Accuracy of the safe current [12]			
Safety function SLT			
SIL 2 / PL d / Cat. 3	Hardware upgrade 1.10.2.x: 1.545 A Hardware upgrade 1.10.3.0 or later: 1.244 A [13]	Hardware upgrade 1.10.2.x: 1.714 A Hardware upgrade 1.10.3.0 or later: 1.421 A [13]	Hardware upgrade 1.10.2.x: 2.035 A Hardware upgrade 1.10.3.0 or later: 1.754 A [13]
Safety function SBT			
SIL 2 / PL d / Cat. 3	Hardware upgrade 1.10.2.x: 1.441 A Hardware upgrade 1.10.3.0 or later: 1.136 A [13]	Hardware upgrade 1.10.2.x: 1.501 A Hardware upgrade 1.10.3.0 or later: 1.199 A [13]	Hardware upgrade 1.10.2.x: 1.613 A Hardware upgrade 1.10.3.0 or later: 1.317 A [13]
Reduction of continuous current depending on switching frequency [14]			
Switching frequency 5 kHz	No reduction		1.571 A/K (starting at 53.1°C) [15]
Switching frequency 10 kHz	No reduction		0.108 A/K (starting at 29.5°C)
Switching frequency 20 kHz	No reduction	0.091 A/K (starting at 29.4°C) [16]	0.091 A/K (starting at -17.9°C) [16]

Table 141: 8EI2X2HWDS0.XXXX-1, 8EI4X5HWDS0.XXXX-1, 8EI8X8HWDS0.XXXX-1 - Technical data

Model number	8EI2X2HWDS0.XXXX-1	8EI4X5HWDS0.XXXX-1	8EI8X8HWDS0.XXXX-1
Reduction of continuous current depending on installation elevation			
Starting at 500 m above sea level	0.22 A_{eff} per 1000 m	0.45 A_{eff} per 1000 m	0.88 A_{eff} per 1000 m
Peak current per motor connection	6 / 6 A_{eff}	12.25 / 12.25 A_{eff}	24 / 24 A_{eff}
Peak power output	2.5 kW	5 kW	10 kW [17]
Nominal switching frequency	5 kHz		
Possible switching frequencies [18]	5 / 10 / 20 kHz [19]		
Electrical stress of connected motor per IEC TS 60034-25	Limit value curve A		
Protective measures			
Overload protection	Yes		
Short circuit and ground fault protection	Yes		
Max. output frequency	598 Hz [20]	598 Hz [21]	598 Hz [20]
Variant			
U, V, W, PE	Male connector		
Shield connection	Yes		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	1.5 to 6 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Max. motor cable length depending on switching frequency			
Switching frequency 5 kHz	75 m [22]		
Switching frequency 10 kHz	38 m [22]		
Switching frequency 20 kHz	19 m [22]		
Motor holding brake connection			
Quantity	2		
Output voltage [23]	Depends on the input voltage on connector X2		
Continuous current	1.3 A		
Max. internal resistance	0.25 Ω		
Extinction potential	Approx. 30 V		
Max. extinction energy per switching operation	1.5 Ws		
Max. switching frequency	0.5 Hz		
Protective measures			
Overload and short-circuit protection	Yes		
Open circuit monitoring	Yes		
Undervoltage monitoring	Yes		
Response threshold for open circuit monitoring	Approx. 30 mA		
Response threshold for undervoltage monitoring	Approx. 23 V		
Max. cable length	75 m [24]		
Braking resistor [25]			
Peak power int./ext.	7 kW / 25 kW		
Continuous power int./ext.	150 W / 2 kW		
Minimum braking resistance (ext.)	25 Ω		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Protective measures			
Overload protection	No		
Short circuit and ground fault protection	Short circuit protection: Yes Ground fault protection: No		
Max. cable length	3 m		
Fieldbus			
Type	POWERLINK V2 controlled node (CN)		
Variant	2x RJ45, shielded, 2-port hub		
Cable length	Max. 100 m between 2 stations (segment length)		
Transfer rate	100 Mbit/s		
Encoder interfaces			
Quantity	2		
Type	Digital multi-encoder interface, configurable [26]		
Connections	8-pin female mini I/O connector		
Status indicators	None [27]		
Electrical isolation			
Encoder - ACOPOS P3	No		
Max. encoder cable length	75 m Depends on the cross section of the power supply wires of the encoder cable [28]		

Table 141: 8EI2X2HWDS0.XXXX-1, 8EI4X5HWDS0.XXXX-1, 8EI8X8HWDS0.XXXX-1 - Technical data

Model number	8EI2X2HWDS0.XXXX-1	8EI4X5HWDS0.XXXX-1	8EI8X8HWDS0.XXXX-1
Encoder power supply			
Output voltage	Configurable Typ. 11.45 V ± 0.1 V / 5.2 V ± 0.1 V [29][30]		
Load capacity	Max. 300 mA		
Sense lines	2, compensation of max. 2x 0.7 V		
Protective measures			
Short-circuit proof	Yes		
Overload-proof	Yes		
Synchronous serial interface			
Signal transmission	RS485 [31]		
Data transfer rate	Depends on the configured encoder type		
Differential voltage [32]			
Minimum	2.0 V		
Maximum	6.0 V		
Max. power consumption per encoder interface	$P_{ENCODER}$ [W] = U_{24V} [V] * ($I_{ENCODER}$ [A] * 0.7) + 0.5 W [33]		
Trigger inputs			
Quantity	2		
Circuit	Sink		
Electrical isolation			
Input - ACOPOS P3	Yes		
Input - Input	Yes		
Input voltage			
Nominal	24 VDC		
Maximum	30 VDC		
Switching threshold			
Low	<5 V		
High	>15 V		
Input current at nominal voltage	7 mA		
Switching delay			
Rising edge	<51 µs		
Falling edge	<52 µs		
Modulation compared to ground potential	Max. ±38 V		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 2.5 mm²		
Approbation data			
UL/C-UL-US	26 to 12 AWG		
CSA	26 to 12 AWG		
Max. cable length	100 m		
Support			
Motion system			
mapp Motion	5.00.0 and higher		
ACP10/ARNC0	3.14.1 and higher		
Operating conditions			
Permissible mounting orientations			
Hanging vertically	Yes		
Standing horizontally	Yes		
Installation elevation above sea level			
Nominal	0 to 500 m		
Maximum	4000 m		
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)		
Overvoltage category per EN 61800-5-1	III		
Degree of protection per EN 60529	IP20 [34]		
Ambient conditions			
Temperature			
Operation			
Nominal	5 to 40°C		
Maximum	55°C		
Storage	-25 to 55°C		
Transport	-25 to 70°C		
Relative humidity			
Operation	5 to 85%, non-condensing		
Storage	5 to 95%		
Transport	95% at 40°C		

Table 141: 8EI2X2HWDS0.XXXX-1, 8EI4X5HWDS0.XXXX-1, 8EI8X8HWDS0.XXXX-1 - Technical data

Model number	8EI2X2HWDS0.XXXX-1	8EI4X5HWDS0.XXXX-1	8EI8X8HWDS0.XXXX-1
Mechanical properties			
Dimensions			
Width	66 mm		
Height	374 mm		
Depth			
Wall mounting	258.5 mm (with 8EXA front cover: 261 mm)		
Weight	4 kg		

Table 141: 8EI2X2HWDS0.XXXX-1, 8EI4X5HWDS0.XXXX-1, 8EI8X8HWDS0.XXXX-1 - Technical data

1) A line filter must be connected.
CE compliance can only be ensured by connecting a B&R line filter (8x0F...).
In extreme cases, using line filters from 3rd-party manufacturers can result in irreparable damage to the 8EI ACOPOS P3 servo drive.
2) P_{AVG} ... Average continuous power of the module
I_{AX1}, I_{AX2} ... RMS value of the current on axis 1 and axis 2
I_{BR1}, I_{BR2} ... Nominal current of the motor holding brake on axis 1 and axis 2
P_{VSLOT} ... Power dissipation of the 8EAC plug-in module
3) P_{AVG} ... Average continuous power of the module
I_{AX1}, I_{AX2} ... RMS value of the current on axis 1, axis 2
I_{BR1}, I_{BR2} ... Nominal current of the motor holding brake on axis 1, axis 2
P_{VSLOT} ... Power dissipation of the 8EAC plug-in module
4) Maximum cable length between line filter and mains connection on the module.
5) Valid for a mains input voltage of ≥3x 400 VAC.
The sum of the continuous power values on all motor connections and the power of the DC bus connector is not permitted to exceed this value.
6) The continuous power is reduced as a percentage of the continuous current if the continuous current is subject to derating.
7) This value applies to unshielded wiring inside a control cabinet.
Maximum length of the DC bus wiring inside a control cabinet.
8) Current consumption depends on the configuration of the ACOPOS P3 8EI servo drive.
The inrush current of the 24 VDC power supply is not limited by the module.
9) Valid under the following conditions: 560 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
10) The total continuous power of all motor connections is not permitted to exceed 2 kW. The continuous power is reduced as a percentage of the continuous current if the continuous current is subject to derating.
11) The total continuous power of all motor connections is not permitted to exceed 4 kW. The continuous power is reduced as a percentage of the continuous current if the continuous current is subject to derating.
12) The accuracy of the safe current is relevant for safety functions SLT and SBT, which are based on the safe current measurement. Safety functions SBT, SLT and SSO are available starting with hardware upgrade 1.10.2.0 and only for 8EI servo drives with 8ZELxxxx revision D0 or later. See the device information on the left side cover of the servo drive.
13) These values apply up to the continuous current specified in the technical data (taking into account the respective derating specifications).
14) The temperature specifications refer to the ambient temperature.
15) Value for the nominal switching frequency.
16) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
17) The total peak power of all motor connections is not permitted to exceed 10 kW.
18) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
19) A switching frequency of 20 kHz is not recommended when using safety function SLT, SBT or SSO since availability problems may occur.
20) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use per Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
21) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
22) The sum of the length of all motor cables connected to this module is not permitted to exceed this value.
23) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified input voltage and wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
24) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified cable length. For the permissible operating voltage range of the holding brake, see the user documentation for the motor being used.
25) There is a connection for external braking resistors. An internal braking resistor is available as an option.
26) The encoder type is not predefined from the factory. The encoder type necessary in each case must be configured in Automation Studio.
27) The direction of rotation of the encoder can be displayed on the 8EAD0000.000-1 display module.
28) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 75 m is not permitted to exceeded):

l_{max} = f / I_G * A * 1/(2*ρ)

f ... (Output voltage of encoder interface [V] - Min. permissible supply voltage of connected encoder [V]) * 1.1
I_G ... Max. current consumption of connected encoder [A]
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
29) The output voltage is not predefined from the factory (with the exception of encoder types EnDat 2.2 and HIPERFACE DSL). It must be configured in Automation Studio based on the encoder type. If no output voltage is configured, then the encoder will not be supplied by digital multi-encoder interface X4x. Power to the encoder can then be supplied externally.
30) Output voltage 5.2 V is only available under the following conditions:
- 8EI servo drive with 8ZECxxx revision D0 and higher - see the device information on the left side cover of the 8EI servo drive
- ACOPOS operating system 3.15.0 and higher (for 8EIxxxxxD... 2-axis modules and 8EIxxxxxT... 3-axis modules)
- ACOPOS operating system 3.17.0 and higher (for 8EIxxxxxS... 1-axis modules)
31) Except encoder type HIPERFACE DSL.
32) Values valid for clock output and data input. Except encoder type HIPERFACE DSL.

33) $I_{ENCODER}$ ... Current consumption of the encoder
U_{24V} ... Input voltage on the +24 VDC input of the module

34) The specified degree of protection is only met if either the slot cover is installed on the module or an 8EAC plug-in module is installed and suitable terminals are connected to all connectors and all fans are installed.

4.1.2.3.2.2 Continuous power 2 x 7 kW to 2 x 9 kW (motor connection)

Order data

Model number	Short description	Figure
	2-axis modules SafeMOTION	
8EI017HWDS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 2x 17 A, SafeMOTION EnDat 2.2, 2 axes, wall mounting	
8EI022HWDS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 2x 22 A, SafeMOTION EnDat 2.2, 2 axes, wall mounting	
	Optional accessories	
	Display modules	
8EAD0000.000-1	Display module, LCD, 128 x 64, black/white, 1x USB 3.0	
	Front covers	
8EXA300.0010-00	ACOPOS P3 cover, B&R orange, double-width, height 2	
8EXA300.0020-00	ACOPOS P3 cover, B&R dark gray, double-width, height 2	
	Plug-in modules	
8EAC0122.001-1	ACOPOS P3 plug-in module, resolver interface 10 kHz	
8EAC0122.003-1	ACOPOS P3 plug-in module, 3 resolver interfaces 10 kHz	
8EAC0130.000-1	ACOPOS P3 plug-in module, 8 digital I/O 24 V (4x 400 mA, 4x 100 mA) individually configurable as inputs or outputs, 2 digital I/O 24 V 2 A configurable in pairs as inputs or outputs, order terminal block 8TB0230.221A-00 separately!	
8EAC0150.001-1	ACOPOS P3 plug-in module, digital multi-encoder interface	
8EAC0150.003-1	ACOPOS P3 plug-in module, 3 digital multi-encoder interfaces	
8EAC0151.001-1	ACOPOS P3 plug-in module, incremental encoder interface	
8EAC0151.003-1	ACOPOS P3 plug-in module, 3 incremental encoder interfaces	
8EAC0152.001-1	ACOPOS P3 plug-in module, analog multi-encoder interface	
8EAC0152.003-1	ACOPOS P3 plug-in module, 3 analog multi-encoder interfaces	
	Shield component sets	
8SCSE01.0200-00	ACOPOS P3 shield component set: 1x ACOPOS P3 shield mounting plate, 2x 2x M3x6 screws	
8SCSE02.0100-00	ACOPOS P3 shield component set: 1x shield component set, type SK14	
8SCSE02.0200-00	ACOPOS P3 shield component set: 1x shield component set, type SK20	
	Terminals	
8TB2104.2210-00	Push-in terminal block 4-pin, 1-row, pitch: 5.08 mm, label 1: numbered consecutively	
8TB3102.222C-20	Push-in terminal block, 2-pin, single row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3202.222C-40	Push-in terminal block, 2-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3308.222A-00	Push-in terminal block 4+4-pin 1-row/2-row, spacing: 7.62 mm, label 2: T- B- T+ B+ PE W V U A keying: 0000	
8TB4103.222A-10	Push-in terminal block, 3-pin, 1-row, spacing: 10.16 mm, label 2: PE RB- RB+, A keying: 000	
8TB4104.222L-10	Push-in terminal block, 4-pin, 1-row, spacing: 10.16 mm, label 2: PE L3 L2 L1, L keying: 1010	
8TB4104.227F-10	Push-in terminal block, 4-pin, 1-row, spacing: 10.16 mm, label 4: DC-, DC-, DC+, DC+ F keying: 0101	
8TB4204.202L-10	4-pin push-in screw terminal block, 2-row, pitch: 10.16 mm, label 2: PE L3 L2 L1, coding L: 1010	

Table 142: 8EI017HWDS0.XXXX-1, 8EI022HWDS0.XXXX-1 - Order data

Connection	1-row connector	2-row connector
X1	8TB4104.222L-10	8TB4204.202L-10
X2	8TB3102.222C-20	8TB3202.222C-40
X5x	8TB3308.222A-00	
X6	8TB4103.222A-10	
X7	8TB2104.2210-50	8TB2204.2210-50
X8	8TB2104.2210-00	
X11	8TB4104.227F-10	

Table 143: Terminal blocks - Model numbers

Information:

Connector X7 does <u>not</u> exist on ACOPOS P3 SafeMOTION servo drives.

Technical data

Model number	8EI017HWDS0.XXXX-1	8EI022HWDS0.XXXX-1
General information		
Slots for plug-in modules	1	
Certifications		
CE	Yes	
UL	cULus E225616 Power conversion equipment	
EAC	Yes	
KC	In preparation	
Mains connection		
Network configurations	TN-S, TN-C-S with grounded neutral	
Mains input voltage	3x 200 VAC to 480 VAC ±10%	
Frequency	50 / 60 Hz ±4%	
Installed load	Max. 26.4 kVA	Max. 30.5 kVA
Inrush current	100 A	
Switch-on interval	In preparation	
Integrated line filter per EN 61800-3, category C3	No [1)]	
Terminal connection cross section		
Flexible and fine-stranded wires		
With wire end sleeves	0.75 to 16 mm²	
Approbation data		
UL/C-UL-US	20 to 4 AWG	
CSA	20 to 4 AWG	
Power dissipation at device nominal power without braking resistor	In preparation	
Max. cable length	3 m [2)]	
DC bus connection		
Continuous power [3)]	14 kW [4)]	18 kW
Reduction of continuous power depending on mains input voltage		
Mains input voltage <3x 400 VAC	14 kW * (Mains input voltage [V] / 400 V)	18 kW * (Mains input voltage [V] / 400 V)
DC bus capacitance	1680 µF	
Terminal connection cross sections		
Flexible and fine-stranded wires		
With wire end sleeves	0.75 to 16 mm²	
Approbation data		
UL/C-UL-US	20 to 4 AWG	
CSA	20 to 4 AWG	
Max. cable length	3 m [5)]	
24 VDC power supply		
Input voltage	24 VDC ±25%	
Input capacitance	5500 µF	
Current consumption	2.4 A + Current for motor holding brake [6)7)]	
Terminal connection cross sections		
Flexible and fine-stranded wires		
With wire end sleeves	0.25 to 4 mm²	
Approbation data		
UL/C-UL-US	24 to 8 AWG	
CSA	24 to 8 AWG	
Max. cable length	30 m	
Motor connection		
Quantity	2	
Continuous power per motor connection [8)]	7 / 7 kW	9 / 9 kW
Continuous current per motor connection [8)]	17 / 17 A_{eff}	22 / 22 A_{eff}
Reduction of continuous current depending on switching frequency		
Switching frequency 5 kHz	No reduction	0.333 A/K (starting at 40°C) [9)]
Switching frequency 10 kHz	0.195 A/K (starting at 16°C) [9)]	0.195 A/K (starting at -9°C) [9)]
Switching frequency 20 kHz	0.145 A/K (starting at -59°C) [9)]	0.145 A/K (starting at -93°C) [9)]
Reduction of continuous current depending on installation elevation		
Starting at 500 m above sea level	1.7 A_{eff} per 1000 m	2.2 A_{eff} per 1000 m
Peak current per motor connection	42.5 / 42.5 A_{eff}	55 / 55 A_{eff}
Peak power output	17.5 / 17.5 kW	22.5 / 22.5 kW
Nominal switching frequency	5 kHz	
Possible switching frequencies [10)]	5 / 10 / 20 kHz	
Electrical stress of connected motor per IEC TS 60034-25	Limit value curve A	
Protective measures		
Overload protection	Yes	
Short circuit and ground fault protection	Yes	
Max. output frequency	598 Hz [11)]	

Table 144: 8EI017HWDS0.XXXX-1, 8EI022HWDS0.XXXX-1 - Technical data

Model number	8EI017HWDS0.XXXX-1	8EI022HWDS0.XXXX-1
Variant		
U, V, W, PE	Connector	
Shield connection	Yes	
Terminal connection cross section		
Flexible and fine-stranded wires		
With wire end sleeves	1.5 to 6 mm²	
Approbation data		
UL/C-UL-US	24 to 8 AWG	
CSA	24 to 8 AWG	
Max. motor cable length depending on switching frequency		
Switching frequency 5 kHz	75 m [12]	
Switching frequency 10 kHz	75 m [12]	
Switching frequency 20 kHz	30 m [12]	
Motor holding brake connection		
Quantity	2	
Output voltage [13]	Depends on the input voltage on connector X2	
Continuous current	4 A	
Max. internal resistance	0.25 Ω	
Extinction potential	In preparation	
Max. extinction energy per switching operation	In preparation	
Max. switching frequency	In preparation	
Protective measures		
Overload and short-circuit protection	Yes	
Open circuit monitoring	Yes	
Undervoltage monitoring	Yes	
Response threshold for open circuit monitoring	In preparation	
Response threshold for undervoltage monitoring	Approx. 23 V	
Max. breaking current SBC	80 mA	
Max. cable length	In preparation	
Braking resistor [14]		
Peak power output	45 kW	
Continuous power	4 kW	
Minimum braking resistance (ext.)	13 Ω	
Terminal connection cross section		
Flexible and fine-stranded wires		
With wire end sleeves	0.75 to 16 mm²	
Approbation data		
UL/C-UL-US	20 to 4 AWG	
CSA	20 to 4 AWG	
Protective measures		
Overload protection	No	
Short circuit and ground fault protection	Short-circuit protection: Yes Ground fault protection: No	
Max. cable length	3 m	
Fieldbus		
Type	POWERLINK V2 controlled node (CN)	
Variant	2x RJ45, shielded, 2-port hub	
Cable length	Max. 100 m between 2 stations (segment length)	
Transfer rate	100 Mbit/s	
Encoder interfaces		
Quantity	2	
Type	Digital multi-encoder interface, configurable [15]	
Connections	8-pin female Mini I/O connector	
Status indicators	None [16]	
Electrical isolation		
Encoder - ACOPOS P3	No	
Max. encoder cable length	75 m Depends on the cross section of the power supply wires in the encoder cable [17]	
Encoder power supply		
Output voltage	Configurable Typ. 11.45 V ±0.1 V / 5.2 V ± 0.1 V [18][19]	Configurable Typ. 11.45 V ±0.1 V / 5.2 V ± 0.1 V [19][20]
Load capacity	Max. 300 mA	
Sense lines	2, compensation of max. 2x 0.7 V	
Protective measures		
Short-circuit proof	Yes	
Overload-proof	Yes	
Synchronous serial interface		
Signal transmission	RS485 [21]	
Data transfer rate	Depends on the configured encoder type	
Differential voltage [22]		
Minimum	2.0 V	
Maximum	6.0 V	

Table 144: 8EI017HWDS0.XXXX-1, 8EI022HWDS0.XXXX-1 - Technical data

Model number	8EI017HWDS0.XXXX-1	8EI022HWDS0.XXXX-1
Max. power consumption per encoder interface	$P_{ENCODER}$ [W] = U_{24V} [V] * ($I_{ENCODER}$ [A] * 0.7) + 0.5 W [23]	
Trigger inputs		
Quantity	2	
Circuit	Sink	
Electrical isolation		
Input - ACOPOS P3	Yes	
Input - Input	Yes	
Input voltage		
Nominal	24 VDC	
Maximum	30 VDC	
Switching threshold		
Low	<5 V	
High	>15 V	
Input current at nominal voltage	7 mA	
Switching delay		
Rising edge	<51 µs	
Falling edge	<52 µs	
Modulation compared to ground potential	Max. ±38 V	
Terminal connection cross section		
Flexible and fine-stranded wires		
With wire end sleeves	0.25 to 2.5 mm²	
Approbation data		
UL/C-UL-US	26 to 12 AWG	
CSA	26 to 12 AWG	
Max. cable length	100 m	
Support		
Motion system		
mapp Motion	5.03.0 and higher	
ACP10/ARNC0	5.03.0 and higher	
Operating conditions		
Permissible mounting orientations		
Hanging vertically	Yes	
Standing horizontally	Yes	
Installation elevation above sea level		
Nominal	0 to 500 m	
Maximum	4000 m	
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)	
Overvoltage category per EN 61800-5-1	III	
Degree of protection per EN 60529	IP20 [24]	
Ambient conditions		
Temperature		
Operation		
Nominal	5 to 40°C	
Maximum	55°C	
Storage	-25 to 55°C	
Transport	-25 to 70°C	
Relative humidity		
Operation	5 to 85%, non-condensing	
Storage	5 to 95%	
Transport	95% at 40°C	
Mechanical properties		
Dimensions		
Width	133 mm	
Height	374 mm	
Depth		
Wall mounting	258.5 mm (with 8EXA front cover: 261 mm)	
Weight	8 kg	

Table 144: 8EI017HWDS0.XXXX-1, 8EI022HWDS0.XXXX-1 - Technical data

1) A line filter must be connected.
CE compliance can only be ensured by connecting a B&R line filter (8x0F...).
In extreme cases, using line filters from 3rd-party manufacturers can result in irreparable damage to the 8EI ACOPOS P3 servo drive.
2) Maximum line length between line filter and mains connection on the module.
3) Valid for a mains input voltage of ≥3x 400 VAC.
The sum of the continuous power values on all motor connections and the power of the DC bus connector is not permitted to exceed this value.
4) The value can be higher under certain conditions.
5) This value applies to unshielded wiring inside a control cabinet.
Maximum length of the DC bus wiring inside a control cabinet.
6) Current consumption depends on the respective configuration of the ACOPOS P3 8EI servo drive.
The inrush current of the 24 VDC power supply is not limited by the module.
7) At nominal 24 VDC supply voltage and 20 kHz switching frequency. Without plug-in card.
8) Valid under the following conditions: 560 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.

9) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
10) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
11) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
12) The sum of the cable lengths of all motor cables connected to this module is not permitted to exceed this value.
13) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified input voltage and wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
14) This values apply to an external braking resistor. This module is not equipped with an internal braking resistor.
15) The encoder type is not predefined from the factory. The encoder type necessary in each case must be configured in Automation Studio.
16) The direction of rotation of the encoder can be displayed on the 8EAD0000.000-1 display module.
17) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 75 m is not permitted to exceeded):

    $l_{max} = f / I_G * A * 1/(2*\rho)$

    f ... (Output voltage of encoder interface [V] - Min. permissible supply voltage of connected encoder [V]) * 1.1
    I_G ... Max. current consumption of connected encoder [A]
    A ... Cross section of the power supply wires [mm²]
    ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
18) The output voltage is not predefined from the factory (with the exception of encoder types EnDat 2.2 and HIPERFACE DSL) . It must be configured in Automation Studio based on the encoder type. If no output voltage is configured, then the encoder will not be supplied by digital multi-encoder interface X4x. Power to the encoder can then be supplied externally.
19) Output voltage 5.2 V is only available under the following conditions:
    - 8EI servo drive with 8ZECxxx revision D0 and higher - see the device information on the left side cover of the 8EI servo drive
    - ACOPOS operating system 3.15.0 and higher (for 8EIxxxxxD... 2-axis modules and 8EIxxxxxT... 3-axis modules)
    - ACOPOS operating system 3.17.0 and higher (for 8EIxxxxxS... 1-axis modules)
20) The output voltage is not predefined from the factory (with the exception of encoder types EnDat 2.2 and HIPERFACE DSL). It must be configured in Automation Studio based on the encoder type. If no output voltage is configured, then the encoder will not be supplied by digital multi-encoder interface X4x. Power to the encoder can then be supplied externally.
21) Except encoder type HIPERFACE DSL.
22) Values valid for clock output and data input. Except encoder type HIPERFACE DSL.
23) $I_{ENCODER}$ ... Current consumption of the encoder
    U_{24V} ... Input voltage on the +24 VDC input of the module
24) The specified degree of protection is only met if either the slot cover is installed on the module or an 8EAC plug-in module is installed and suitable terminals are connected to all connectors and all fans are installed.

4.1.2.4 3-axis modules

4.1.2.4.1 Mains input voltage - 1x 110 to 230 VAC / 3x 200 to 230 VAC

4.1.2.4.1.1 Order data

Model number	Short description	Figure
	3-axis modules SafeMOTION	
8EI2X2MWTS0.XXXX-1	ACOPOS P3 servo drive, 1x 110-230 VAC, 3x 200-230 VAC, 3x 2.2 A, SafeMOTION EnDat 2.2, 3 axes, wall mounting	
8EI4X5MWTS0.XXXX-1	ACOPOS P3 servo drive, 1x 110-230 VAC, 3x 200-230 VAC, 3x 4.5 A, SafeMOTION EnDat 2.2, 3 axes, wall mounting	
8EI8X8MWTS0.XXXX-1	ACOPOS P3 servo drive, 1x 110-230 VAC, 3x 200-230 VAC, 3x 8.8 A, SafeMOTION EnDat 2.2, 3 axes, wall mounting	
	Optional accessories	
	Display modules	
8EAD0000.000-1	Display module, LCD, 128 x 64, black/white, 1x USB 3.0	
	Front covers	
8EXA200.0010-00	ACOPOS P3 cover, B&R orange, single-width, height 2	
8EXA200.0020-00	ACOPOS P3 cover, B&R dark gray, single-width, height 2	
	Plug-in modules	
8EAC0122.001-1	ACOPOS P3 plug-in module, resolver interface 10 kHz	
8EAC0122.003-1	ACOPOS P3 plug-in module, 3 resolver interfaces 10 kHz	
8EAC0130.000-1	ACOPOS P3 plug-in module, 8 digital I/O 24 V (4x 400 mA, 4x 100 mA) individually configurable as inputs or outputs, 2 digital I/O 24 V 2 A configurable in pairs as inputs or outputs, order terminal block 8TB0230.221A-00 separately!	
8EAC0150.001-1	ACOPOS P3 plug-in module, digital multi-encoder interface	
8EAC0150.003-1	ACOPOS P3 plug-in module, 3 digital multi-encoder interfaces	
8EAC0151.001-1	ACOPOS P3 plug-in module, incremental encoder interface	
8EAC0151.003-1	ACOPOS P3 plug-in module, 3 incremental encoder interfaces	
8EAC0152.001-1	ACOPOS P3 plug-in module, analog multi-encoder interface	
8EAC0152.003-1	ACOPOS P3 plug-in module, 3 analog multi-encoder interfaces	
	Shield component sets	
8SCSE01.0100-00	ACOPOS P3 shield component set: 1x ACOPOS P3 shield mounting plate, 1x 2x M3x6 screws	
8SCSE02.0100-00	ACOPOS P3 shield component set: 1x shield component set, type SK14	
8SCSE02.0200-00	ACOPOS P3 shield component set: 1x shield component set, type SK20	
	Terminals	
8TB2104.2210-00	Push-in terminal block 4-pin, 1-row, pitch: 5.08 mm, label 1: numbered consecutively	
8TB3102.222C-20	Push-in terminal block, 2-pin, single row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3103.222A-20	Push-in terminal block, 3-pin, 1-row, spacing: 7.62 mm, label 2: PE RB- RB+, A keying: 000	
8TB3106.223C-20	Push-in terminal block, 6-pin, 1-row, with locking mechanism, spacing: 7.62 mm, label 3: PE L3 N(L2) L1 DC- DC+, C keying: 000010	
8TB3202.222C-40	Push-in terminal block, 2-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3206.223C-40	Push-in terminal block, 6-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 3: PE L3 N(L2) L1 DC- DC+, C keying: 000010	
8TB3308.222A-00	Push-in terminal block 4+4-pin 1-row/2-row, spacing: 7.62 mm, label 2: T- B- T+ B+ PE W V U A keying: 0000	

Table 145: 8EI2X2MWTS0.XXXX-1, 8EI4X5MWTS0.XXXX-1, 8EI8X8MWTS0.XXXX-1 - Order data

Connection	1-row connector	2-row connector
X1	8TB3106.223C-20	8TB3206.223C-40
X2	8TB3102.222C-20	8TB3202.222C-40
X5x	8TB3308.222A-00	
X6	8TB3103.222A-20	
X7	8TB2104.2210-50	8TB2204.2210-50
X8	8TB2104.2210-00	

Table 146: Terminal blocks - Model numbers

Information:

Connector X7 does <u>not</u> exist on ACOPOS P3 SafeMOTION servo drives.

4.1.2.4.1.3 Technical data

Model number	8EI2X2MWTS0.XXXX-1	8EI4X5MWTS0.XXXX-1	8EI8X8MWTS0.XXXX-1
General information			
Slots for plug-in modules	1		
Certifications			
CE	Yes		
UL	cULus E225616 Power conversion equipment		
EAC	Yes		
KC	Yes		
Mains connection			
Network configurations	TN-S, TN-C-S with grounded neutral		
Mains input voltage	1x 110 VAC to 230 VAC ±10% 3x 200 VAC to 230 VAC ±10%		
Frequency	50/60 Hz ±4%		
Installed load	Max. 3.75 kVA	Max. 5 kVA	
Inrush current	Max. 22 A		
Switch-on interval	Typ. 60 s		
Integrated line filter per EN 61800-3, category C3	No [1]		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Power dissipation at device nominal power without braking resistor	$[(40 + 10 * P_{AVG}$ [kW] $+ 5.8 * (I_{AX1}$ [A] $+ I_{AX2}$ [A] $+ I_{AX3}$ [A]) + $0.25 * (I_{BR1}^2$ [A] $+ I_{BR2}^2$ [A] $+ I_{BR3}^2$ [A]) $+ P_{VSLOT}) * 1.1]$ [W] [2]		
Max. cable length	3 m [3]		
DC bus connection			
Continuous power [4]	1.5 kW [5]	2 kW [5]	
Reduction of continuous power depending on mains input voltage			
Mains input voltage <230 VAC	1.5 kW * (Mains input voltage [V] / 230 V)	2 kW * (Mains input voltage [V] / 230 V)	
DC bus capacitance	1880 µF		
Terminal connection cross sections			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Max. cable length	3 m [6]		
24 VDC power supply			
Input voltage	24 VDC ±25%		
Input capacitance	5500 µF		
Current consumption	1.2 A + Current for motor holding brake [7]		
Terminal connection cross sections			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Max. cable length	30 m		
Motor connection			
Quantity	3		
Continuous power per motor connection [8]	0.5 / 0.5 / 0.5 kW [9]	1 / 1 / 1 kW [10]	2 / 2 / 2 kW [10]
Continuous current per motor connection [8]	2.2 / 2.2 / 2.2 A_{eff}	4.5 / 4.5 / 4.5 A_{eff}	8.8 / 8.8 / 8.8 A_{eff}
Accuracy of the safe current [11]			
Safety function SLT			
SIL 2 / PL d / Cat. 3	Hardware upgrade 1.10.2.x: 1.545 A Hardware upgrade 1.10.3.0 or later: 1.244 A [12]	Hardware upgrade 1.10.2.x: 1.714 A Hardware upgrade 1.10.3.0 or later: 1.421 A [12]	Hardware upgrade 1.10.2.x: 2.035 A Hardware upgrade 1.10.3.0 or later: 1.754 A [12]
Safety function SBT			
SIL 2 / PL d / Cat. 3	Hardware upgrade 1.10.2.x: 1.441 A Hardware upgrade 1.10.3.0 or later: 1.136 A [12]	Hardware upgrade 1.10.2.x: 1.501 A Hardware upgrade 1.10.3.0 or later: 1.199 A [12]	Hardware upgrade 1.10.2.x: 1.613 A Hardware upgrade 1.10.3.0 or later: 1.317 A [12]
Reduction of continuous current depending on switching frequency [13]			
Switching frequency 5 kHz	No reduction		1.375 A/K (starting at 52.0°C) [14]
Switching frequency 10 kHz	No reduction		0.393 A/K (starting at 45.5°C)
Switching frequency 20 kHz	No reduction	0.120 A/K (starting at 41.9°C) [15]	0.120 A/K (starting at 5.9°C) [15]

Table 147: 8EI2X2MWTS0.XXXX-1, 8EI4X5MWTS0.XXXX-1, 8EI8X8MWTS0.XXXX-1 - Technical data

Model number	8EI2X2MWTS0.XXXX-1	8EI4X5MWTS0.XXXX-1	8EI8X8MWTS0.XXXX-1
Reduction of continuous current depending on installation elevation			
Starting at 500 m above sea level	0.22 A_{eff} per 1000 m	0.45 A_{eff} per 1000 m	0.88 A_{eff} per 1000 m
Peak current per motor connection	6 / 6 / 6 A_{eff}	12.25 / 12.25 / 12.25 A_{eff}	24 / 24 / 24 A_{eff}
Peak power output	1.25 kW	2.5 kW [16]	5 kW [16]
Nominal switching frequency	5 kHz		
Possible switching frequencies [17]	5 / 10 / 20 kHz [18]		
Electrical stress of connected motor per IEC TS 60034-25	Limit value curve A		
Protective measures			
Overload protection	Yes		
Short circuit and ground fault protection	Yes		
Max. output frequency	598 Hz [19]	598 Hz [20]	
Variant			
U, V, W, PE	Male connector		
Shield connection	Yes		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	1.5 to 6 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Max. motor cable length depending on switching frequency			
Switching frequency 5 kHz	75 m [21]		
Switching frequency 10 kHz	38 m [21]		
Switching frequency 20 kHz	19 m [21]		
Motor holding brake connection			
Quantity	3		
Output voltage [22]	Depends on the input voltage on connector X2		
Continuous current	1.3 A		
Max. internal resistance	0.25 Ω		
Extinction potential	Approx. 30 V		
Max. extinction energy per switching operation	1.5 Ws		
Max. switching frequency	0.5 Hz		
Protective measures			
Overload and short-circuit protection	Yes		
Open circuit monitoring	Yes		
Undervoltage monitoring	Yes		
Response threshold for open circuit monitoring	Approx. 30 mA		
Response threshold for undervoltage monitoring	Approx. 23 V		
Max. cable length	75 m [23]		
Braking resistor [24]			
Peak power int./ext.	1.5 kW / 11 kW		
Continuous power int./ext.	150 W / 970 W		
Minimum braking resistance (ext.)	12 Ω		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Protective measures			
Overload protection	No		
Short circuit and ground fault protection	Short circuit protection: Yes Ground fault protection: No		
Max. cable length	3 m		
Fieldbus			
Type	POWERLINK V2 controlled node (CN)		
Variant	2x RJ45, shielded, 2-port hub		
Cable length	Max. 100 m between 2 stations (segment length)		
Transfer rate	100 Mbit/s		
Encoder interfaces			
Quantity	3		
Type	Digital multi-encoder interface, configurable [25]		
Connections	8-pin female mini I/O connector		
Status indicators	None [26]		
Electrical isolation			
Encoder - ACOPOS P3	No		
Max. encoder cable length	75 m Depends on the cross section of the power supply wires of the encoder cable [27]		

Table 147: 8EI2X2MWTS0.XXXX-1, 8EI4X5MWTS0.XXXX-1, 8EI8X8MWTS0.XXXX-1 - Technical data

Model number	8EI2X2MWTS0.XXXX-1	8EI4X5MWTS0.XXXX-1	8EI8X8MWTS0.XXXX-1
Encoder power supply			
Output voltage	Configurable Typ. 11.45 V ± 0.1 V / 5.2 V ± 0.1 V [28][29]		
Load capacity	Max. 300 mA		
Sense lines	2, compensation of max. 2x 0.7 V		
Protective measures			
Short-circuit proof	Yes		
Overload-proof	Yes		
Synchronous serial interface			
Signal transmission	RS485 [30]		
Data transfer rate	Depends on the configured encoder type		
Differential voltage [31]			
Minimum	2.0 V		
Maximum	6.0 V		
Max. power consumption per encoder interface	$P_{ENCODER}$ [W] = U_{24V} [V] * ($I_{ENCODER}$ [A] * 0.7) + 0.5 W [32]		
Trigger inputs			
Quantity	2		
Circuit	Sink		
Electrical isolation			
Input - ACOPOS P3	Yes		
Input - Input	Yes		
Input voltage			
Nominal	24 VDC		
Maximum	30 VDC		
Switching threshold			
Low	<5 V		
High	>15 V		
Input current at nominal voltage	7 mA		
Switching delay			
Rising edge	<51 µs		
Falling edge	<52 µs		
Modulation compared to ground potential	Max. ±38 V		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 2.5 mm²		
Approbation data			
UL/C-UL-US	26 to 12 AWG		
CSA	26 to 12 AWG		
Max. cable length	100 m		
Support			
Motion system			
mapp Motion	5.00.0 and higher		
ACP10/ARNC0	3.14.1 and higher		3.14.0 and higher
Operating conditions			
Permissible mounting orientations			
Hanging vertically	Yes		
Standing horizontally	Yes		
Installation elevation above sea level			
Nominal	0 to 500 m		
Maximum	4000 m		
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)		
Overvoltage category per EN 61800-5-1	III		
Degree of protection per EN 60529	IP20 [33]		
Ambient conditions			
Temperature			
Operation			
Nominal	5 to 40°C		
Maximum	55°C		
Storage	-25 to 55°C		
Transport	-25 to 70°C		
Relative humidity			
Operation	5 to 85%, non-condensing		
Storage	5 to 95%		
Transport	95% at 40°C		

Table 147: 8EI2X2MWTS0.XXXX-1, 8EI4X5MWTS0.XXXX-1, 8EI8X8MWTS0.XXXX-1 - Technical data

Model number	8EI2X2MWTS0.XXXX-1	8EI4X5MWTS0.XXXX-1	8EI8X8MWTS0.XXXX-1
Mechanical properties			
Dimensions			
Width	66 mm		
Height	374 mm		
Depth			
Wall mounting	258.5 mm (with 8EXA front cover: 261 mm)		
Weight	4 kg		

Table 147: 8EI2X2MWTS0.XXXX-1, 8EI4X5MWTS0.XXXX-1, 8EI8X8MWTS0.XXXX-1 - Technical data

1) A line filter must be connected.
CE compliance can only be ensured by connecting a B&R line filter (8x0F...).
In extreme cases, using line filters from 3rd-party manufacturers can result in irreparable damage to the 8EI ACOPOS P3 servo drive.
2) P_{AVG} ... Average continuous power of the module
I_{AX1}, I_{AX2}, I_{AX3} ... RMS value of the current on axis 1, axis 2, axis 3
I_{BR1}, I_{BR2}, I_{BR3} ... Nominal current of the motor holding brake on axis 1, axis 2, axis 3
P_{VSLOT} ... Power dissipation of the 8EAC plug-in module
3) Maximum cable length between line filter and mains connection on the module.
4) Valid for a mains input voltage of 230 VAC.
The sum of the continuous power values on all motor connections and the power of the DC bus connector is not permitted to exceed this value.
5) The continuous power is reduced as a percentage of the continuous current if the continuous current is subject to derating.
6) This value applies to unshielded wiring inside a control cabinet.
Maximum length of the DC bus wiring inside a control cabinet.
7) Current consumption depends on the configuration of the ACOPOS P3 8EI servo drive.
The inrush current of the 24 VDC power supply is not limited by the module.
8) Valid under the following conditions: 325 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
9) The total continuous power of all motor connections is not permitted to exceed 1.5 kW. The continuous power is reduced as a percentage of the continuous current if the continuous current is subject to derating.
10) The total continuous power of all motor connections is not permitted to exceed 2 kW. The continuous power is reduced as a percentage of the continuous current if the continuous current is subject to derating.
11) The accuracy of the safe current is relevant for safety functions SLT and SBT, which are based on the safe current measurement. Safety functions SBT, SLT and SSO are available starting with hardware upgrade 1.10.2.0 and only for 8EI servo drives with 8ZELxxxx revision D0 or later. See the device information on the left side cover of the servo drive.
12) These values apply up to the continuous current specified in the technical data (taking into account the respective derating specifications).
13) The temperature specifications refer to the ambient temperature.
14) Value for the nominal switching frequency.
15) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
16) The total peak power of all motor connections is not permitted to exceed 5 kW.
17) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
18) A switching frequency of 20 kHz is not recommended when using safety function SLT, SBT or SSO since availability problems may occur.
19) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
20) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use per Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
21) The sum of the length of all motor cables connected to this module is not permitted to exceed this value.
22) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified input voltage and wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
23) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified cable length. For the permissible operating voltage range of the holding brake, see the user documentation for the motor being used.
24) There is a connection for external braking resistors. An internal braking resistor is available as an option.
25) The encoder type is not predefined from the factory. The encoder type necessary in each case must be configured in Automation Studio.
26) The direction of rotation of the encoder can be displayed on the 8EAD0000.000-1 display module.
27) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 75 m is not permitted to exceeded):

$l_{max} = f / I_G * A * 1/(2*\rho)$

f ... (Output voltage of encoder interface [V] - Min. permissible supply voltage of connected encoder [V]) * 1.1
I_G ... Max. current consumption of connected encoder [A]
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
28) The output voltage is not predefined from the factory (with the exception of encoder types EnDat 2.2 and HIPERFACE DSL). It must be configured in Automation Studio based on the encoder type. If no output voltage is configured, then the encoder will not be supplied by digital multi-encoder interface X4x. Power to the encoder can then be supplied externally.
29) Output voltage 5.2 V is only available under the following conditions:
- 8EI servo drive with 8ZECxxx revision D0 and higher - see the device information on the left side cover of the 8EI servo drive
- ACOPOS operating system 3.15.0 and higher (for 8EIxxxxxD... 2-axis modules and 8EIxxxxxT... 3-axis modules)
- ACOPOS operating system 3.17.0 and higher (for 8EIxxxxxS... 1-axis modules)
30) Except encoder type HIPERFACE DSL.
31) Values valid for clock output and data input. Except encoder type HIPERFACE DSL.
32) $I_{ENCODER}$ ... Current consumption of the encoder
U_{24V} ... Input voltage on the +24 VDC input of the module
33) The specified degree of protection is only met if either the slot cover is installed on the module or an 8EAC plug-in module is installed and suitable terminals are connected to all connectors and all fans are installed.

4.1.2.4.2 Mains input voltage - 3x 200 to 480 VAC

4.1.2.4.2.1 Order data

Model number	Short description	Figure
	3-axis modules SafeMOTION	
8EI2X2HWTS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 3x 2.2 A, SafeMOTION EnDat 2.2, 3 axes, wall mounting	
8EI4X5HWTS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 3x 4.5 A, SafeMOTION EnDat 2.2, 3 axes, wall mounting	
8EI8X8HWTS0.XXXX-1	ACOPOS P3 servo drive, 3x 200-480 VAC, 3x 8.8 A, SafeMOTION EnDat 2.2, 3 axes, wall mounting	
	Optional accessories	
	Display modules	
8EAD0000.000-1	Display module, LCD, 128 x 64, black/white, 1x USB 3.0	
	Front covers	
8EXA200.0010-00	ACOPOS P3 cover, B&R orange, single-width, height 2	
8EXA200.0020-00	ACOPOS P3 cover, B&R dark gray, single-width, height 2	
	Plug-in modules	
8EAC0122.001-1	ACOPOS P3 plug-in module, resolver interface 10 kHz	
8EAC0122.003-1	ACOPOS P3 plug-in module, 3 resolver interfaces 10 kHz	
8EAC0130.000-1	ACOPOS P3 plug-in module, 8 digital I/O 24 V (4x 400 mA, 4x 100 mA) individually configurable as inputs or outputs, 2 digital I/O 24 V 2 A configurable in pairs as inputs or outputs, order terminal block 8TB0230.221A-00 separately!	
8EAC0150.001-1	ACOPOS P3 plug-in module, digital multi-encoder interface	
8EAC0150.003-1	ACOPOS P3 plug-in module, 3 digital multi-encoder interfaces	
8EAC0151.001-1	ACOPOS P3 plug-in module, incremental encoder interface	
8EAC0151.003-1	ACOPOS P3 plug-in module, 3 incremental encoder interfaces	
8EAC0152.001-1	ACOPOS P3 plug-in module, analog multi-encoder interface	
8EAC0152.003-1	ACOPOS P3 plug-in module, 3 analog multi-encoder interfaces	
	Shield component sets	
8SCSE01.0100-00	ACOPOS P3 shield component set: 1x ACOPOS P3 shield mounting plate, 1x 2x M3x6 screws	
8SCSE02.0100-00	ACOPOS P3 shield component set: 1x shield component set, type SK14	
8SCSE02.0200-00	ACOPOS P3 shield component set: 1x shield component set, type SK20	
	Terminals	
8TB2104.2210-00	Push-in terminal block 4-pin, 1-row, pitch: 5.08 mm, label 1: numbered consecutively	
8TB3102.222C-20	Push-in terminal block, 2-pin, single row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3103.222A-20	Push-in terminal block, 3-pin, 1-row, spacing: 7.62 mm, label 2: PE RB- RB+, A keying: 000	
8TB3106.222B-20	Push-in terminal block, 6-pin, single row, with locking mechanism, spacing: 7.62 mm, label 2: PE L3 L2 L1 DC- DC+, B keying: 000001	
8TB3202.222C-40	Push-in terminal block, 2-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 2: COM 24 V, C keying: 10	
8TB3206.222B-40	Push-in terminal block, 6-pin, 2-row, with locking mechanism, spacing: 7.62 mm, label 2: PE L3 L2 L1 DC- DC+, C keying: 000001	
8TB3308.222A-00	Push-in terminal block 4+4-pin 1-row/2-row, spacing: 7.62 mm, label 2: T- B- T+ B+ PE W V U A keying: 0000	

Table 148: 8EI2X2HWTS0.XXXX-1, 8EI4X5HWTS0.XXXX-1, 8EI8X8HWTS0.XXXX-1 - Order data

Connection	1-row connector	2-row connector
X1	8TB3106.222B-20	8TB3206.222B-40
X2	8TB3102.222C-20	8TB3202.222C-40
X5x	8TB3308.222A-00	
X6	8TB3103.222A-20	
X7	8TB2104.2210-50	8TB2204.2210-50
X8	8TB2104.2210-00	

Table 149: Terminal blocks - Model numbers

Information:

Connector X7 does not exist on ACOPOS P3 SafeMOTION servo drives.

4.1.2.4.2.3 Technical data

Model number	8EI2X2HWTS0.XXXX-1	8EI4X5HWTS0.XXXX-1	8EI8X8HWTS0.XXXX-1
General information			
Slots for plug-in modules	1		
Certifications			
CE	Yes		
UL	cULus E225616 Power conversion equipment		
EAC	Yes		
KC	Yes		
Mains connection			
Network configurations	TN-S, TN-C-S with grounded neutral		
Mains input voltage	3x 200 VAC to 480 VAC ±10%		
Frequency	50/60 Hz ±4%		
Installed load	Max. 7.5 kVA	Max. 10 kVA	
Inrush current	Max. 45 A		
Switch-on interval	Typ. 60 s		
Integrated line filter per EN 61800-3, category C3	No [1]		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Power dissipation at device nominal power without braking resistor	$[(60 + 6.9 * P_{AVG}$ [kW] $+ 7.5 * (I_{AX1}$ [A] $+ I_{AX2}$ [A] $+ I_{AX3}$ [A]) $+ 0.25 * (I_{BR1}^2$ [A] $+ I_{BR2}^2$ [A] $+ I_{BR3}^2$ [A]) $+ P_{VSLOT}) * 1.1]$ [W] [2]		
Max. cable length	3 m [3]		
DC bus connection			
Continuous power [4]	3 kW [5]	4 kW [5]	
Reduction of continuous power depending on mains input voltage			
Mains input voltage <3x 400 VAC	3 kW * (Mains input voltage [V] / 400 V)	4 kW * (Mains input voltage [V] / 400 V)	
DC bus capacitance	470 µF		
Terminal connection cross sections			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Max. cable length	3 m [6]		
24 VDC power supply			
Input voltage	24 VDC ±25%		
Input capacitance	5500 µF		
Current consumption	1.2 A + Current for motor holding brake [7]		
Terminal connection cross sections			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Max. cable length	30 m		
Motor connection			
Quantity	3		
Continuous power per motor connection [8]	1 / 1 / 1 kW [9]	2 / 2 / 2 kW [10]	4 / 4 / 4 kW [10]
Continuous current per motor connection [8]	2.2 / 2.2 / 2.2 A_{eff}	4.5 / 4.5 / 4.5 A_{eff}	8.8 / 8.8 / 8.8 A_{eff}
Accuracy of the safe current [11]			
Safety function SLT			
SIL 2 / PL d / Cat. 3	Hardware upgrade 1.10.2.x: 1.545 A Hardware upgrade 1.10.3.0 or later: 1.244 A [12]	Hardware upgrade 1.10.2.x: 1.714 A Hardware upgrade 1.10.3.0 or later: 1.421 A [12]	Hardware upgrade 1.10.2.x: 2.035 A Hardware upgrade 1.10.3.0 or later: 1.754 A [12]
Safety function SBT			
SIL 2 / PL d / Cat. 3	Hardware upgrade 1.10.2.x: 1.441 A Hardware upgrade 1.10.3.0 or later: 1.136 A [12]	Hardware upgrade 1.10.2.x: 1.501 A Hardware upgrade 1.10.3.0 or later: 1.199 A [12]	Hardware upgrade 1.10.2.x: 1.613 A Hardware upgrade 1.10.3.0 or later: 1.317 A [12]
Reduction of continuous current depending on switching frequency [13]			
Switching frequency 5 kHz	No reduction		0.373 A/K (starting at 45.2°C) [14]
Switching frequency 10 kHz	No reduction	0.154 A/K (starting at 46.5°C)	0.154 A/K (starting at 18.5°C)
Switching frequency 20 kHz	0.075 A/K (starting at 37.1°C) [15]	0.075 A/K (starting at 6.4°C) [15]	0.075 A/K (starting at -50.9°C) [15]

Table 150: 8EI2X2HWTS0.XXXX-1, 8EI4X5HWTS0.XXXX-1, 8EI8X8HWTS0.XXXX-1 - Technical data

Model number	8EI2X2HWTS0.XXXX-1	8EI4X5HWTS0.XXXX-1	8EI8X8HWTS0.XXXX-1
Reduction of continuous current depending on installation elevation			
Starting at 500 m above sea level	0.22 A_{eff} per 1000 m	0.45 A_{eff} per 1000 m	0.88 A_{eff} per 1000 m
Peak current per motor connection	6 / 6 / 6 A_{eff}	12.25 / 12.25 / 12.25 A_{eff}	24 / 24 / 24 A_{eff}
Peak power output	2.5 kW	5 kW [16)]	10 kW [16)]
Nominal switching frequency	5 kHz		
Possible switching frequencies [17)]	5 / 10 / 20 kHz [18)]		
Electrical stress of connected motor per IEC TS 60034-25	Limit value curve A		
Protective measures			
Overload protection	Yes		
Short circuit and ground fault protection	Yes		
Max. output frequency	598 Hz [19)]	598 Hz [20)]	
Variant			
U, V, W, PE	Male connector		
Shield connection	Yes		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	1.5 to 6 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Max. motor cable length depending on switching frequency			
Switching frequency 5 kHz	75 m [21)]		
Switching frequency 10 kHz	38 m [21)]		
Switching frequency 20 kHz	19 m [21)]		
Motor holding brake connection			
Quantity	3		
Output voltage [22)]	Depends on the input voltage on connector X2		
Continuous current	1.3 A		
Max. internal resistance	0.25 Ω		
Extinction potential	Approx. 30 V		
Max. extinction energy per switching operation	1.5 Ws		
Max. switching frequency	0.5 Hz		
Protective measures			
Overload and short-circuit protection	Yes		
Open circuit monitoring	Yes		
Undervoltage monitoring	Yes		
Response threshold for open circuit monitoring	Approx. 30 mA		
Response threshold for undervoltage monitoring	Approx. 23 V		
Max. cable length	75 m [23)]		
Braking resistor [24)]			
Peak power int./ext.	7 kW / 25 kW		
Continuous power int./ext.	150 W / 2 kW		
Minimum braking resistance (ext.)	25 Ω		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 4 mm²		
Approbation data			
UL/C-UL-US	24 to 8 AWG		
CSA	24 to 8 AWG		
Protective measures			
Overload protection	No		
Short circuit and ground fault protection	Short circuit protection: Yes Ground fault protection: No		
Max. cable length	3 m		
Fieldbus			
Type	POWERLINK V2 controlled node (CN)		
Variant	2x RJ45, shielded, 2-port hub		
Cable length	Max. 100 m between 2 stations (segment length)		
Transfer rate	100 Mbit/s		
Encoder interfaces			
Quantity	3		
Type	Digital multi-encoder interface, configurable [25)]		
Connections	8-pin female mini I/O connector		
Status indicators	None [26)]		
Electrical isolation			
Encoder - ACOPOS P3	No		
Max. encoder cable length	75 m Depends on the cross section of the power supply wires of the encoder cable [27)]		

Table 150: 8EI2X2HWTS0.XXXX-1, 8EI4X5HWTS0.XXXX-1, 8EI8X8HWTS0.XXXX-1 - Technical data

Model number	8EI2X2HWTS0.XXXX-1	8EI4X5HWTS0.XXXX-1	8EI8X8HWTS0.XXXX-1
Encoder power supply			
Output voltage	Configurable Typ. 11.45 V ± 0.1 V / 5.2 V ± 0.1 V [28][29]		
Load capacity	Max. 300 mA		
Sense lines	2, compensation of max. 2x 0.7 V		
Protective measures			
Short-circuit proof	Yes		
Overload-proof	Yes		
Synchronous serial interface			
Signal transmission	RS485 [30]		
Data transfer rate	Depends on the configured encoder type		
Differential voltage [31]			
Minimum	2.0 V		
Maximum	6.0 V		
Max. power consumption per encoder interface	$P_{ENCODER}$ [W] = U_{24V} [V] * ($I_{ENCODER}$ [A] * 0.7) + 0.5 W [32]		
Trigger inputs			
Quantity	2		
Circuit	Sink		
Electrical isolation			
Input - ACOPOS P3	Yes		
Input - Input	Yes		
Input voltage			
Nominal	24 VDC		
Maximum	30 VDC		
Switching threshold			
Low	<5 V		
High	>15 V		
Input current at nominal voltage	7 mA		
Switching delay			
Rising edge	<51 µs		
Falling edge	<52 µs		
Modulation compared to ground potential	Max. ±38 V		
Terminal connection cross section			
Flexible and fine-stranded wires			
With wire end sleeves	0.25 to 2.5 mm²		
Approbation data			
UL/C-UL-US	26 to 12 AWG		
CSA	26 to 12 AWG		
Max. cable length	100 m		
Support			
Motion system			
mapp Motion	5.00.0 and higher		
ACP10/ARNC0	3.14.1 and higher		3.14.0 and higher
Operating conditions			
Permissible mounting orientations			
Hanging vertically	Yes		
Standing horizontally	Yes		
Installation elevation above sea level			
Nominal	0 to 500 m		
Maximum	4000 m		
Pollution degree per EN 61800-5-1	2 (non-conductive pollution)		
Overvoltage category per EN 61800-5-1	III		
Degree of protection per EN 60529	IP20 [33]		
Ambient conditions			
Temperature			
Operation			
Nominal	5 to 40°C		
Maximum	55°C		
Storage	-25 to 55°C		
Transport	-25 to 70°C		
Relative humidity			
Operation	5 to 85%, non-condensing		
Storage	5 to 95%		
Transport	95% at 40°C		

Table 150: 8EI2X2HWTS0.XXXX-1, 8EI4X5HWTS0.XXXX-1, 8EI8X8HWTS0.XXXX-1 - Technical data

Model number	8EI2X2HWTS0.XXXX-1	8EI4X5HWTS0.XXXX-1	8EI8X8HWTS0.XXXX-1
Mechanical properties			
Dimensions			
Width	66 mm		
Height	374 mm		
Depth			
Wall mounting	258.5 mm (with 8EXA front cover: 261 mm)		
Weight	4 kg		

Table 150: 8EI2X2HWTS0.XXXX-1, 8EI4X5HWTS0.XXXX-1, 8EI8X8HWTS0.XXXX-1 - Technical data

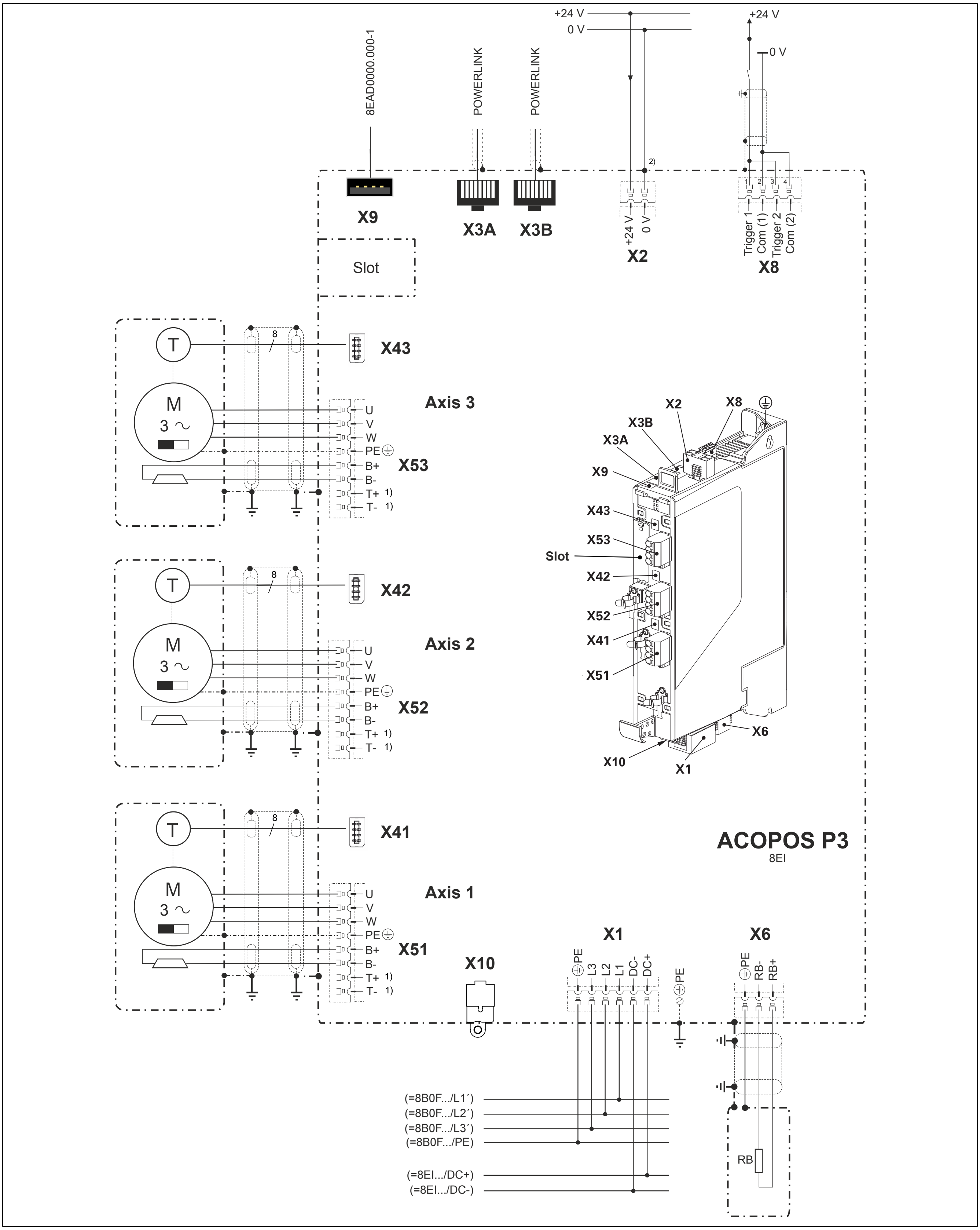
1) A line filter must be connected.
CE compliance can only be ensured by connecting a B&R line filter (8x0F...).
In extreme cases, using line filters from 3rd-party manufacturers can result in irreparable damage to the 8EI ACOPOS P3 servo drive.
2) P_{AVG} ... Average continuous power of the module
I_{AX1}, I_{AX2}, I_{AX3} ... RMS value of the current on axis 1, axis 2, axis 3
I_{BR1}, I_{BR2}, I_{BR3} ... Nominal current of the motor holding brake on axis 1, axis 2, axis 3
P_{VSLOT} ... Power dissipation of the 8EAC plug-in module
3) Maximum cable length between line filter and mains connection on the module.
4) Valid for a mains input voltage of ≥3x 400 VAC.
The sum of the continuous power values on all motor connections and the power of the DC bus connector is not permitted to exceed this value.
5) The continuous power is reduced as a percentage of the continuous current if the continuous current is subject to derating.
6) This value applies to unshielded wiring inside a control cabinet.
Maximum length of the DC bus wiring inside a control cabinet.
7) Current consumption depends on the configuration of the ACOPOS P3 8EI servo drive.
The inrush current of the 24 VDC power supply is not limited by the module.
8) Valid under the following conditions: 560 VDC DC bus voltage, 5 kHz switching frequency, 40°C ambient temperature, installation elevation <500 m above sea level, no derating due to cooling type.
9) The total continuous power of all motor connections is not permitted to exceed 3 kW. The continuous power is reduced as a percentage of the continuous current if the continuous current is subject to derating.
10) The total continuous power of all motor connections is not permitted to exceed 4 kW. The continuous power is reduced as a percentage of the continuous current if the continuous current is subject to derating.
11) The accuracy of the safe current is relevant for safety functions SLT and SBT, which are based on the safe current measurement. Safety functions SBT, SLT and SSO are available starting with hardware upgrade 1.10.2.0 and only for 8EI servo drives with 8ZELxxxx revision D0 or later. See the device information on the left side cover of the servo drive.
12) These values apply up to the continuous current specified in the technical data (taking into account the respective derating specifications).
13) The temperature specifications refer to the ambient temperature.
14) Value for the nominal switching frequency.
15) The module cannot supply the full continuous current at this switching frequency. This unusual value for the ambient temperature, at which derating of the continuous current must be taken into account, ensures that the derating of the continuous current can be determined in the same manner as at other switching frequencies.
16) The total peak power of all motor connections is not permitted to exceed 10 kW.
17) B&R recommends operating the module at its nominal switching frequency. Operating the module at a higher switching frequency for application-specific reasons reduces the continuous current and increases the CPU load.
18) A switching frequency of 20 kHz is not recommended when using safety function SLT, SBT or SSO since availability problems may occur.
19) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use in accordance with Council Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
20) The module's electrical output frequency (SCTRL_SPEED_ACT * MOTOR_POLEPAIRS) is monitored to protect against dual use per Regulation (EC) 428/2009 | 3A225. If the electrical output frequency of the module exceeds the limit value of 598 Hz uninterrupted for more than 0.5 s, then the current movement is aborted and error 6060 is output ("Power unit: Limit speed exceeded").
21) The sum of the length of all motor cables connected to this module is not permitted to exceed this value.
22) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified input voltage and wiring. For the operating voltage range of the holding brake, see the user documentation for the motor being used.
23) During the project development phase, it is necessary to check if the minimum voltage can be maintained on the holding brake with the specified cable length. For the permissible operating voltage range of the holding brake, see the user documentation for the motor being used.
24) There is a connection for external braking resistors. An internal braking resistor is available as an option.
25) The encoder type is not predefined from the factory. The encoder type necessary in each case must be configured in Automation Studio.
26) The direction of rotation of the encoder can be displayed on the 8EAD0000.000-1 display module.
27) The maximum encoder cable length l_{max} can be calculated as follows (the maximum permissible encoder cable length of 75 m is not permitted to exceeded):

$l_{max} = f / I_G * A * 1/(2*\rho)$

f ... (Output voltage of encoder interface [V] - Min. permissible supply voltage of connected encoder [V]) * 1.1
I_G ... Max. current consumption of connected encoder [A]
A ... Cross section of the power supply wires [mm²]
ρ ... Specific resistance [Ω mm²/m] (e.g. for copper: ρ = 0.0178)
28) The output voltage is not predefined from the factory (with the exception of encoder types EnDat 2.2 and HIPERFACE DSL). It must be configured in Automation Studio based on the encoder type. If no output voltage is configured, then the encoder will not be supplied by digital multi-encoder interface X4x. Power to the encoder can then be supplied externally.
29) Output voltage 5.2 V is only available under the following conditions:
- 8EI servo drive with 8ZECxxx revision D0 and higher - see the device information on the left side cover of the 8EI servo drive
- ACOPOS operating system 3.15.0 and higher (for 8EIxxxxxD... 2-axis modules and 8EIxxxxxT... 3-axis modules)
- ACOPOS operating system 3.17.0 and higher (for 8EIxxxxxS... 1-axis modules)
30) Except encoder type HIPERFACE DSL.
31) Values valid for clock output and data input. Except encoder type HIPERFACE DSL.
32) $I_{ENCODER}$ ... Current consumption of the encoder
U_{24V} ... Input voltage on the +24 VDC input of the module
33) The specified degree of protection is only met if either the slot cover is installed on the module or an 8EAC plug-in module is installed and suitable terminals are connected to all connectors and all fans are installed.

4.1.2.5 Wiring

4.1.2.5.1 Pinout overview



1) A temperature sensor does not need to be connected when using 8ECHxxx hybrid motor cables since the motor temperature is transferred digitally.
2) The COM connection on the X2 connector must be grounded to achieve a defined relationship between the signal ground and ground potential!

4.1.2.5.2 X1 connector - Pinout

Mains voltage 1x 110 to 230 VAC / 3x 200 to 230 VAC

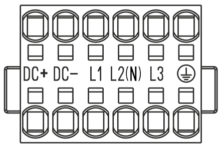
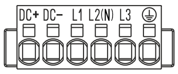
X1		Description	Function
		DC+	DC bus connection DC+
		DC-	DC bus connection DC-
		L1	Mains connection L1
		L2(N)	Mains connection L2(N)
		L3	Mains connection L3
		PE	Protective ground conductor

Table 151: Connector X1 - Pinout

Warning!

Only DC bus circuits of 8EI servo drives with the same supply voltage range are permitted to be connected.

Notice!

The max. permissible mains voltage for 8EIxxxM... servo drives is 230 VAC!
Connecting to mains voltages > 230 VAC will result in irreparable damage to the servo drive!

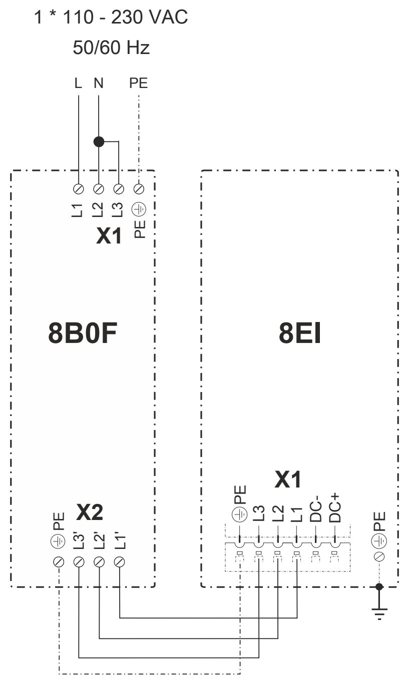


Figure 52: Mains connection 1x 110 - 230 VAC

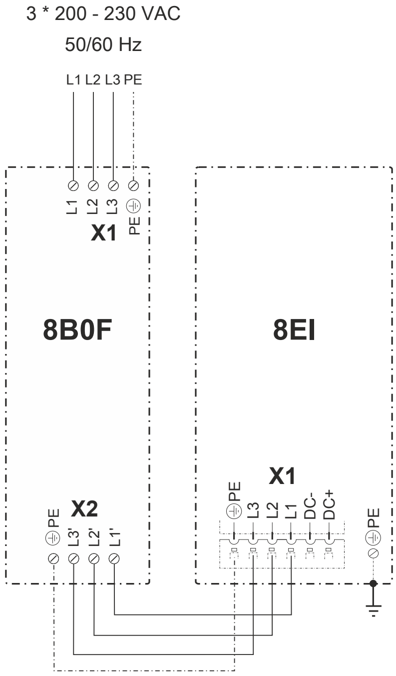


Figure 53: Mains connection 3x 200 - 230 VAC

Mains voltage 3x 200 to 480 VAC

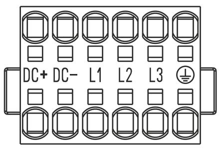
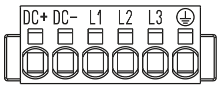
X1		Description	Function
		DC+	DC bus connection DC+
		DC-	DC bus connection DC-
		L1	Mains connection L1
		L2	Mains connection L2
		L3	Mains connection L3
		PE	Protective ground conductor

Table 152: Connector X1 - Pinout

Warning!

Only DC bus circuits of 8EI servo drives with the same supply voltage range are permitted to be connected.

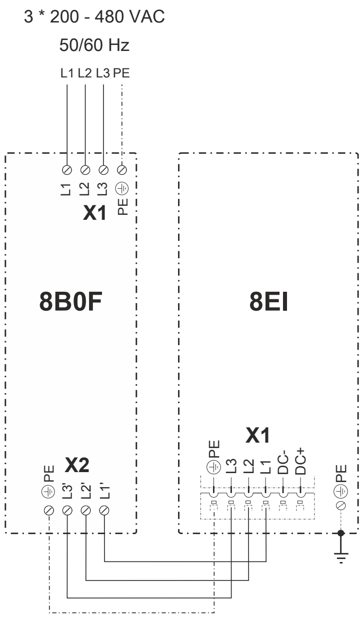


Figure 54: Mains connection 3x 200 - 480 VAC

4.1.2.5.3 Connector X2 - Pinout

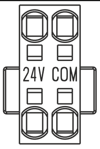
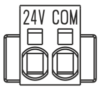
X2		Description	Function
		COM	0 V power supply
		24 V	+24 V power supply

Table 153: Connector X2 - Pinout

4.1.2.5.4 Connectors X3A, X3B - Pinout

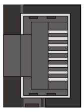
X3A, X3B	Pin	Description	Function
 1	1	RXD	Receive signal
	2	RXD\	Receive signal inverted
	3	TXD	Transmit signal
	4	Shield	Shield
	5	Shield	Shield
	6	TXD\	Transmit signal inverted
	7	Shield	Shield
	8	Shield	Shield

Table 154: X3A, X3B connectors - Pinout

4.1.2.5.5 X4x connector (digital multi-encoder interface) - Pinout

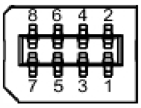
X4x	Pin	Name	Function
	1	U_P	Encoder power supply +12 V
	2	T	Clock output
	3	---	---
	4	T\	Clock output inverted
	5	---	---
	6	D	Data
	7	U_n	Encoder power supply 0 V
	8	D\	Data inverted

Table 155: X4x connector - Pinout

4.1.2.5.6 Connector X5x - Pinout

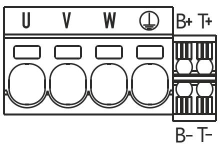
X5x	Description	Function
	B+	Brake +
	B-	Brake -
	T+	Temperature sensor + 1)
	T-	Temperature sensor - 1)
	PE	Protective ground conductor
	U	Motor connection U
	V	Motor connection V
	W	Motor connection W

Table 156: Connector X5x - Pinout

1) A temperature sensor does not need to be connected when using a hybrid motor cable solution since the motor temperature is transferred digitally.

Danger!

The connections for the motor temperature sensors and the motor holding brake are safely isolated circuits. These connections are therefore only permitted to be connected to devices or components that have sufficient isolation per IEC 60364-4-41 or EN 61800-5-1.

Information:

B&R recommends wiring the ACOPOS P3 X5x motor connectors in the following order:

1. **X51**
2. **X52**
3. **X53**

4.1.2.5.7 Connector X6 - Pinout

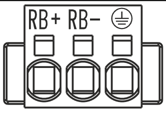
X6	Description	Function
	PE	Protective ground conductor
	RB-	Braking resistor -
	RB+	Braking resistor +

Table 157: Connector X6 - Pinout

Danger!

During operation, the contacts of connector X6 carry dangerous voltages greater than 60 VDC. Touching one of these contacts can result in a life-threatening electric shock. This could result in death or severe injury.

For this reason, terminal block 8TB3103.222A-20 or 8TB4103.222A-10 must always be connected to connector X6 during operation.

4.1.2.5.8 Connector X8 - Pinout

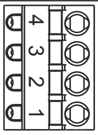
X8	Pin	Description	Function
	1	Trigger 1	Trigger 1
	2	COM (1)	Trigger 1 0 V
	3	Trigger 2	Trigger 2
	4	COM (2)	Trigger 2 0 V

Table 158: Connector X8 - Pinout

4.1.2.5.9 Connector X10 - Pinout

In preparation

4.1.3 Setting POWERLINK node numbers

ACOPOS P3 8EI servo drives do not have node number switches and are delivered with the node number set to 0.

There are 2 ways to set the node number:

- Setting with dynamic node allocation (DNA) in Automation Studio
- Setting with the 8EAD0000.000-1 display module

Information:

If an ACOPOS P3 8EI servo drive is supplied with 24 VDC and its node number is set to 0, then LED "PLK" is lit solid red.

Information:

Node numbers in the range 001 to 239 are permitted.

Node number 000 and in the range 240 to 255 are reserved and not permitted.

Information:

A node number set using the 8EAD0000.000-1 display module is only applied the next time the 24 VDC power supply of the ACOPOS P3 8E1 servo drive is switched back on.

Setting with dynamic node allocation (DNA)

Information:

The node number of the first ACOPOS P3 8EI servo drive in an ACOPOS P3 drive system can only be set using DNA if it is connected via POWERLINK directly to the controller or another POWERLINK-capable module (in DNA mode) that can switch hub ports (e.g. X20BC...).

If this is not the case, the node number of the first ACOPOS P3 8EI servo drive in an ACOPOS P3 drive system can only be set using the 8EAD000.0000-00 display module.

> **Information:**
>
> **Setting the node number using DNA only works on ACOPOS P3 8EI servo drives with node number 0 (factory setting).**

See also section "Dynamic node allocation (DNA)" in Automation Help.

Setting with the 8EAD0000.000-1 display module

See "Accessories / Display module 8EAD0000.000-1" in the ACOPOS P3 user's manual.

4.2 Installation

See ACOPOS P3 user's manual MAACPP3-ENG, chapter "Installation".

4.3 Dimensioning

See ACOPOS P3 user's manual MAACPP3-ENG, chapter "Dimensioning".

4.4 Wiring

See ACOPOS P3 user's manual MAACPP3-ENG, chapter "Wiring".

5 System characteristics

5.1 Integrated (network-based) safety technology - SafeMOTION

5.1.1 General information

5.1.1.1 ACOPOSmulti SafeMOTION and ACOPOSmotor SafeMOTION

SafeMOTION integrated safety technology is implemented using an integrated SafeMOTION module on ACOPOSmulti inverter modules and the ACOPOSmotor SafeMOTION inverter unit.

One SafeMOTION module is integrated in the safe drive for each safe axis.

A SafeMOTION module is the equivalent of a safe node and performs the safety functions on the drive.

Only 1-axis modules are available for ACOPOSmulti SafeMOTION SinCos.

> **Information:**
>
> **ACOPOSmulti SafeMOTION EnDat 2.2**
>
> **A safe 2-axis module includes two SafeMOTION modules. It is therefore the equivalent of one POWERLINK node and two safe nodes. This should be taken into consideration when designing the system.**

> **Information:**
>
> **The user is not able to connect or disconnect the SafeMOTION module! This means that a standard axis (ACOPOSmulti, ACOPOS P3, ACOPOSmotor) cannot be retrofitted!**

5.1.1.2 ACOPOS P3 SafeMOTION

On ACOPOS P3 SafeMOTION servo drives, SafeMOTION integrated safety technology is implemented as an integrated option.

On ACOPOS P3 servo drives, up to 3 axes are integrated in a SafeMOTION module.

An ACOPOS P3 SafeMOTION servo drive corresponds to a safe node (regardless of the number of axes integrated in a SafeMOTION module) and executes the safety function on the drive.

> **Information:**
>
> **The user is not able to connect or disconnect the SafeMOTION module! This means that a standard axis (ACOPOSmulti, ACOPOS P3, ACOPOSmotor) cannot be retrofitted!**

5.1.2 Safety functions

The following safety functions are supported by the SafeMOTION module:

Safety function	ACOPOSmulti SafeMOTION		EN ISO 13849-1		EN 61508 / EN 62061		Safe Encoder evaluation Necessary
	EnDat 2.2	SinCos	EnDat 2.2	SinCos	EnDat 2.2	SinCos	
	Starting in Safety Release						
Safe Torque Off (STO)	R 1.3	R 1.4	PL e / Cat. 4	PL e / Cat. 4	SIL 3	SIL 3	No
Safe Torque Off One Channel (STO1)	R 1.3	R 1.4	PL d / Cat. 3	PL d / Cat. 3	SIL 2	SIL 2	No
Safe Operation Stop (SOS)	R 1.3	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safe Stop 1 (SS1)	R 1.3	R 1.4	Time-based monitoring: PL e / Cat. 4 Ramp-based monitoring: PL d / Cat. 3	Time-based monitoring: PL e / Cat. 4 Ramp-based monitoring: Max. PL e / Cat. 4, depends on the encoder used	Time-based monitoring: SIL 3 Ramp-based monitoring: SIL 2	Time-based monitoring: SIL 3 Ramp-based monitoring: Max. SIL 3, Depends on the encoder used	Time-based monitoring: No Ramp-based monitoring: Yes
Safe Stop 2 (SS2)	R 1.3	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safely Limited Speed (SLS)	R 1.3	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safe Maximum Speed (SMS)	R 1.3	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safe Direction (SDI)	R 1.3	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safely Limited Increment (SLI)	R 1.3	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safely Limited Acceleration (SLA)	R 1.9	R 1.9	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safe Brake Control (SBC)	R 1.3	R 1.4	PL d / Cat. 3	PL d / Cat. 3	SIL 2	SIL 2	No
Safely Limited Position (SLP)	R 1.4	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safe Maximum Position (SMP)	R 1.4	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safe Homing	R 1.4	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safe Brake Test (SBT)	-	R 1.7	-	Max. PL d / Cat. 3, depends on the encoder used	-	Max. SIL 2, Depends on the encoder used	Yes
Remanent Safe Position (RSP)	R 1.9	-	PL d / Cat. 3	-	SIL 2	-	Yes

Table 159: ACOPOSmulti SafeMOTION: Safety functions and associated safety levels

Safety function	ACOPOSmotor SafeMOTION	EN ISO 13849-1	EN 61508 / EN 62061	Safe Encoder evaluation Necessary
	Starting in Safety Release			
Safe Torque Off (STO)	R 1.10	PL e / Cat. 4	SIL 3	No
Safe Torque Off One Channel (STO1)	R 1.10	PL d / Cat. 3	SIL 2	No
Safe Operation Stop (SOS)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Stop 1 (SS1)	R 1.10	Time-based monitoring: PL e / Cat. 4 Ramp-based monitoring: PL d / Cat. 3	Time-based monitoring: SIL 3 Ramp-based monitoring: SIL 2	Time-based monitoring: No Ramp-based monitoring: Yes
Safe Stop 2 (SS2)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safely Limited Speed (SLS)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Maximum Speed (SMS)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Direction (SDI)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safely Limited Increment (SLI)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safely Limited Acceleration (SLA)	R 1.10	PL d / Cat. 3	SIL 2	Yes

Table 160: ACOPOSmotor SafeMOTION: Safety functions and associated safety levels

Safety function	ACOPOSmotor SafeMOTION	EN ISO 13849-1	EN 61508 / EN 62061	Safe Encoder evaluation Necessary
Safe Brake Control (SBC) [1]	R 1.10	PL d / Cat. 3	SIL 2	No
Safely Limited Position (SLP)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Maximum Position (SMP)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Homing	R 1.10	PL d / Cat. 3	SIL 2	Yes
Remanent Safe Position (RSP)	R 1.10	PL d / Cat. 3	SIL 2	Yes

Table 160: ACOPOSmotor SafeMOTION: Safety functions and associated safety levels

1) Safety function SBC does not apply to the motor holding brake integrated in the ACOPOSmotor SafeMOTION; it is not safety-related.

Safety function	ACOPOS P3 SafeMOTION	EN ISO 13849-1	EN 61508 / EN 62061	Safe Encoder evaluation Necessary
	EnDat 2.2			
	Starting with hardware upgrade			
Safe Torque Off (STO)	1.10.x.x	PL e / Cat. 4	SIL 3	No
Safe Torque Off One Channel (STO1)	1.10.x.x	PL d / Cat. 3	SIL 2	No
Safe Operation Stop (SOS)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safe Stop 1 (SS1)	1.10.x.x	Time-based monitoring: PL e / Cat. 4 Ramp-based monitoring: PL d / Cat. 3	Time-based monitoring: SIL 3 Ramp-based monitoring: SIL 2	Time-based monitoring: No Ramp-based monitoring: Yes
Safe Stop 2 (SS2)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safely Limited Speed (SLS)	1.10.x.x[2]	PL d / Cat. 3	SIL 2	Yes[1]
Safe Maximum Speed (SMS)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safe Direction (SDI)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safely Limited Increment (SLI)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safely Limited Acceleration (SLA)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safe Brake Control (SBC)	1.10.x.x	PL d / Cat. 3	SIL 2	No
Safely Limited Position (SLP)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safe Maximum Position (SMP)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safe Homing	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safe Brake Test (SBT)	1.10.2.x	PL d / Cat. 3	SIL 2	Yes
Safely Limited Torque (SLT)	1.10.2.x	PL d / Cat. 3	SIL 2	No
Remanent Safe Position (RSP)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes

Table 161: ACOPOS P3 SafeMOTION: Safety functions and associated safety levels

1) Safe encoder evaluation is not necessary in conjunction with SSO.
2) Supported in hardware upgrade 1.10.2.x and later in conjunction with SSO.

For details about the individual safety functions, see section 6 "Safety technology" on page 282.

5.2 Integrated safety technology

Seamless integration of safety technology in the standard application is a reality with B&R's safety technology products. This allows fixed wiring to be replaced by safe data transfer via the existing machine bus system. Flexibly configured or programmed safety behavior can be adapted optimally to various safety situations. Complete diagnostic information about safety components accessible via the machine bus system provides detailed data about the state of the machine.

Insufficient protection from manipulation and the inadequacy of existing safety solutions provide some justification for dangerous behavior when it comes to operating the machine. The possibilities provided by the latest safety technology allow considerable potential for improvement here. In the pursuit of improving machine safety, safety technology guidelines are continually updated according to the current technological situation. Consequently, improvements become mandatory. B&R's integrated safety technology is state-of-the-art and meets both current and expected future demands on safety components.

Safety shutdowns do not always have to involve a full machine stop. When opening a protective cover, it is often sufficient to reduce the speed. Smart, safe reactions to various situations provide safety without having to stop the production process. The machine does not need to be emptied and set up again, and manipulation is not necessary. This results in real advantages for the user that can be implemented with programmable safety behavior.

Integrated safety technology products are certified for use in safety applications up to:

- EN ISO 13849, PL e / Cat. 4
- IEC 62061, SIL 3
- IEC 61508, SIL 3
- IEC 61511, SIL 3

The actual level of safety achieved depends on the respective safety function and the components being used!

A cycle time of 400 µs for SIL 3 SafeMOTION safety applications is a new dimension for safe communication. Response times decrease by a factor of 10, and the advantages of hard-wired solutions are combined with the possibilities of advanced, integrated and intelligent safety bus technology. POWERLINK and openSAFETY accomplish all this using only standard Ethernet mechanisms. As a result, these protocols can be combined with all conventional and, more important, newer Ethernet profiles. openSAFETY is the fastest and most flexible real-time safety bus system on the market.

The reduction to a single cable allows safety-related data to be transferred using the existing infrastructure. Additional cabling of a safe line is not necessary. Transparent and non-reactive access of secure data is an integral part of functional machine control. Complicated communication mechanisms between the safety application and standard application are also no longer necessary. Smart, safe reactions instead of hard machine stops provide advantages for processes, help to avoid manipulation and therefore increase the value of machines.

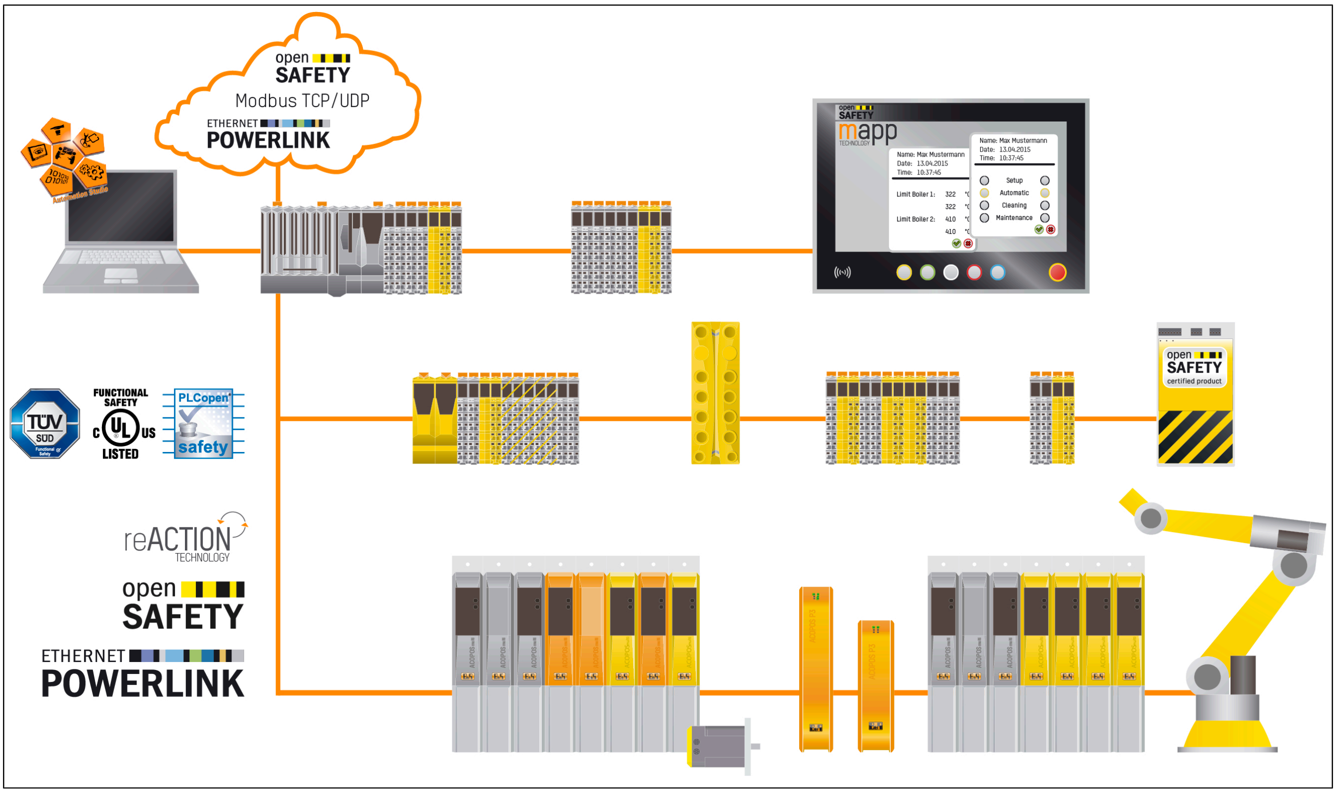


Figure 55: Integrated safety technology - Topology

5.3 System requirements

Integrated safety technology requires the use of the following software and hardware:

- POWERLINK V2
- Automation Studio V3.0.80 or higher
- Automation Studio V4.2.5.x or higher (Safety Release 1.10 or later)
- Automation Runtime V3.00 or higher
- ACP10 software V2.180 or higher (for Safety Release R1.3 ACOPOSmulti SafeMOTION EnDat 2.2)
- ACP10 software V2.250 or higher (starting with Safety Release R1.3 ACOPOSmulti SafeMOTION EnDat 2.2)
- ACP10 software V2.391 or higher (starting with Safety Release R1.3 ACOPOSmulti SafeMOTION SinCos)
- ACP10 software V2.480 or higher (ACOPOSmulti SafeMOTION Safety Release R1.9 or later)
- ACP10 software V3.140 or higher (Safety Release 1.10 ACOPOSmotor SafeMOTION or later)
- ACP10 software V3.161 or higher (Safety Release 1.10 ACOPOS P3 SafeMOTION or later)
- ACP10 software V5.040 or higher (hardware upgrade 1.10.2 ACOPOS P3 SafeMOTION or later)
- ACP10 software V5.051 or higher (hardware upgrade 1.10.2 or later if library "SafeMC" is required for safe machine options)
- SG4 CPUs

5.4 System limits

The following limitations exist when using SafeMOTION modules:

- A SafeMOTION module basically corresponds to a safe node[3]. Additionally, each drive module equates to **one POWERLINK node**.
- A SafeMOTION module can only communicate safely with one (1) SafeLOGIC controller with SafeMOTION support (see SafeLOGIC data sheets X20SL80xx, X20SL81xx and X20SLXx10 on www.br-automation.com). It is not possible for a SafeMOTION module to communicate safely with multiple SafeLOGIC controllers or with other safe modules (other SafeIO, SafeMOTION, etc.).
- The output-side payload data size of the SafeLOGIC controller is limited to 1490 bytes. Among other things, this limitation reduces the resulting number of usable SafeIO or SafeMOTION modules during SafeLOGIC-to-SafeLOGIC communication.
- The safe state is implemented in B&R safety modules by cutting off the output. This is a design feature of the modules and cannot be changed.
  This is particularly important for SafeMOTION modules since the safe state cuts off the torque on the motor!

Danger!

After the safe state (STO) is activated or in state FAIL SAFE, the drive is not supplied with power; the motor therefore no longer exerts torque or force.

If the motor was moving before STO is activated, it is only stopped by a safe motor holding brake (if available) or by the friction of the complete system!

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

Danger!

The safety response time must be taken into consideration since this has a substantial effect on the residual distances and remaining times to be considered!

In order to calculate the total safety response time, the user must validate the rundown time of the complete system! For the switch-off time, see 5.5 "Safety response time" on page 269.

[3] ACOPOSmulti SafeMOTION inverter modules: A SafeMOTION module is integrated into a single-axis inverter module, i.e. **one safe node**. A 2-axis inverter module has two integrated SafeMOTION modules, i.e. **two safe nodes**.

5.5 Safety response time

The safety response time is the time between the arrival of the signal on the input channel and the output of the cutoff signal on the output.

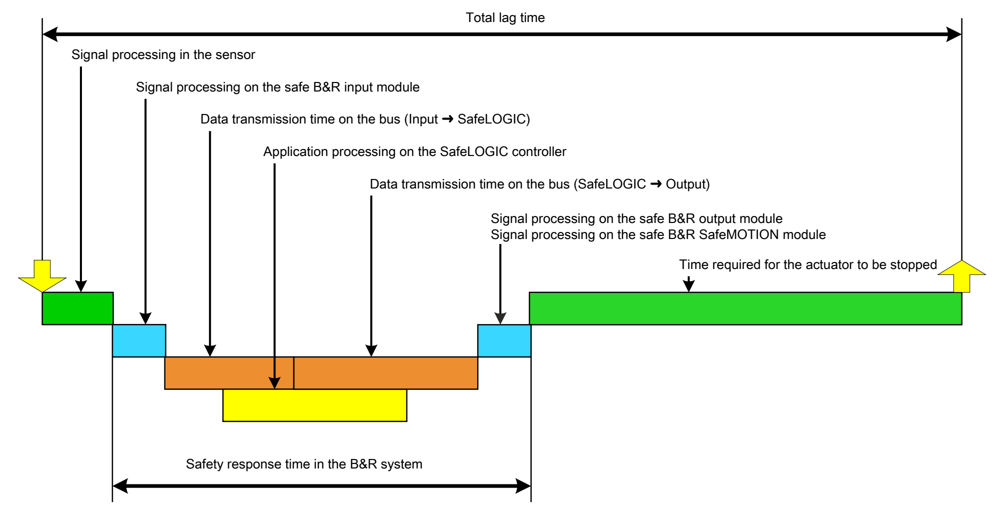


Figure 56: Total lag time

As illustrated in the figure, the safety response time in the B&R system is composed of the following partial response times:

- Signal processing on the safe B&R input module
- Data transmission time on the bus (Input → SafeLOGIC)
- Data transmission time on the bus (SafeLOGIC → Output)
- Signal processing in the safe B&R output module (or safe B&R SafeMOTION module)

Danger!

The following sections are dedicated exclusively to the safety response time in the B&R system. When assessing the complete safety response time, the user must include signal processing in the sensor as well as the time until the actuator is stopped.

Be sure to validate the total lag time on the system!

Information:

The safety response time in B&R products already contains all delays caused by sampling input data (sampling theorem).

5.5.1 Signal processing on the safe B&R input module

The maximum I/O update time in the "I/O update time" chapter for the respective module must be taken into account when processing signals in the safe B&R input module.

5.5.2 Data transmission time on the bus

The following relationship must be taken into consideration for the data transmission time on the bus:

- The time needed to transfer data from the input to the SafeLOGIC controller or to the output depends on the sum of the cycle times and CPU copy times in effect on the transfer line.
- POWERLINK MN (managing node, standard CPU) settings are important for the actual timing on the bus, but they cannot be used from a safety point of view since the values can be changed at any time in the course of modifications made outside of the safety application.
- In the SafeLOGIC controller, data transmission times are monitored on the bus using openSAFETY services. The time needed to process the application on the SafeLOGIC controller is taken into account in this test (system-dependent). Monitoring is defined in SafeDESIGNER using the parameters in parameter group "Safety Response Time".

Information:

The safety components located in this network segment could be cut off by the SafeLOGIC controller if modified parameters on the POWERLINK MN alter the data transmission times on the bus so that they lie outside of the SafeDESIGNER parameters defined in parameter group "Safety Response Time".

Information:

The safety components located in this network segment could be cut off by the SafeLOGIC controller if EMC disturbances cause data failures that fall outside of the SafeDESIGNER parameters defined in parameter group "Safety Response Time".

Calculating the maximum data transmission time - up to Release 1.9:

- The total max. data transmission time on the bus is calculated by adding parameter "Worst_Case_Response_Time_us" for the safe input module and parameter "Worst_Case_Response_Time_us" for the safe output module. When doing this, be sure to check parameter "Manual_Configuration". If parameter "Manual_Configuration" is set to "No", the value specified for parameter "Default_Worst_Case_Response_Time_us" is used.
- **Special case: Local inputs on the X20SLX module:**
  The total max. data transmission time on the bus is calculated by adding parameter "Cycle_Time_max_us" + 2000 µs and parameter "Worst_Case_Response_Time_us" for the safe output module. When doing this, be sure to check parameter "Manual_Configuration". If parameter "Manual_Configuration" is set to "No", the value specified for parameter "Default_Worst_Case_Response_Time_us" is used.

Calculating the maximum data transmission time - Release 1.10 and later:

The following parameters are relevant for calculating the data transmission time between the safe input module and safe output module; parameter "Manual Configuration" deserves special attention.

- Relevant parameters for "Manual Configuration = No":
  - "PacketLoss1": Parameter "Default Additional Tolerated Packet Loss" of group "Safety Response Time Defaults" of the SafeLOGIC controller
  - "DataDuration1": Parameter "Default Safe Data Duration" of group "Safety Response Time Defaults" of the SafeLOGIC controller
  - "NetworkSyncCompensation1": 12 ms
  - "PacketLoss2": Same as "PacketLoss1"
  - "DataDuration2": Same as "DataDuration1"
  - "NetworkSyncCompensation2": Same as "NetworkSyncCompensation1"
- Relevant parameters for "Manual Configuration = Yes":
  - "PacketLoss1": Parameter "Additional Tolerated Packet Loss" of group "Safety Response Time" of the safe input module
  - "DataDuration1": Parameter "Safe Data Duration" of group "Safety Response Time" of the safe input module
  - "NetworkSyncCompensation1": 12 ms
  - "PacketLoss2": Parameter "Additional Tolerated Packet Loss" of group "Safety Response Time" of the safe output module
  - "DataDuration2": Parameter "Safe Data Duration" of group "Safety Response Time" of the safe output module
  - "NetworkSyncCompensation2": Same as "NetworkSyncCompensation1"
- **Special case: Local inputs on the X20SLX module:**
  - "PacketLoss1": 0
  - "DataDuration1": Parameter "Cycle Time max" of group "Module Configuration" of the X20SLX + 2000 µs
  - "NetworkSyncCompensation1": 0 ms
- **Special case: Local outputs on the X20SLX module:**
  - "PacketLoss2": 0
  - "DataDuration2": Parameter "Cycle Time max" of group "Module Configuration" of the X20SLX + 2000 µs
  - "NetworkSyncCompensation2": 0 ms
- **Special case: Linking local inputs with local outputs on the X20SRT module:**
  - "PacketLoss1": 0
  - "PacketLoss2": 0
  - "DataDuration1": Parameter "Cycle time" of group "General"
  - "DataDuration2": Parameter "Cycle time" of group "General"
  - "NetworkSyncCompensation1": 0 ms
  - "NetworkSyncCompensation2": 0 ms

The following equation is used to calculate the maximum data transmission time between the safe input module and safe output module:

Maximum data transmission time = (PacketLoss1+1)* DataDuration1 + NetworkSyncCompensation1 + (PacketLoss2+1)* DataDuration2 + NetworkSyncCompensation2

Information:

In addition to the data transmission time on the bus, the time for signal processing in the safe B&R input and output module must be taken into account (see section "Safety response time").

Information:

For more information about the actual data transmission time, see Automation Help, section Diagnostics and service -> Diagnostics tools -> Network analyzer -> Editor -> Calculation of safety runtime. The cycle time of the safety application must also be added.

5.5.3 Signal processing on the safe B&R output module

The maximum I/O update time in the "I/O update time" chapter for the respective module must be taken into account when processing signals in the safe B&R output module.

5.5.4 Signal processing on the safe B&R SafeMOTION module

The duration of signal processing in the event of a function request depends on the drive module, see Tab. 162 "Error response times" on page 273.

In addition to the signal processing, however, the duration of the communication between the POWERLINK interface and the SafeMOTION module must also be taken into account. In the worst case, this can be 1600 µs.

Safe error response time

In addition to the signal processing duration in functional situations, the safe error response time is also relevant when setting up safety equipment.

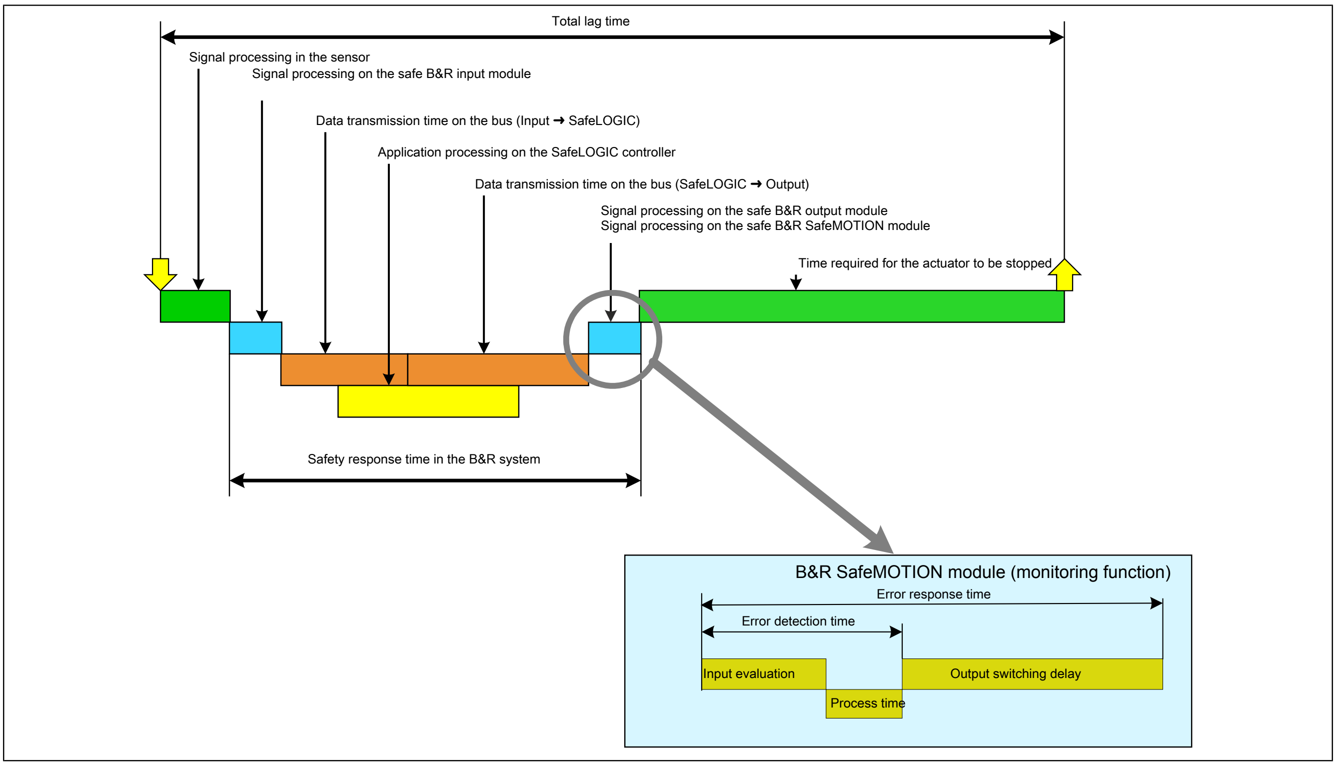


Figure 57: Safe error response time

The safe error response time plays a role if the currently monitored limit is exceeded when a safety function is activated on the SafeMOTION module.

The safe error response time includes:

- Error detection time (input evaluation + process time on the SafeMOTION module)
- Output switching delay

	ACOPOSmulti EnDat 2.2	ACOPOSmulti SinCos	ACOPOSmotor	ACOPOS P3 - 1	ACOPOS P3 -2/3
Process time (functions except SLT) [µs]	800	800	800	800	1600
Process time SLT (SLT) [µs]	-	-	-	200	400
Input evaluation (position) [µs]	200 + Process time	200 + Process time	200 + Process time	200 + Process time	200 + Process time
Input evaluation (speed) [µs]	200 + Process time * 1.5	200 + Process time * 1.5	200 + Cycle * 1.5	200 + Process time * 1.5	200 + Process time * 1.5
Input evaluation (speed with SSO) [µs]	-	-	-	900 + Process time * 2.5	900 + Process time * 2.5
Input evaluation (torque) [µs]	-	-	-	400 + Process time SLT * 2	400 + Process time SLT * 2
Output switching delay (pulse disabling) [µs]	5000	5000	5000	2000	2000
Output switching delay (brake output) [µs]	0	0	0	0	0

Table 162: Error response times

	ACOPOSmulti EnDat 2.2	ACOPOSmulti SinCos	ACOPOSmotor	ACOPOS P3 - 1	ACOPOS P3 -2/3
Error response time (position functions) [µs]	6800	6800	6800	3800	5400
Error response time (speed functions) [µs]	7200	7200	7200	4200	6200
Error response time (SSO speed functions) [µs]	-	-	-	5700	8500
Error response time (torque functions) [µs]	-	-	-	2800	3200
Error response time (worst case) [µs]	7200	7200	7200	4200	6200
Error response time (SSO worst case) [µs]	-	-	-	5700	8500

Table 162: Error response times

Danger!

For the worst-case safe error response time on the SafeMOTION module, see Tab. 162 "Error response times" on page 273.

When setting up the safety measures, the assumption must be that the drive will accelerate to its maximum within this amount of time.

This speed must be considered together with the speed when the safety function is violated in order to determine the maximum possible speed when coasting to a stop!

In addition, the error response time for determining the residual distance must be used when an error occurs in order to determine the maximum distance by which a monitored position limit can be exceeded!

Danger!

For the worst-case safe error response time on the SafeMOTION module, see Tab. 162 "Error response times" on page 273.

For the design of safety equipment, it must be assumed that limitation of the torque for the drive cannot be ensured within this time.

The resulting achievable change in angular momentum must be determined in a risk analysis and is not permitted to result in any hazard!

I/O update time

For the I/O update times of the safe B&R SafeMOTION module, see Tab. 163 "Maximum I/O update time" on page 275 for all drive modules.

Term definition

I update time	Time until the encoder data is on the bus to the SL controller (when using the position/speed in the SL controller)
O update time	Time until the data from the bus results in a reaction (time until a requested STO on the module is triggered)

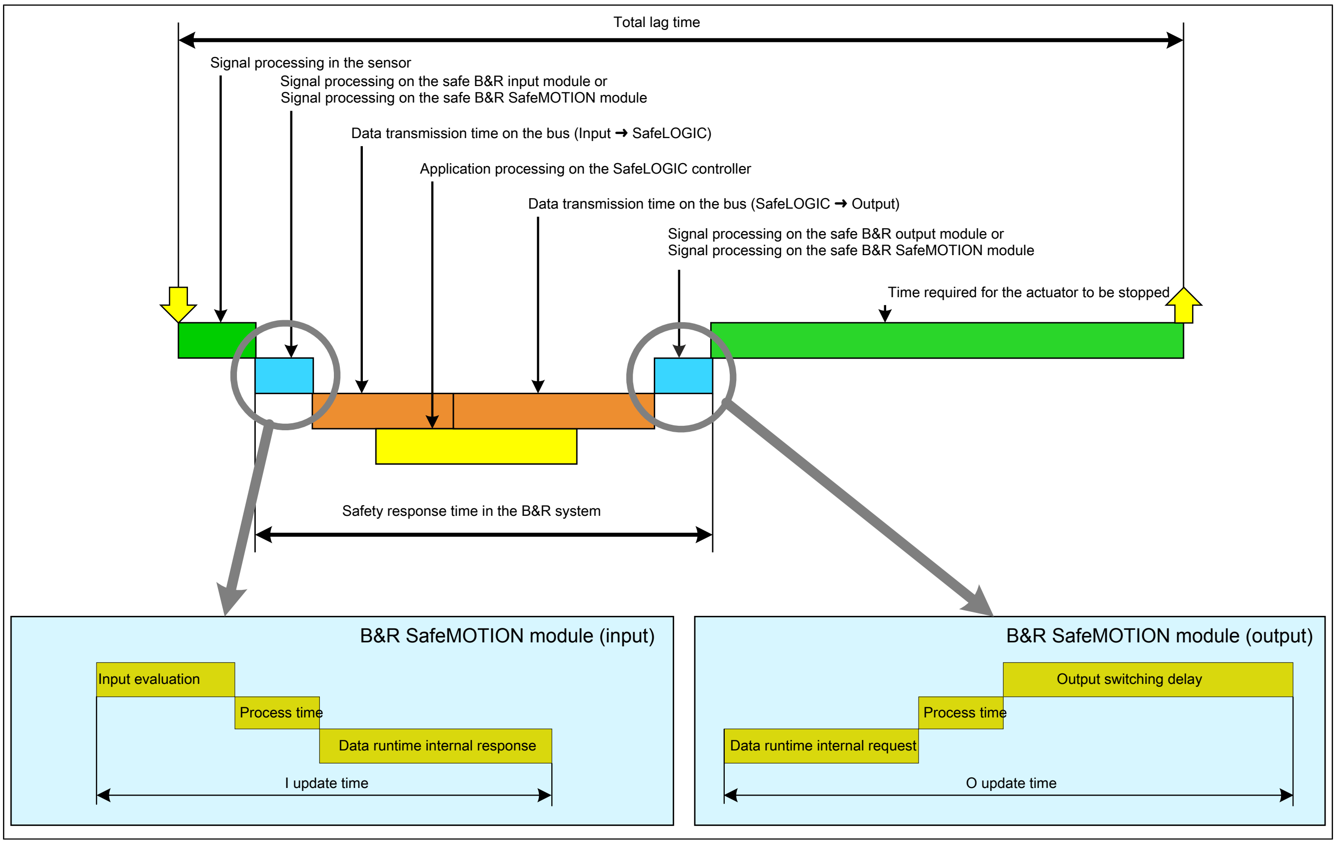


Figure 58: I/O update times

	ACOPOSmulti EnDat 2.2	ACOPOSmulti SinCos	ACOPOSmotor	ACOPOS P3 - 1	ACOPOS P3 -2/3
Data runtime internal request [µs]	1200	1200	1200	1250	1250
Data runtime internal response [µs]	1600	1600	1600	1550	1550
I update time (position) [µs]	3400	3400	3400	3350	4950
I update time (speed) [µs]	3800	3800	3800	3750	5750
I update time (speed at SSO) [µs]	-	-	-	5250	8050
O update time (STO / pulse disabling) [µs]	7000	7000	7000	4050	4850
O update time (SBC / holding brake output) [µs]	2000	2000	2000	2050	2850

Table 163: Maximum I/O update time

5.5.5 Calculating the safety response time

Information:

The information in this section applies only up to SafeDESIGNER 4.1.x.

The safety response time can be calculated using the Response Time Calculator. This tool can be opened with "Project → Response Time Calculator".

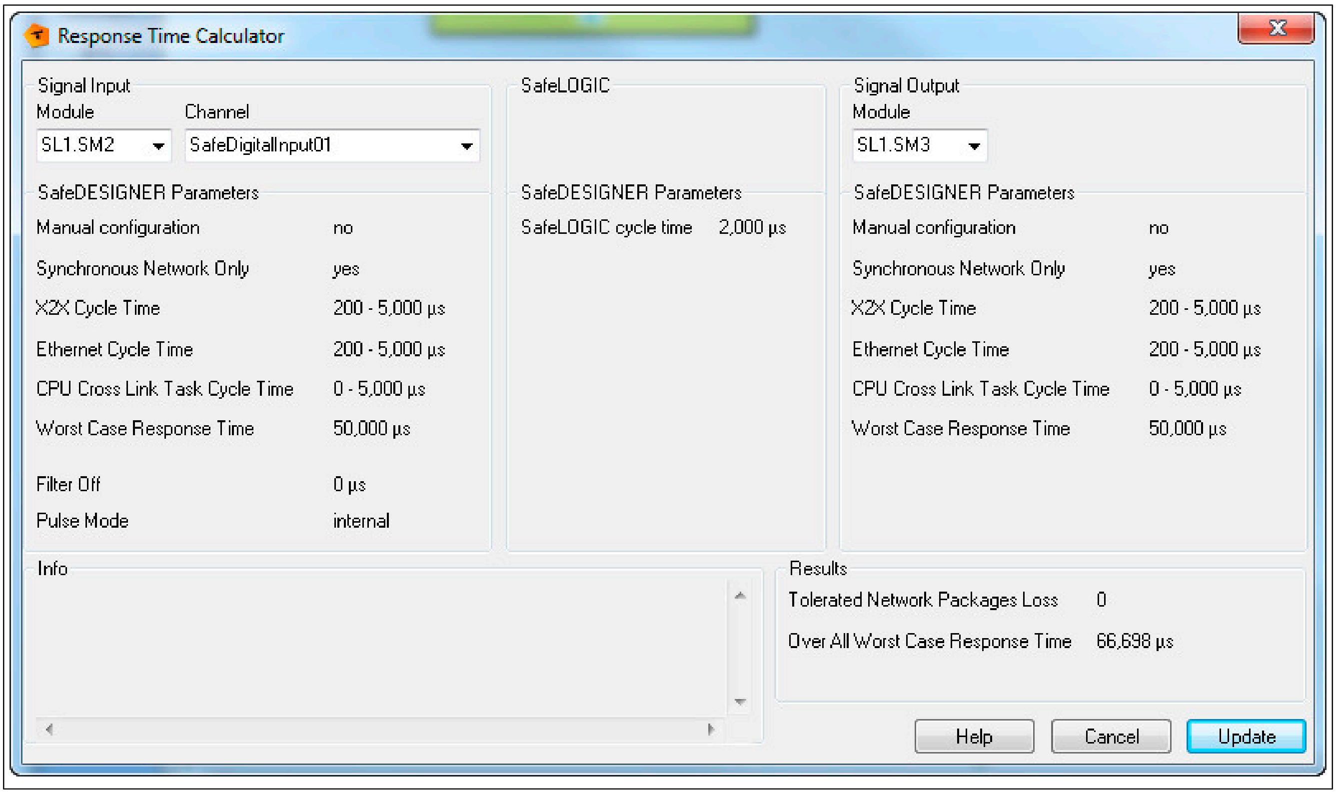


Figure 59: Response Time Calculator

This tool takes the values set in SafeDESIGNER and uses them to calculate the total response time and the tolerated packet loss on the network.

The modules relevant for the calculation can be selected in the "Signal input" and "Signal output" section. The values that are set accordingly are automatically shown in SafeDESIGNER and the total response time is calculated.

If the values set in SafeDESIGNER for the response time calculation result in a longer maximum response time than is set in SafeDESIGNER, the calculation is canceled and the error is shown in the "Info" field.

SafeDESIGNER parameters can also be changed with the dialog box window open. The values are applied either after changing which inputs/outputs are selected or after updating using the "Refresh" button.

Input fields:

Input field	Value	Function	Corresponding SafeDESIGNER parameters
Synchronous network only	Yes	All networks involved in data transfer are synchronous.	Synchronous_Network_Only = Yes
	No	At least one of the networks involved in data transfer is not synchronous.	Synchronous_Network_Only = No
X2X cycle time	200-30,000 µs	X2X cycle time entry for checking the data transmission time on the SafeLOGIC controller	Min_X2X_CycleTime_us Max_X2X_CycleTime_us
Ethernet cycle time	200-30,000 µs	POWERLINK cycle time entry for checking the data transmission time on the SafeLOGIC controller	Min_Powerlink_CycleTime_us - Max_Powerlink_CycleTime_us
CPU cross link task cycle time	0-30,000 µs	Cycle time entry of the CPU cross link task for checking the data transmission time in the SafeLOGIC controller. See the table below.	Min_CPU_CrossLinkTask_CycleTime_us - Max_CPU_CrossLinkTask_CycleTime_us
Response time	3000-500,000 µs	Limit value for monitoring the data transmission time on the bus	Worst_Case_Response_Time_us
Filter off	0	A switch-off filter is not being used on the input module.	Filter_Off_us
	1-500,000 µs	A switch-off filter is being used on the input module.	
Pulse mode	External	"External pulse signals" mode is being used on the input module.	Pulse_Mode = External
	Internal	"Internal pulse signals" mode is being used on the input module.	Pulse_Mode = Internal
	None	"External pulse signals" mode is not being used on the input module.	Pulse_Mode = No pulse
SafeLOGIC cycle time	800-20,000 µs	SafeLOGIC cycle time parameter "Cycle_Time_us" from SafeDESIGNER in µs.	Cycle_Time_us

Table 164: Fields in the "Response Time Calculator"

If the SafeLOGIC controller is on a different POWERLINK interface than the SafeIO modules, then the data must be copied to the CPU on its way from the SafeIO modules to the SafeLOGIC controller. An internal system task (CPU_CrossLinkTask) handles this copy procedure. The cycle time of this task is automatically assigned by the system.

It is important to know the configuration options of CPU_CrossLinkTask for monitoring data transmission time on the SafeLOGIC controller:

Min. CPU cross link task	Max. CPU cross link task	Description
Value > 0	Value > 0	Data is always copied via the CPU. Application situations where data is not copied are detected by the SafeLOGIC controller and registered as errors due to the very short runtime.
Value > 0	0	Not a valid combination
No	Value > 0	Runtime monitoring in the SafeLOGIC controller accepts application situations where data is copied as well as application situations where it is not.
0	0	Data is never copied via the CPU. Application situations where data is copied are detected by the SafeLOGIC controller and registered as errors due to the very long runtime.

Table 165: Meaning of "Min./Max. CPU" parameters

Output fields:

Output field	Value	Function	Corresponding SafeDESIGNER parameters
Tolerated network packages loss	0-10	Number of lost packets that are tolerated without cutting off the safety function	-
Total response time	- -	Resulting safety response time in the B&R system.	-

Table 166: Output fields in the "Response time calculator"

5.5.6 Parameters for the safety response time in SafeDESIGNER

The parameters for the safety response time are generally configured in the same way for all stations involved in the application. For this reason, these parameters are configured for the SafeLOGIC controller in SafeDESIGNER.

For application situations in which individual safety functions require optimal response time behavior, the parameters for the safety response time can be configured individually on the respective module.

The parameters and their limits for the SafeMOTION module are described below for each specific module.

Up to SafeDESIGNER 4.1.x:

<table>
<tr><th>Parameter</th><th>Description</th><th>Default value</th><th>Unit</th></tr>
<tr><td rowspan="2">Manual_Configuration</td><td>This parameter makes it possible to manually and individually configure the safety response time for the module.

The parameters for the safety response time are generally configured in the same way for all stations involved in the application. For this reason, these parameters are configured for the SafeLOGIC controller in SafeDESIGNER. For application situations in which individual safety functions require optimal response time behavior, the parameters for the safety response time can be configured individually on the respective module.</td><td>No</td><td>-</td></tr>
<tr><td colspan="3"><table><tr><th>Parameter value</th><th>Description</th></tr><tr><td>Yes</td><td>Data from the module's "Safety_Response_Time" group is used to calculate the safety response time for the module's signals.</td></tr><tr><td>No</td><td>The parameters for the safety response time are taken from the "Safety_Response_Time" group on the SafeLOGIC controller.</td></tr></table></td></tr>
<tr><td rowspan="2">Synchronous_Network_Only</td><td>This parameter determines the synchronization characteristics of the network being used.</td><td>Yes</td><td>-</td></tr>
<tr><td colspan="3"><table><tr><th>Parameter value</th><th>Description</th></tr><tr><td>Yes</td><td>In order to calculate the safety response time, networks must be synchronous and their cycle times must either be the same or an integer ratio of the cycle times.</td></tr><tr><td>No</td><td>No requirement for synchronization of the networks</td></tr></table></td></tr>
<tr><td>Max_X2X_CycleTime_us</td><td>This parameter specifies the maximum X2X cycle time used to calculate the safety response time.
• Permissible values: 200 to 25,000 µs</td><td>5000</td><td>µs</td></tr>
<tr><td>Max_Powerlink_CycleTime_us</td><td>This parameter specifies the maximum POWERLINK cycle time used to calculate the safety response time.
• Permissible values: 200 to 25,000 µs</td><td>5000</td><td>µs</td></tr>
<tr><td>Max_CPU_CrossLinkTask_
CycleTime_us</td><td>This parameter specifies the maximum cycle time for the copy task on the CPU used to calculate the safety response time. The value 0 indicates that a copy task is not included for the response time.
• Permissible values: 0 to 25,000 µs</td><td>5000</td><td>µs</td></tr>
<tr><td>Min_X2X_CycleTime_us</td><td>This parameter specifies the minimum X2X cycle time used to calculate the safety response time.
• Permissible values: 200 to 25,000 µs</td><td>200</td><td>µs</td></tr>
<tr><td>Min_Powerlink_CycleTime_us</td><td>This parameter specifies the minimum POWERLINK cycle time used to calculate the safety response time.
• Permissible values: 200 to 25,000 µs</td><td>200</td><td>µs</td></tr>
<tr><td>Min_CPU_CrossLinkTask_
CycleTime_us</td><td>This parameter specifies the minimum cycle time for the copy task on the CPU used to calculate the safety response time. The value 0 indicates that configurations without a copy task are also included for the response time.
• Permissible values: 0 to 25,000 µs</td><td>0</td><td>µs</td></tr>
<tr><td>Worst_Case_Response_Time_us</td><td>This parameter specifies the limit value for monitoring the safety response time.
• Permissible values: 3000 to 5,000,000 µs (corresponds to 0 to 5 s)</td><td>50000</td><td>µs</td></tr>
<tr><td>Node_Guarding_Lifetime</td><td>This parameter specifies the maximum number of attempts to be made during the time set with parameter "Node_Guarding_Timeout_s". The purpose of these attempts is to ensure that the module is available.
• Permissible values: 1 to 255
Note
• The larger the configured value, the greater the amount of asynchronous data traffic.
• This setting is not critical to safety functionality. The time for safely cutting off actuators is determined independently using parameter "Worst_Case_Response_Time_us".</td><td>5</td><td>-</td></tr>
</table>

Table 167: SafeDESIGNER parameters: Safety_Response_Time

SafeDESIGNER 4.2.x and higher:

<table>
<tr><th>Parameter</th><th>Description</th><th>Default value</th><th>Unit</th></tr>
<tr><td rowspan="2">Manual Configuration</td><td>This parameter makes it possible to manually and individually configure the safety response time for the module.

The parameters for the safety response time are generally configured in the same way for all stations involved in the application. For this reason, these parameters are configured for the SafeLOGIC controller in SafeDESIGNER. For application situations in which individual safety functions require optimal response time behavior, the parameters for the safety response time can be configured individually on the respective module.</td><td>No</td><td>-</td></tr>
<tr><td colspan="3"><table><tr><th>Parameter value</th><th>Description</th></tr><tr><td>Yes</td><td>Data from the module's "Safety Responsetime" group is used to calculate the safety response time for the module's signals.</td></tr><tr><td>No</td><td>The parameters for the safety response time are taken from the "Safety Responsetime" group on the SafeLOGIC controller.</td></tr></table></td></tr>
<tr><td rowspan="2">Synchronous Network Only</td><td>This parameter determines the synchronization characteristics of the network being used.</td><td>Yes</td><td>-</td></tr>
<tr><td colspan="3"><table><tr><th>Parameter value</th><th>Description</th></tr><tr><td>Yes</td><td>In order to calculate the safety response time, networks must be synchronous and their cycle times must either be the same or an integer ratio of the cycle times.</td></tr><tr><td>No</td><td>No requirement for synchronization of the networks</td></tr></table></td></tr>
<tr><td>Safe Data Duration</td><td>This parameter specifies the data transmission time between the SafeLOGIC controller and SafeIO module.
• Permissible values: 500 to 30,000,000 µs</td><td>20000</td><td>µs</td></tr>
<tr><td>Additional Tolerated Packet Loss</td><td>This parameter specifies the number of additional tolerated lost packets during data transfer.
• Permissible values: 0 to 20</td><td>0</td><td>Packages</td></tr>
<tr><td>Packets per Node Guarding</td><td>This parameter specifies the maximum number of packets used for node guarding.
• Permissible values: 1 to 255
Note
• The larger the configured value, the greater the amount of asynchronous data traffic.
• This setting is not critical to safety functionality. The time for safely cutting off actuators is determined independently of this.</td><td>5</td><td>Packages</td></tr>
</table>

Table 168: SafeDESIGNER parameters: Safety Responsetime

5.5.7 Minimum signal lengths

The parameters in group "Safety Response Time" in SafeDESIGNER influence the maximum number of data packets that are permitted to fail without triggering a safety response. These parameters therefore act like a switch-off filter. If several data packets are lost within the tolerated amount, safety signals may not be detected if their low phase is shorter than the determined data transmission time.

Danger!

Lost signals can result in serious safety errors. Check all signals to determine the smallest possible pulse length and make sure that it is larger than the determined data transmission time.

Suggested solution:

- The switch-on filter can be used to extend the low phase of a signal on the input module.
- Low phases of signals from the SafeLOGIC controller can be lengthened with restart interlock functions or timer function blocks.

5.6 Detecting errors within the module

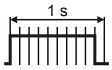
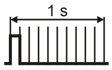
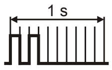
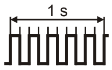
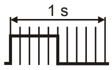
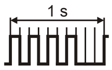
Module-internal errors are detected promptly with the diagnostic coverage (DC) specified in the respective safety function in accordance with the requirements of the standards listed in the certificate. After this occurs, the module reverts back to a safe state within the safe error response time.

The internal module tests needed for this are only performed, however, if the module's firmware has been booted and the module is in either state PREOPERATIONAL or state OPERATIONAL. If this state is not achieved (because the module has not been configured in the application, for example), then the module will remain in state BOOT or PRE OPERATIONAL.

The red "SE" LED makes it possible to evaluate the following critical states:

- State BOOT or PRE OPERATIONAL
- Incompatible firmware version
- Error state that cannot be acknowledged
    - Module error, e.g. defective RAM, defective CPU
    - Overtemperature/Undertemperature
    - Overvoltage/Undervoltage
    - Incorrect configuration
    - ...

The current module state is clearly indicated by the following blink sequences of LED "SE".

LED	Color	Status	Description
SE or FAILSAFE	Red	Off	Mode RUN, firmware in state OPERATIONAL or I/O component not supplied with voltage
			Boot phase, defective processor or missing X2X link (for X2X modules)
			Safety state PRE OPERATIONAL or "SafeOSstate!=RUN" (for SafeLOGIC controllers) Modules that are not used in the SafeDESIGNER application remain in state PRE OPERATIONAL.
			Safe communication channel not OK, openSAFETY connection valid problem or "SafeOSstate!=RUN" (for SafeLOGIC controllers) If the module remains in this state for a longer time, parameter "Safe data duration" must be checked.
			The firmware of the module is a non-certified pilot customer version, or the safety application was created with a test or pilot version of SafeDESIGNER.
			Boot phase, faulty firmware or setup mode active For details about setup mode, see section "Setup mode".
			SafeDESIGNER in "Debug" mode (for SafeLOGIC controllers)
		On	Safety state of the entire module active, error state that cannot be acknowledged (state FAIL SAFE)
	LED "FAILSAFE" or the "SE" LEDs describe the states in the safety processors.		

Danger!

Danger from an accumulation of errors due to missing module diagnostics

In critical states (BOOT, PRE OPERATIONAL or error), the necessary module-internal tests are not performed.
Permanent operation of the safety modules in a critical state is not permitted!

Safe output channels STO and SBC control safe pulse disabling and the safe motor holding brake output and thus form the basis of the idle current principle.

The safe output channels are only tested in the switched-on state (STO or SBC enabled).
For output channels that are switched off (STO or SBC not enabled) or in critical states (BOOT, PRE OPERATIONAL or error), the required internal system tests are not performed.

The calculation of the safety characteristics is based on the execution of the channel tests at least every 24 hours in order to be able to exclude an accumulation of errors.

In order for the module-internal tests to be fully completed, the output channels must be in the switched-on state for at least 1500 ms. This ensures that both the high-side and low-side switches are tested.

In order to meet the requirements of the respective application-specific standards, the output channels must be tested by the user in the application by switching on the safe output channels (STO, SBC) for at least 1500 ms at least every 24 hours.
This means that pulse disabling must be enabled and the motor holding brake (if used) must be released. The controller does not need to be switched on for this. An error entry is not made if this condition is not met.

Danger!

Danger from an accumulation of errors due to missing module diagnostics

A safe output channel (STO, SBC) is only permitted to be switched off for a maximum of 24 hours.
The channel must be switched on for at least 1500 ms by the end of this period so that the module-internal channel tests can be performed.

6 Safety technology

6.1 Integrated safety technology - SafeMOTION

6.1.1 General information

The safety functions integrated in the drive open up entirely new possibilities for guaranteeing the safety of personnel while maintaining maximum machine availability.
ACOPOSmulti SafeMOTION inverter modules, ACOPOS P3 SafeMOTION servo drives and ACOPOSmotor SafeMOTION with integrated safety technology round off the B&R safety concept and make it possible to design an entire safety application using state-of-the-art products from B&R.

> **Information:**
>
> **Due to the internal cycle time on the ACOPOSmulti SafeMOTION, the POWERLINK cycle time must be set to 400 µs or a whole-number multiple of 400 µs.**

The products are intended for use worldwide, in the following areas for example:

- Automotive industry
- Electrical industry
- Beverages industry
- Food industry
- Glass and cement building materials industry
- Handling robotics industry
- Metal industry
- Packaging industry
- Paper printing industry
- Pharmaceutical industry
- Plastics industry
- Textile industry
- Transport systems
- Wood handling and processing industry

This list shows typical areas of application but is by no means complete.

> **Danger!**
>
> **B&R drive systems and servo motors have been designed, developed and manufactured for conventional use in industrial environments. They were not designed, developed and manufactured for any use involving serious risks or hazards that could lead to death, injury, serious physical impairment or loss of any kind without the implementation of exceptionally stringent safety precautions.**
>
> **In particular, these risks include the use of these devices to monitor nuclear reactions in nuclear power plants, in flight control or flight safety systems as well as in the control of mass transportation systems, medical life support systems or weapons systems.**

6.1.2 Safe power transmission system

The main components of a safe power transmission system are the safe inverter module or servo drive, the encoder cable, the motor cable and a motor with a position encoder that meets the requirements for use in integrated safety technology.

The following components are permanently installed:

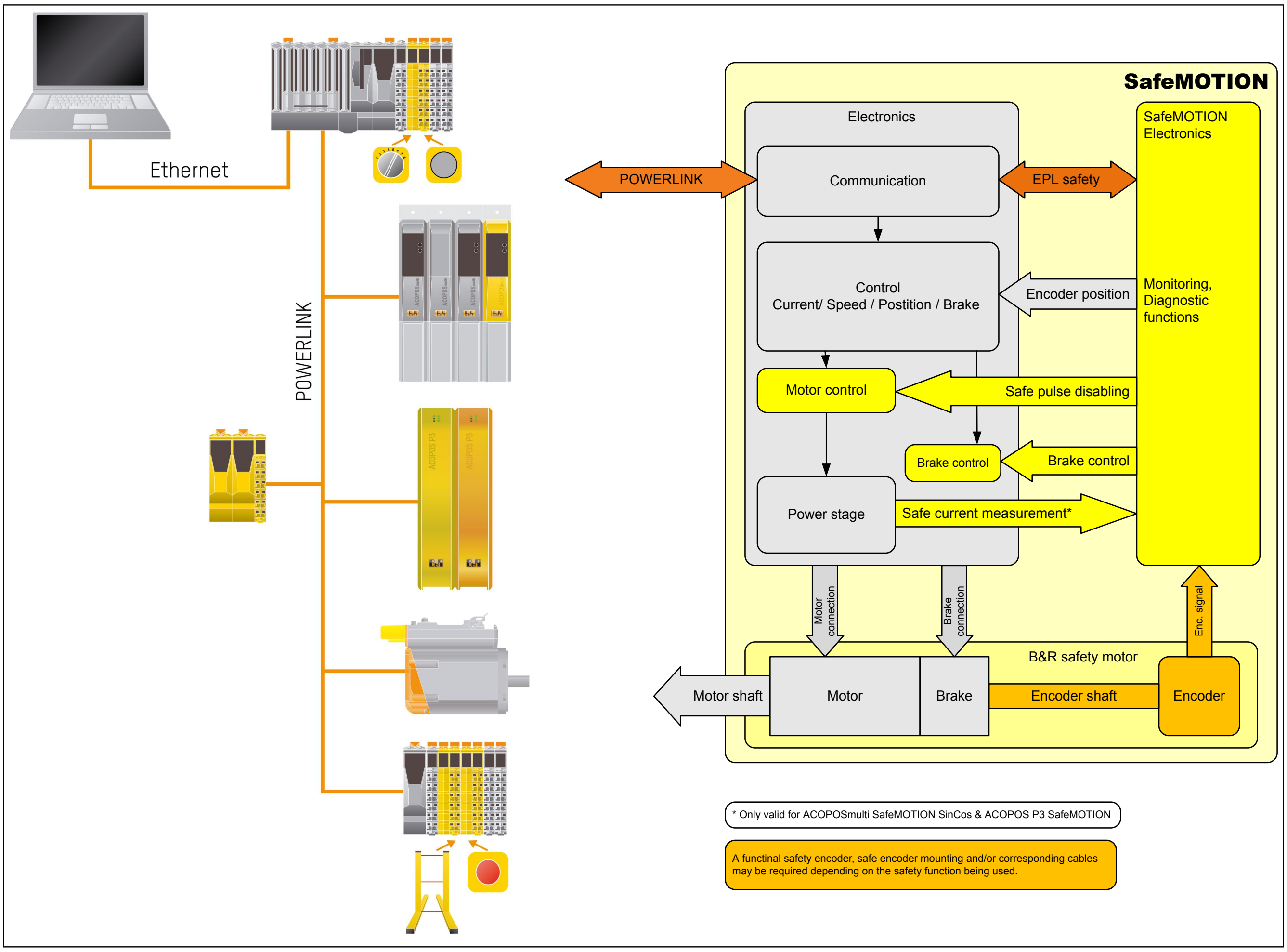


Figure 60: Safe power transmission system

Safe drive module

The safe drive module basically consists of a standard module with additional SafeMOTION hardware and firmware.

SafeMOTION integrated safety technology is implemented using an integrated SafeMOTION module on ACOPOSmulti inverter modules and the ACOPOSmotor SafeMOTION inverter unit.

One SafeMOTION module is integrated in the safe drive for each safe axis. A safe 1-axis module includes one permanent installed SafeMOTION module and is the equivalent of one POWERLINK node and one safe node.

With ACOPOSmulti SafeMOTION EnDat 2.2, a 2-axis module contains two permanently installed SafeMOTION modules and corresponds to one POWERLINK node and two safe nodes.

On ACOPOS P3 SafeMOTION servo drives, SafeMOTION integrated safety technology is implemented as an integrated option. On ACOPOS P3 servo drives, up to 3 axes are integrated in a SafeMOTION module. An ACOPOS P3 SafeMOTION servo drive corresponds to a safe node (regardless of the number of axes integrated in a SafeMOTION module).

As before, actual control is performed via the standard application and is not safety-related. The additional SafeMOTION components provides safety-related monitoring of predefined limits based on requirements, however. If these limits are exceeded, the SafeMOTION module activates safe pulse disabling and the motor holding brake output is switched to 0 V.

6.1.2.1 ACOPOSmulti SafeMOTION EnDat 2.2 and ACOPOS P3 SafeMOTION

Motor with safe position encoder

In order to be able to use all safety functions, the use of an EnDat 2.2 functional safety encoder from Heidenhain is mandatory! With standard EnDat 2.2 encoders, only the STO, SBC and time-monitored SS1 safety functions are available!

B&R safety motors (Sx, D4/D5, D8/D9, DA/DB, Z8/Z9 encoder option)

For motors with the Sx, D4/D5, D8/D9, DA/DB, Z8/Z9 encoder option, the EnDat 2.2 functional safety encoder is installed in strict accordance with Heidenhain's installation guidelines.
In this way, encoder slippage or encoder shaft breakage can be ruled out as a mechanical error.

> **Danger!**
>
> **Encoders used with B&R safety motors (Sx, D4/D5, D8/D9, DA/DB,Z8/Z9 encoder option) are only permitted to be replaced by B&R!**
>
> **If the encoder is replaced by someone other than B&R, it is no longer permitted to assume that mechanical errors such as encoder slippage or shaft breakage can be ruled out.**

B&R standard motors (B8/B9, D0/D1 encoder option)

For motors with the B8/B9, D0/D1 encoder option, the SafeMOTION module can sufficiently detect encoder slippage or encoder shaft breakage in some applications. In this case, the application must meet all requirements specified under 6.2.3.3.3 "Encoder mounting without proof of fatigue strength - Safe lag error monitoring" on page 309 and all limitations listed in this section must be taken into account. Under these conditions, B&R standard motors can also be used for safety applications!

Combining B&R motors with gearboxes

> **Danger!**
>
> **When combining B&R motors with gearboxes, the mechanical connection between the motor and gearbox does not meet "functional safety" requirements. It is not possible to rule out slippage or breakage.**
>
> **For combinations of B&R motors and gearboxes, only safety functions in which no safe absolute position is monitored are permitted to be used (STO, SBC, SOS, SS1, SS2, SLS, SMS, SLI, SDI, SLA, SBT (only available for ACOPOSmulti SafeMOTION SinCos and ACOPOS P3 SafeMOTION), SLT (only available for ACOPOS P3 SafeMOTION), and Safe Speed).**
>
> **The use of B&R motor-gearbox combinations is not permitted with hanging loads and other comparable applications where breakage between the motor and gearbox would result in a dangerous situation!**

Encoder cable

ACOPOSmulti SafeMOTION EnDat 2.2

The encoder cable is connected to the SafeMOTION module with a male DSUB connector. Please note the instructions in the "Cable connection via male DSUB connector" section under 2.6.1.3.1 "Wiring / General information / Connection diagrams for ground and shield connections / 8BVI inverter modules with SafeMOTION (1-axis modules)" on page 155.

> **Information:**
>
> **Only B&R 8BCF EnDat 2.2 cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the encoder interfaces!**

ACOPOS P3 SafeMOTION EnDat 2.2

The encoder cable is connected to the SafeMOTION module with using a mini I/O connector. See ACOPOS P3 user's manual MAACPP3-ENG, chapter "Wiring".

> **Information:**
>
> **Only 8ECF EnDat 2.2 cables from B&R or 8ECH hybrid motor cables from B&R are permitted to be connected to the encoder interfaces!**

Motor cable

The motor cable is connected to the safe inverter module with a male motor connector.

ACOPOSmulti SafeMOTION EnDat 2.2

Information:

Only B&R 8BCM motor cables or B&R 8BCH hybrid motor cables are permitted to be used for wiring the motor connections!

ACOPOS P3 SafeMOTION EnDat 2.2

Information:

Only 8ECM motor cables from B&R or 8ECH hybrid motor cables from B&R are permitted to be wired to the motor connections!

6.1.2.2 ACOPOSmulti SafeMOTION SinCos

Available safety functions

In order to use all of the available safety functions, the encoders used must meet the requirements listed in section 6.2.3.2.2.1 "Safety requirements for SinCos measuring instruments" on page 299. Note that fault exclusion is required for encoder slippage and encoder shaft breakage and that the encoder installation must therefore be evaluated accordingly.

If encoder slippage or encoder shaft breakage is covered only by the lag error monitoring performed by the SafeMOTION module, then the safety-related use of the Safe Homing, SLP and SMP safety functions is not permitted!

Compatible B&R standard motors (Ex encoder option)

For B&R standard motors, the SafeMOTION module can sufficiently detect encoder slippage or encoder shaft breakage in some safety applications. In this case, the safety application must meet all of the requirements specified under 6.2.3.3.3 "Encoder mounting without proof of fatigue strength - Safe lag error monitoring" on page 309, and all limitations listed in this section must be taken into consideration. Under these conditions, B&R standard motors can be used for safety applications.

- **Encoder cable and encoder**
  The encoder cable is connected to the SafeMOTION module with a male DSUB connector. Please note the instructions in the "Cable connection via male DSUB connector" section under 2.6.1.3.1 "Wiring / General information / Connection diagrams for ground and shield connections / 8BVI inverter modules with SafeMOTION (1-axis modules)" on page 155.
  The following encoder types are used with B&R standard motors with encoder options E0/E1, E4/E5 and E6/E7:
  Heidenhain ECN 1313, EQN 1325, ECN 1113, EQN 1125 (for details, see 6.1.2.4 "B&R motors / List of encoders / SinCos measuring instruments" on page 286)

Information:

Only B&R 8BCS encoder cables or B&R 8BCE encoder cables are permitted to be used for wiring the encoder interfaces!

- **Motor cable**
  The motor cable is connected to the safe inverter module with a male motor connector.

Information:

Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.

Third-party motors

Note the requirements for encoders and motors listed in section 6.2.3.2.2 "Sine-Cosine encoders" on page 299. Under these conditions, third-party motors can be used for safety applications.

- **Encoder cables and encoders**
  The encoders used must meet the requirements set forth in 6.2.3.2.2.1 "Safety requirements for SinCos measuring instruments" on page 299, in particular those listed under "EMC requirements for the SinCos measuring instrument " on page 302.
  In addition, the wiring from the inverter module to the motor and within the motor itself must be comparable to that of B&R cables and B&R motors. If not, it must be subjected to a complete type examination with the increased test levels specified in IEC 61326-3-1!

Information:

If cables from other manufacturers are used, make sure that they have the same wave parameters and the same design as the respective B&R cable. If deviations exist, additional measures are necessary to ensure that EMC directives are met. When using cables from other manufacturers, B&R cannot guarantee adherence to EMC limit values! The connectors on the cables as well as on the motors are part of a properly functioning EMC concept!

For details, see the ACOPOSmulti user's manual (MAACPM-ENG) under "Technical data / Cables".

- **Motor cable**
  The motor cable is connected to the safe inverter module with a male motor connector.

Information:

Only 8BCM motor cables from B&R are permitted to be connected to the motor connectors.

6.1.2.3 ACOPOSmotor SafeMOTION EnDat 2.2

Motor with safe position encoder

In order to use the safety functions, an EnDat 2.2 functional safety encoder from Heidenhain is a fixed component of the ACOPOSmotor. It is installed strictly according to the guidelines provided by Heidenhain.

In this way, encoder slippage or encoder shaft breakage can be ruled out as a mechanical error.

Combining ACOPOSmotor SafeMOTION with gearboxes

Danger!

When combining ACOPOSmotor SafeMOTION with gearboxes, the mechanical connection between the motor and gearbox does not meet "functional safety" requirements. It is not possible to rule out slippage or breakage.

For combinations of ACOPOSmotor SafeMOTION and gearboxes, only safety functions in which no safe absolute position is monitored are permitted to be used (STO, SBC, SOS, SS1, SS2, SLS, SMS, SLI, SDI, SLA, SBT (only available for ACOPOSmulti SafeMOTION SinCos) and Safe Speed).

The use of ACOPOSmotor SafeMOTION and gearbox combinations is not permitted with hanging loads and other comparable applications where breakage between the motor and gearbox would result in a dangerous situation!

Information:

ACOPOSmotor SafeMOTION modules with gearbox mounting are not available.

6.1.2.4 B&R motors / Encoder list

This list contains the encoders that have been tested for safe evaluation of ACOPOSmulti SafeMOTION EnDat 2.2 inverter modules and ACOPOS P3 SafeMOTION servo drives from B&R and are therefore approved by B&R for use.

EnDat 2.2 FS measuring instruments

Manufacturer	Name	Vendor ID Model number	Description	B&R Motor option	Achievable Safety level
Heidenhain	**ECN 1325 FS EnDat22**	678919-12 678919-03 678919-53	EnDat 2.2 single-turn, 2048-line Mounted optical rotary encoder	**S0/D0**	SIL 2
Heidenhain	**EQN 1337 FS EnDat22**	678921-02 677921-03 678921-53	EnDat 2.2 multi-turn, 2048-line, 4096 revolutions Mounted optical rotary encoder	**S1/D1**	SIL 2
Heidenhain	**ECN 1123 FS EnDat22**	640745-01 743586-01 743586-51	EnDat 2.2 single-turn, 512-line Mounted optical rotary encoder	**S4/D4**	SIL 2
Heidenhain	**EQN 1135 FS EnDat22**	640746-01 743587-01 743587-51	EnDat 2.2 multi-turn, 512-line, 4096 revolutions Mounted optical rotary encoder	**S5/D5**	SIL 2
Heidenhain	**ECI 1319 FS EnDat22**	810661-02 810661-04 810661-05	EnDat 2.2 single-turn, 16-line Mounted inductive rotary encoder	**SA/DA**	SIL 2
Heidenhain	**EQI 1331 FS EnDat22**	810662-03 807100-01 810662-04 810662-05	EnDat 2.2 multi-turn, 16-line, 4096 revolutions Mounted inductive rotary encoder	**SB/DB**	SIL 2
Heidenhain	**ECI 1119 FS EnDat22**	826930-01 826930-02 826930-51	EnDat 2.2 single-turn, 16-line Mounted inductive rotary encoder	**S8/D8**	SIL 2
Heidenhain	**ECI 1119 FS EnDat22**	826930-52	EnDat 2.2 single-turn, 16-line Mounted inductive rotary encoder	**B8/Z8**	SIL 2
Heidenhain	**EQI 1131 FS EnDat22**	826933-12 826980-01	EnDat 2.2 multi-turn, 16-line, 4096 revolutions Mounted inductive rotary encoder	**S9/D9**	SIL 2
Heidenhain	**EQI 1131 FS EnDat22**	826980-02 826980-52	EnDat 2.2 multi-turn, 16-line, 4096 revolutions Mounted inductive rotary encoder	**B9/Z9**	SIL 2
Heidenhain	**LC415-570**	89674-11	EnDat 2.2 20 µm grating period Encapsulated length measuring systems	**-**	SIL 2
Heidenhain	**RCN 2310**	667789-01	EnDat 2.2 single-turn, Angular measuring instrument Optical	**-**	SIL 2
Heidenhain	**RCN 8310**	667601-01	EnDat 2.2 single-turn, Angular measuring instrument Optical	**-**	SIL 2
Heidenhain	**RCN 8510**	667595-01	EnDat 2.2 single-turn, Angular measuring instrument Optical	**-**	SIL 2

Table 169: Measuring instruments for safe evaluation of ACOPOSmulti SafeMOTION EnDat 2.2 inverter modules and ACOPOS P3 SafeMOTION servo drives.

The following SinCos measuring instruments have been tested with respect to their safety requirements and their suitability for use with ACOPOSmulti SafeMOTION SinCos inverter modules:

SinCos measuring instruments

Manufacturer	Name	Vendor ID Model number	Description	B&R Motor option	Achievable Safety level
Heidenhain	**ECN1313 EnDat01**	586 640-11 586 640-51	EnDat single-turn, 512-line	**E0 8LS starting with Rev. C3 8JS starting with Rev. C0**	SIL 2
Heidenhain	**EQN 1325 EnDat01**	586 654-05 586 654-55 827039-55	EnDat multi-turn, 512-line, 4096 revolutions	**E1 8LS starting with Rev. C3 8JS starting with Rev. C0**	SIL 2
Heidenhain	*ECI 1317 EnDat01*	*623 042-07 623 042-52*	*EnDat single-turn, (inductive), 32-line*	*E2*	*Not suitable*
Heidenhain	*EQI 1329 EnDat01*	*623 079-14 623 079-61*	*EnDat single-turn, (inductive), 32-line, 4096 revolutions*	*E3*	*Not suitable*
Heidenhain	**ECN 1113 EnDat01**	606 684-01 606 684-P1 803427-01	EnDat single-turn, 512-line	**E4 8LS starting with Rev. C3 8JS starting with Rev. C0**	SIL 2

Table 170: Measuring instruments for safe evaluation of ACOPOSmulti SafeMOTION SinCos inverter modules

Manufacturer	Name	Vendor ID Model number	Description	B&R Motor option	Achievable Safety level
Heidenhain	**EQN 1125 EnDat01**	606 689-13 606 689-16 803427-01	EnDat multi-turn, 512-line, 4096 revolutions	**E5 8LS starting with Rev. C3 8JS starting with Rev. C0**	SIL 2
Heidenhain	**ECN 1313 EnDat01**	586 643-03 768295-03 768295-11	EnDat single-turn, 2048-line	**E6 8LS starting with Rev. C3 8JS starting with Rev. C0**	SIL 2
Heidenhain	**EQN 1325 EnDat01**	586 653-06 586653-09 827039-06	EnDat multi-turn, 2048-line, 4096 revolutions	**E7 8LS starting with Rev. C3 8JS starting with Rev. C0**	SIL 2
Heidenhain	*ECI 1118 EnDat01*	*622 503-01 622503-03*	*EnDat single-turn, (inductive), 16-line*	*E8*	*Not suitable*
Heidenhain	*EQI 1130 EnDat01*	*598 412-03 598412-05*	*EnDat single-turn, (inductive), 16-line, 4096 revolutions*	*E9*	*Not suitable*
Heidenhain	*ECI 1319 EnDat01*	*623 042-04 623 042-54 811 811-52 811 811-54*	*EnDat single-turn, (inductive), 32-line*	*EA*	*Not suitable*
Heidenhain	*EQI 1331 EnDat01*	*623 079-08 623 079-58 811 814-52 811 814-59*	*EnDat single-turn, (inductive), 32-line, 4096 revolutions*	*EB*	*Not suitable*
AMO	**LMKA**	LMKA-x3100.x0x-x, x-Sxx	Absolute length measuring system SSI + 1 Vss	**-**	SIL 2
Pepperl Fuchs	**RVS58S**	RVS58S-xxxxxxxxZ	SinCos rotary encoder 1 Vss 1024-/2048-line	**-**	SIL 3
Kübler	**Sendix 5863 SIL/ 5883 SIL**	8.5863SIL.1xxx.xx2x	Multi-turn rotary encoder SSI/BISS + 1 Vss 2048-line	**-**	SIL 3

Table 170: Measuring instruments for safe evaluation of ACOPOSmulti SafeMOTION SinCos inverter modules

Information:

The "B&R motors / Encoder list" is current as of the publication of this version of the user's manual.

The latest version of the "B&R motors / Encoder list" can be downloaded from www.br-automation.com.

6.1.3 The idle current principle

Integrated safety technology in the SafeMOTION module uses the idle current principle. When there is a logical 0 at a controller input or the current is interrupted, the corresponding safety function or error response is executed. The idle current principle ensures that the system tends toward the safest possible result in case of failure.

This method is an example of the general principle referred to in engineering as "fail-safe".

This is why the only safe function is the cutoff of a drive's energy and torque. The consequences that are described below are a result of the fail-safe principle.

Danger!

After the safe state (STO) is activated or in state FAIL SAFE, the drive is not supplied with power; the motor therefore no longer exerts torque or force.

If the motor was moving before STO is activated, it is only stopped by a safe motor holding brake (if available) or by the friction of the complete system!

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

During a fault event, the drive is not supplied with power; the motor therefore no longer exerts torque or force. Safe pulse disabling (STO) is active.

Information:

Safe pulse disabling
Torque and power are switched off on the drive. No electrical pulses are transmitted from the drive to the motor.

If the drive is in motion at the time of the error, then it will coast to a stop. The residual movement and remaining time must be considered for the worst-case scenario when making all of the calculations for the machine's safety circuit.

Danger!

An error can result in a forward movement followed by the motor coasting to a stop. When estimating the distance and time that results from the forward movement / coasting to a stop, the worst case scenario (i.e. the current maximum possible speed) must always be assumed.

The maximum possible drive speed is calculated from the maximum possible acceleration and the error response time, plus the actively monitored speed limit.

Danger!

Note that multiple errors in the IGBT bridge can cause a brief forward movement. The maximum angle of rotation φ of the motor shaft during this forward movement depends on the motor being used. For permanent magnet synchronous motors, $\varphi = 360°/2p$ (for B&R standard motors, p=3 so the angle is 60°). For three-phase induction motors, there is a relatively small angle of rotation between 5° and 15°.

This short forward movement can be excluded as a fault per EN ISO 13849-1, among other things due to the improbability that this would occur and due to general technical experience.

6.2 Principle - Implementing safety functions

Danger!

The C standards relevant to applications must be observed!

Danger!

Activating safe pulse disabling is not sufficient for achieving a voltage-free drive and therefore does not provide sufficient protection against electrical shock!

6.2.1 Safe pulse disabling

6.2.1.1 ACOPOSmulti SafeMOTION inverter module

Safe pulse disabling in ACOPOSmulti SafeMOTION inverter modules has the exact same structure as in standard ACOPOSmulti inverter modules.

The difference is that no external wiring is required. Instead, pulse disabling is activated internally by the SafeMOTION module. The function is controlled via two channels and tested by the SafeMOTION module.

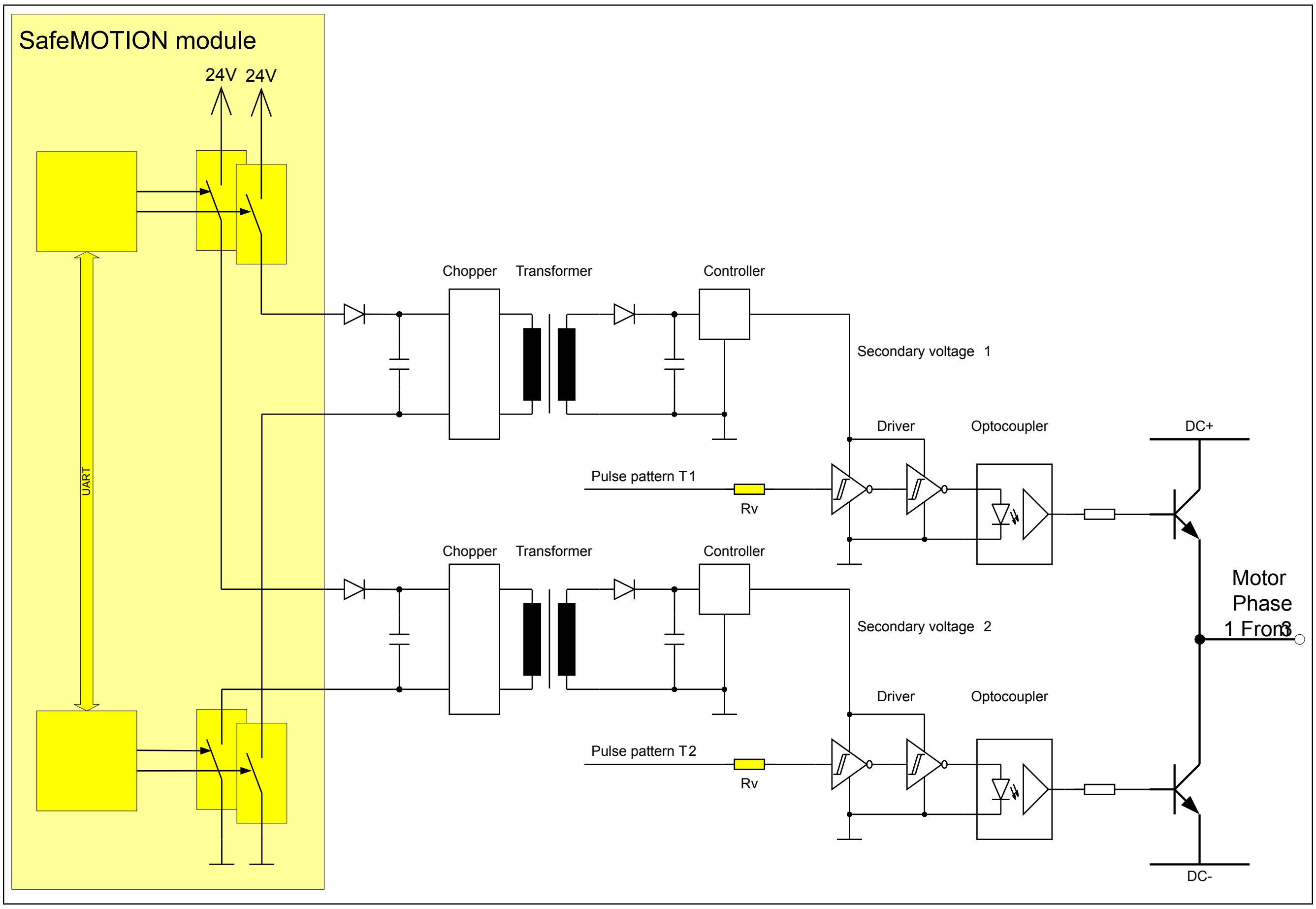


Figure 61: Control of safe pulse disabling - ACOPOSmulti SafeMOTION inverter module

6.2.1.2 ACOPOSmotor SafeMOTION module

Like standard ACOPOSmotor modules, safe pulse disabling on ACOPOSmotor SafeMOTION modules isolates the power supply for the gate control.

No external wiring is required; instead, pulse disabling is activated internally by the SafeMOTION module. The function is controlled via two channels and tested by the SafeMOTION module.

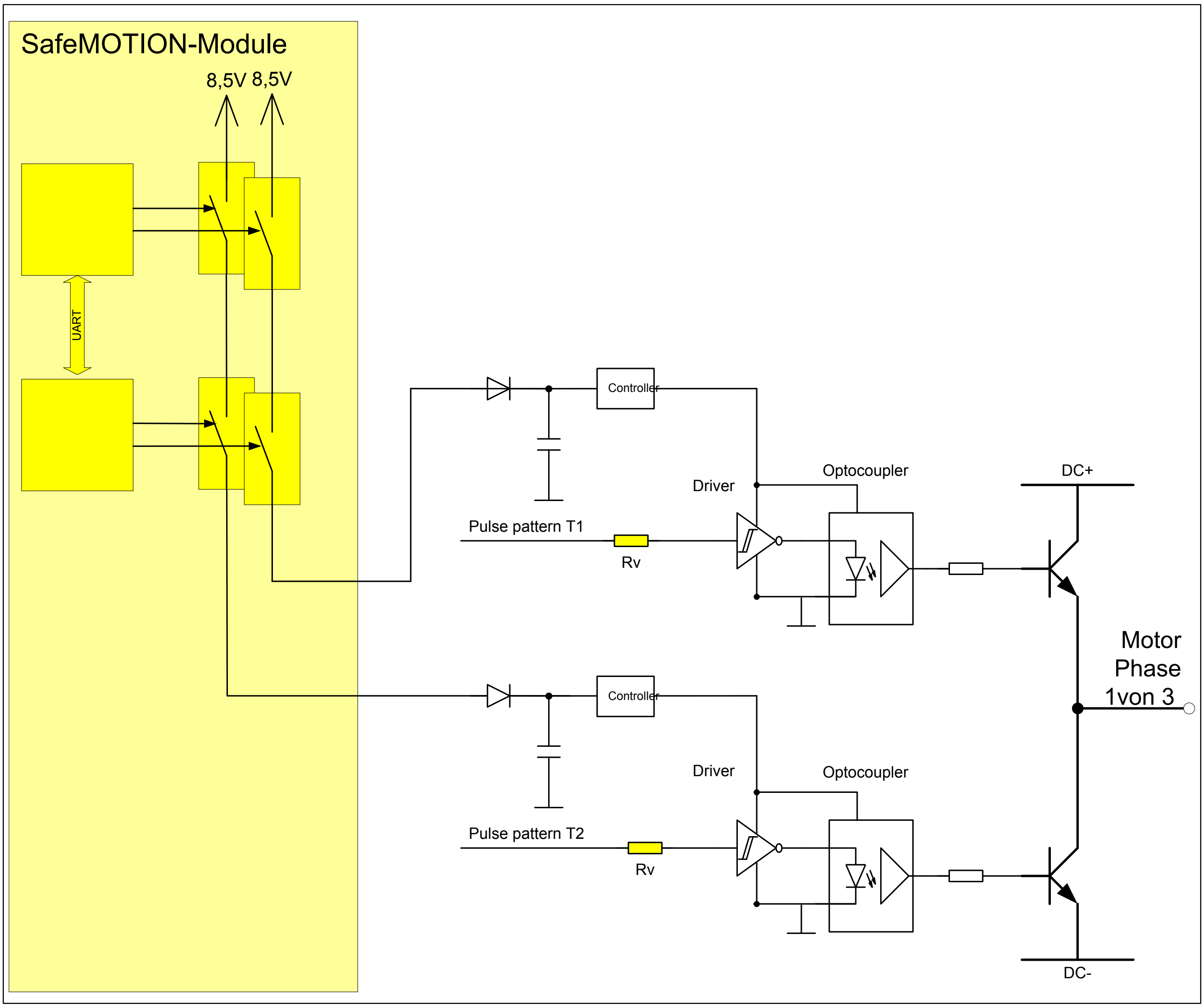


Figure 62: Control of safe pulse disabling - ACOPOSmotor SafeMOTION module

6.2.1.3 ACOPOS P3 SafeMOTION servo drives

Safe pulse disabling in ACOPOS P3 SafeMOTION servo drives has the exact same structure as in standard ACOPOS P3 servo drives.

The difference is that no external wiring is required. Instead, pulse disabling is activated internally in the module by the SafeMOTION components. The function is controlled via two channels and tested by the SafeMOTION components.

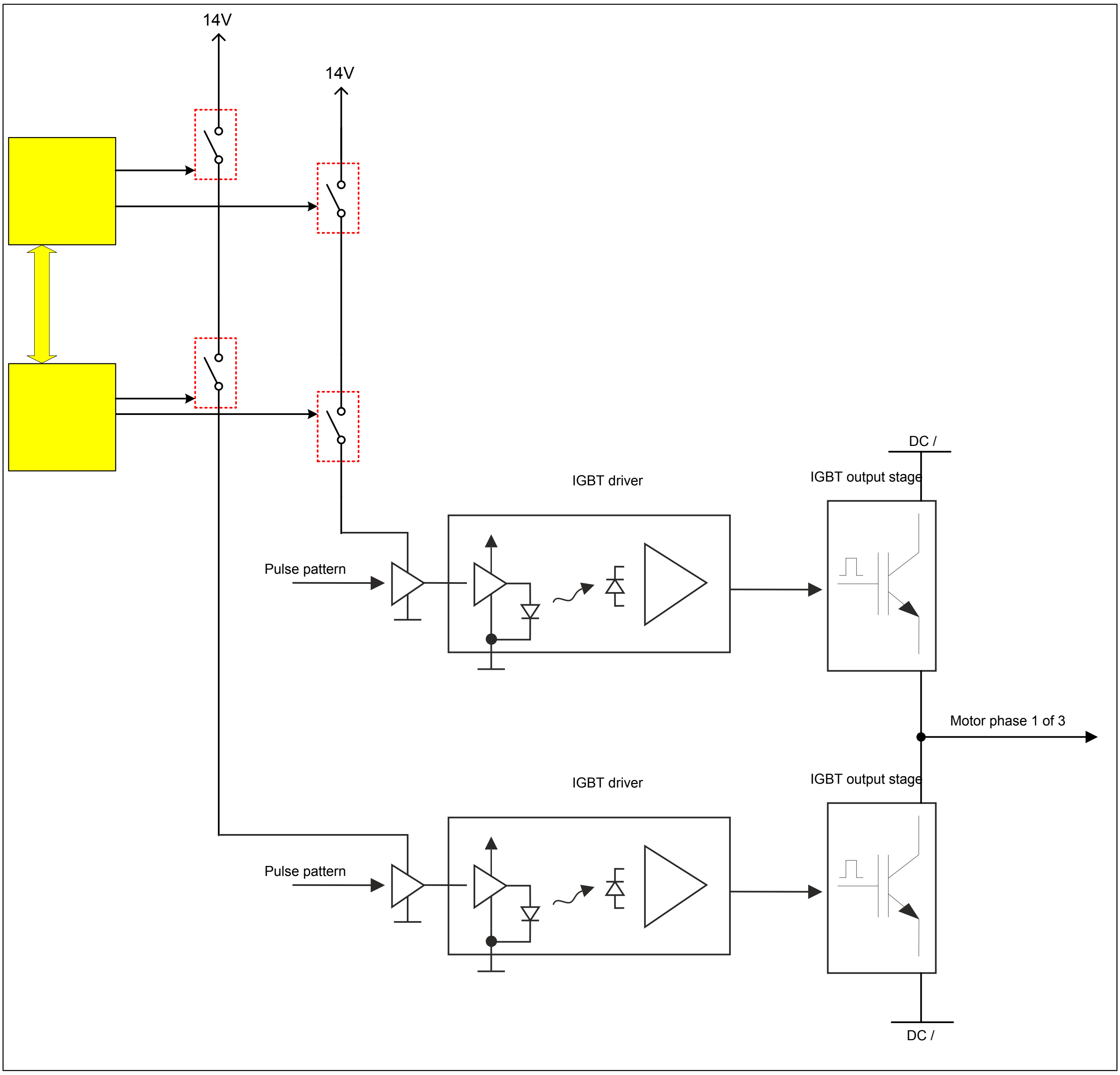


Figure 63: Controlling safe pulse disabling on ACOPOS P3 SafeMOTION servo drives

Information:

Safe pulse disabling is controlled directly by the SafeMOTION module. External wiring is not possible. This also means it is not necessary to apply fault exclusion to wiring errors!

6.2.2 Safe motor holding brake output

6.2.2.1 ACOPOSmulti SafeMOTION inverter module

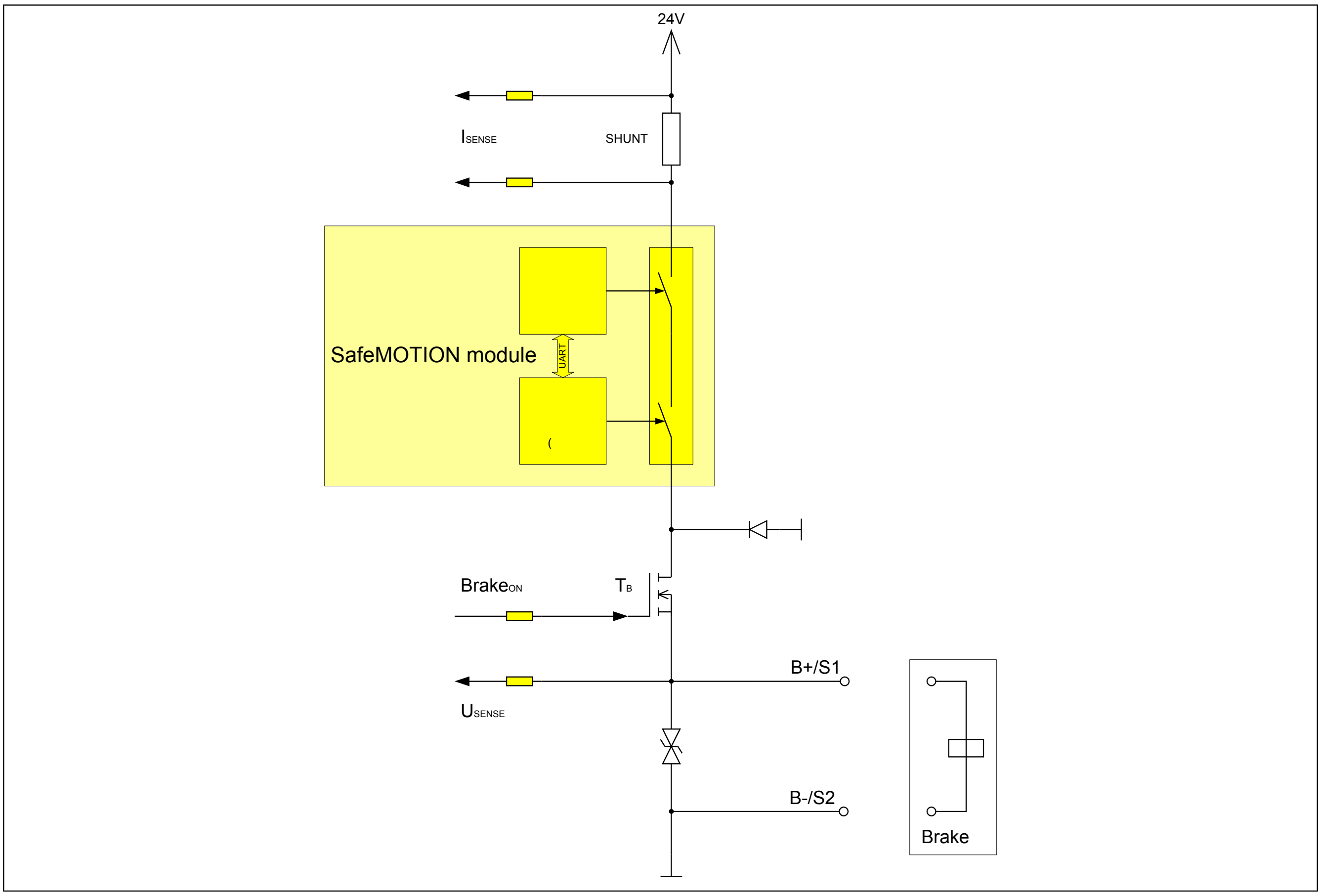


Figure 64: Connection of safe motor holding brake output

A wiring error that causes the output B+ to be shorted to 24 V causes the actuator to remain turned on despite the acknowledgeable FUNCTIONAL FAIL SAFE state being activated.

Error description	Effect	Safety function in accordance with Category 3 / SIL 2 / PL d maintained?
Short circuit: B+ and B-	Error not detected by module-internal testing. However, this is not critical since the motor holding brake is not released in this case (remains engaged).	YES, The motor holding brake output remains in the safe state.
Short circuit between 24 V and B+	Error detected by module-internal testing. The error detection causes the SafeMOTION module to change to the acknowledgeable error state. Safe pulse disabling is activated, and the brake always remains open due to the short circuit to 24 V! **This is a critical error and must therefore be prevented through wiring.**	NO Wiring error must be prevented through appropriate wiring!
Short circuit between ground and B+	Error not detected by module-internal testing. However, this is not critical since the motor holding brake is not released in this case (remains engaged).	YES, The motor holding brake output remains in the safe state.

Table 171: Wiring error in safe motor holding brake output

Danger!

A short circuit of SBC output B+ against 24 V results in state FUNCTIONAL FAIL SAFE being enabled. This means that safe pulse disabling is enabled. The brake always remains switched on / released, however, due to the short circuit to 24 V!
This can lead to dangerous situations since the motor holding brake cannot brake, prevent the spin-out movement or prevent the unbraked lowering movement when loads are suspended!
A short circuit of SBC output B+ against 24 V must be prevented by suitable wiring measures!

Danger!

The SBC output

- **is not permitted to be wired across modules!**
- **is not permitted to be wired as an open emitter!**
- **is not permitted to be wired as an open collector!**

Danger!

Only an output voltage of ≤ 5 V can be ensured for the safe motor holding brake output when switched off. When selecting the motor holding brake, the user must ensure that the required braking torque is achieved with a voltage of 5 V applied.

Information:

The transistors of the SBC output stage are tested cyclically. When the output channels are active, this test emits low pulses on the output with a maximum length of 600 µs.
Make sure to take this into consideration when selecting the motor holding brake.

6.2.2.2 ACOPOSmotor SafeMOTION module

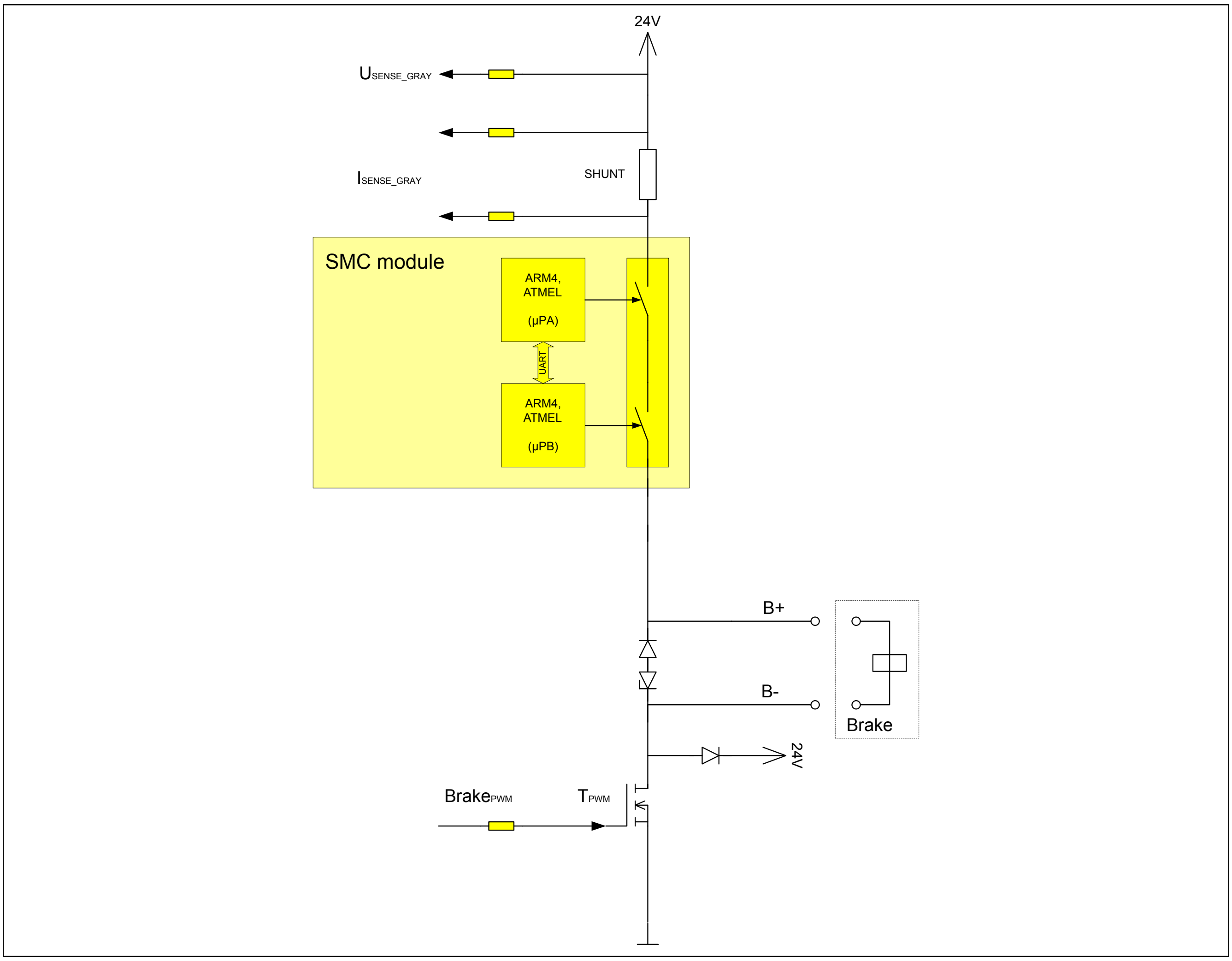


Figure 65: Connection of safe motor holding brake output

Information:

Wiring faults can be excluded since the motor holding brake is integrated in ACOPOSmotor SafeMOTION modules.

6.2.2.3 ACOPOS P3 SafeMOTION servo drives

The safe motor holding brake output on ACOPOS P3 SafeMOTION servo drives is activated internally in the module by the SafeMOTION components. The function is controlled via two channels and tested by the SafeMOTION components.

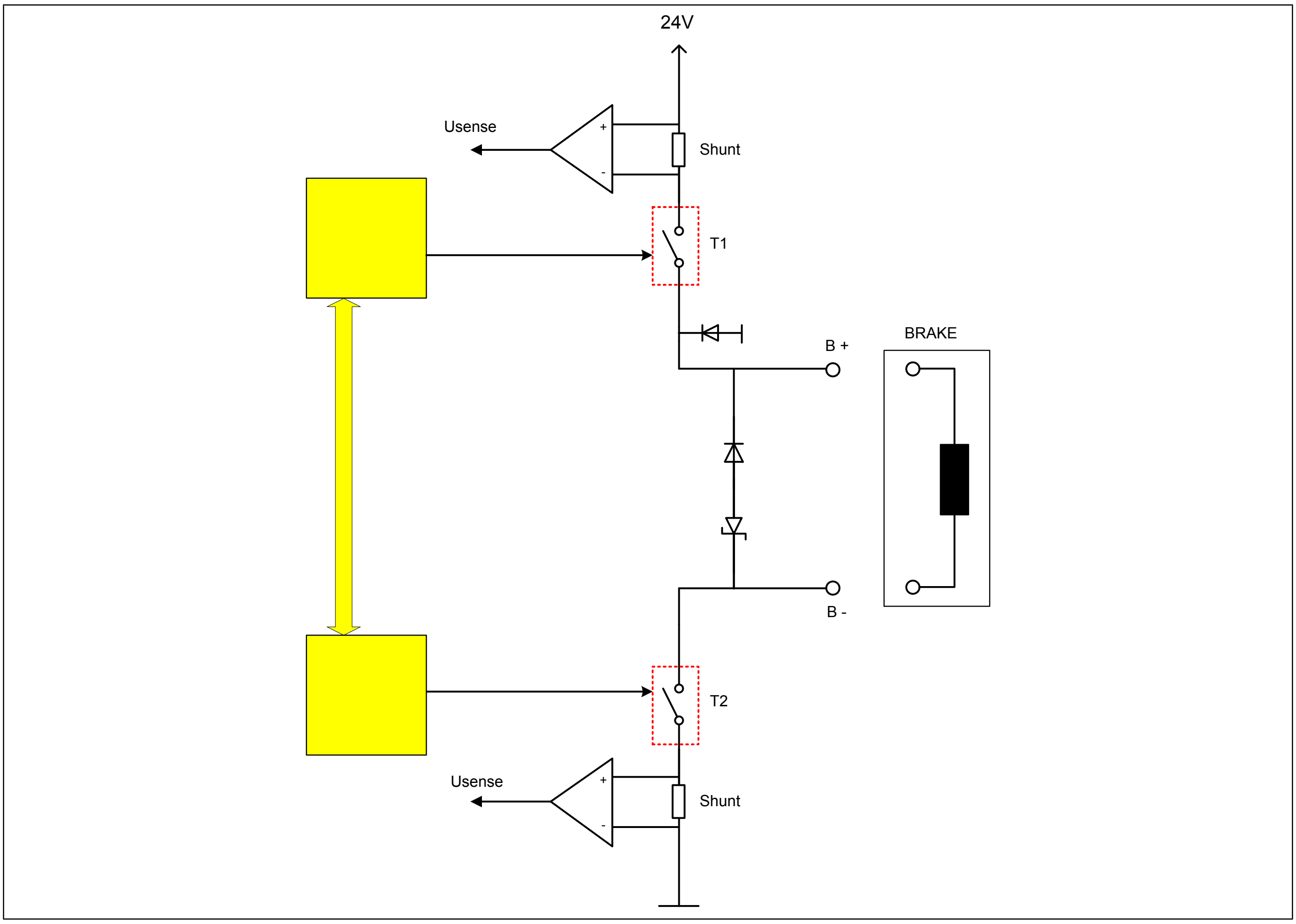


Figure 66: Connection of safe motor holding brake output

The following wiring errors can occur on the safe motor holding brake output:

Error description	**Effect**	**Safety function in accordance with Category 3 / SIL 2 / PL d maintained?**
Short circuit: B+ and B-	Error detected by module-internal testing if short circuit current greater than the specified continuous current of the motor holding brake output. The error detection causes the SafeMOTION module to change to the acknowledgeable error state. Safe pulse disabling is activated, and the brake always remains open due to the short circuit to 24 V!	YES, The motor holding brake output remains in the safe state.
Short circuit between 24 V and B+	Error detected by module-internal testing. The error detection causes the SafeMOTION module to change to the acknowledgeable error state. Safe pulse disabling is enabled, and the brake output is cut off.	YES, The motor holding brake output remains in the safe state.
Short circuit between ground and B+	Error detected by module-internal testing. The error detection causes the SafeMOTION module to change to the acknowledgeable error state. Safe pulse disabling is activated, and the brake always remains open due to the short circuit to 24 V!	YES, The motor holding brake output remains in the safe state.

Table 172: Wiring error in safe motor holding brake output

Danger!

The SBC output

- **is not permitted to be wired across modules!**
- **is not permitted to be wired as an open emitter!**
- **is not permitted to be wired as an open collector!**

Danger!

Only the output current can be ensured for the safe motor holding brake output when switched off. When selecting a motor holding brake, the user must ensure that the required braking torque is reached with current applied.

For the corresponding output current, see the technical data of the respective ACOPOS P3 SafeMOTION servo drive 8EI.

Information:

The transistors of the SBC output stage are tested cyclically. When the output channels are active, this test emits low pulses on the output with a maximum length of 600 µs.
Make sure to take this into consideration when selecting the motor holding brake.

Danger!

The motor holding brake is engaged in the safe state. The motor holding brake will suffer mechanical wear if the motor is in motion just before the safe state is triggered. This must be taken into account when selecting and dimensioning the motor holding brake (emergency stop capability).

Information:

The safe motor holding brake output is only a part of safe function group "Safe motor holding brake". The motor holding brake must be included when determining the safety category or SIL for the entire function group.

6.2.3 Safe encoder input

6.2.3.1 Assessing the safety integrity of the overall system

The entire chain, from the encoder to the safety function, must always be taken into consideration when assessing safety integrity.

6.2.3.1.1 PFH value

To determine the PFH value for the entire safety chain, the PFH value of the current safety function (see 6.3 "Safety characteristics of integrated safety functions " on page 316) and the PFH value of the encoder must be added:

$PFH_{Total} = PFH_{Safety\ function} + PFH_{Encoder}$

6.2.3.1.2 Category

To determine the category, the category of the respective safety function and the category of the encoder must both be taken into account (encoder manufacturer specifications or determined according to method described).

They must be viewed as a chain, which means the lower of the two categories must be used!

6.2.3.1.3 Performance level

When determining the performance level of the overall system, all elements that participate in the safety function must be viewed as a chain.

The PL that is achieved for the safety function can then be determined according to "figure 5" or "table K.1 – Numerical representation of figure 5" in EN ISO 13849.

6.2.3.1.4 SIL

The SIL of the overall system results from the overall PFH value. As a rule of thumb, the drive system (safety function of the ACOPOSmulti SafeMOTION inverter module plus the measuring instrument used) should account for no more then 10% of the SIL limit.

Note that the maximum SIL of the respective safety function (see 6.3 "Safety characteristics of integrated safety functions " on page 316) cannot be exceeded. This also applies if the PFH value of the chain would be sufficient to achieve a higher SIL!

A maximum of SIL 2 can be reached with a non-certified SinCos encoder.

Safety-related evaluation is not possible for EnDat 2.2 encoders without FS certification, and they therefore cannot be used for safety functions that require safe position evaluation.

6.2.3.2 Electrical interface

6.2.3.2.1 EnDat 2.2 functional safety encoder

The concept of integrated safety functions in SafeMOTION EnDat 2.2 modules[4)] includes the use of an EnDat 2.2 functional safety encoder from Heidenhain.

The EnDat 2.2 safety encoder must be installed in such a manner as to eliminate the possibility of slippage and encoder shaft breakage. Please follow the installation guidelines from Heidenhain.

In some applications, the SafeMOTION module is able to sufficiently detect encoder slippage or encoder shaft breakage. Mechanical fault exclusion is not necessary for these applications.

> **Danger!**
>
> **Some safety-related measuring instruments are only permitted to be used in the closed control loop. This limitation is indicated in the technical data for the respective measuring instrument.**
>
> **These types of safety-related measuring instruments are not permitted to be used in combination with a SafeMOTION EnDat 2.2 module!**

4) ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION servo drives, ACOPOSmotor SafeMOTION

Information:

If safety functions are used that require a safe speed and/or position, then a Heidenhain EnDat 2.2 functional safety encoder must be used. Otherwise, the process data from the encoder is set to the FUNCTIONAL FAIL SAFE state.

6.2.3.2.1.1 Safe encoder counting range

For the safe encoder counting range, see the data sheet for the respective encoder. On ECN 1325 single-turn and EQN 1337 multi-turn rotary encoders, this range corresponds with the single-turn range. See excerpt from the data sheet:

Technische Kennwerte	Absolut	
	ECN 1325 Singleturn	EQN 1337 Multiturn
Funktionale Sicherheit für Anwendungen bis	• SIL 2 nach EN 61508 (weitere Prüfgrundlage: EN 61800-5-2) • Kategorie 3 PL d nach EN ISO 13849-1:2008 Sicher im Singleturn-Betrieb	

Information:

The manufacturer's most recent data sheet is the one that is valid. The user is responsible for obtaining this information from the manufacturer.

6.2.3.2.2 Sine-Cosine encoders

The conceptual design of the ACOPOSmulti SafeMOTION SinCos inverter module includes safe evaluation of analog, sinusoidal incremental signals. For this to be possible, the encoder must meet the requirements specified under 6.2.3.2.2.1 "Safety requirements for SinCos measuring instruments" on page 299.

6.2.3.2.2.1 Safety requirements for SinCos measuring instruments

General information

In table D.16, the DIN EN 61800-5-2 standard specifies a general fault model for motion and position sensors that is independent of the construction and design of the motion and position sensors. The following specifications regarding the fault model specified in DIN EN 61800-5-2 refer only to the purely analog 1 V_{ss} signals of a measuring instrument.

Technical data for the encoder interface

The measuring instrument must be suitable according to the technical data for the encoder interface.

Encoder interfaces [1]	
Encoder power supply	
Output voltage	5 V ±5% [2]
Load capacity	300 mA [3]
Sense lines	2, compensation of max. 2 x 0.7 V
Protective measures	
Short-circuit proof	Yes
Sine/Cosine inputs	
Signal transmission	Differential signals, symmetrical
Differential voltage	
In motion	0.5 to 1.35 V [4]
At standstill	0.8 to 1.35 V [5]
Differential voltage deviation per signal period	±10% [6]
Common-mode voltage	Max. ±7 V
Terminating resistor	120 Ω
Max. input frequency	200 kHz
Signal frequency (-5 dB)	<300 kHz
Signal frequency (-3 dB)	DC up to 200 kHz
ADC resolution	12-bit

Table 173: Encoder interface - Technical data

1) Only shielded cables are permitted to be used.
The stranded wire for the analog interface (Sin, nSin, Cos, nCos, Ref, nRef) and the digital interface (T, nT, D, nD) must be twisted pair with a wave impedance of 120 Ω ±10%.
Additional shielding of the analog interface is recommended.
2) During the power-on procedure for the encoder power supply voltage (2 seconds), the monitoring limit for the supply voltage is increased from 5.25 V to 6 V. In this phase, overvoltages up to 6 V are not detected.
A short-term overvoltage of maximum 6 V is not permitted to damage the encoder electronics in any way.
An undervoltage on the encoder power supply will result in a sine or cosine signal outside the specification.
3) An actual reserve of 12 mA exists for the terminating resistor.
4) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2\sqrt{((Sin - nSin)^2 + (Cos - nCos)^2)}$ is monitored according to the specified limits.
5) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2\sqrt{((Sin - nSin)^2 + (Cos - nCos)^2)}$ is also monitored according to the specified limits from the time the evaluation circuit is switched on until a signal period has passed.
6) The sine-cosine output signals from the measuring instrument are checked by the evaluation circuit using pointer length monitoring.
The pointer length $z = 2\sqrt{((Sin - nSin)^2 + (Cos - nCos)^2)}$ is permitted to deviate by a maximum of ±10% per signal period.

Danger!

During the power-on procedure for the encoder power supply voltage (2 seconds), the monitoring limit for the supply voltage is increased from 5.25 V to 6 V. In this phase, overvoltages up to 6 V are not detected.

A short-term overvoltage of maximum 6 V is not permitted to damage the encoder electronics in any way.

An undervoltage on the encoder power supply will result in a sine or cosine signal outside the specification.

Requirements from the "Error list for movement and position sensors per EN 61800-5-2:2007", table D.16

The following requirements from the error list must be assessed and implemented by the manufacturer of the measuring instrument or the machine manufacturer.

No.	Fault description	Fault exclusion	Comment	Requirements that must be met by the measuring instrument manufacturer or machine manufacturer
8	Parts become loose at a standstill: • Sensor housing comes off motor housing • Sensor shaft comes off motor shaft	FMEA and proof of fatigue strength of mechanical attachment	Output signal indicates a speed of zero. If fault exclusion is employed, the fastening mechanism for the sensor housing on the motor housing and the sensor shaft on the motor shaft generally withstands excessive stress up to a factor of approximately 20x and any special maintenance information must be provided.	Fault exclusion based on appropriate mounting must be applied in all cases. Exceptions: In synchronous motors applications where the encoder is integrated in position control, errors can be localized using the safe lag error monitoring function in the SafeMOTION module.
9	Fastening mechanism comes loose during movement: • Sensor housing comes off motor housing • Sensor shaft comes off motor shaft	FMEA and proof of fatigue strength of mechanical attachment	Potential effect: • Static offset of sensor shaft • Dynamic slippage of sensor shaft • Output signal is incorrect / indicates a speed of zero If fault exclusion is employed, the fastening mechanism for the sensor housing on the motor housing and the sensor shaft on the motor shaft generally withstands excessive stress up to a factor of approximately 20x and any special maintenance information must be provided.	Fault exclusion based on appropriate mounting must be applied in all cases. Exceptions: In synchronous motors applications where the encoder is integrated in position control, errors can be localized using the safe lag error monitoring function in the SafeMOTION module.
10	Measuring element comes loose[a)] (e.g. optical encoder disc)	None	Output provides incorrect position information	An error that would lead to a position deviation larger than ±1/2 of a signal period must change the sine-cosine signal enough that pointer length monitoring detects an error. This error must be assessed by the measuring instrument manufacturer.
11	No light in front of sensor diode	None	-	An error that would lead to a position deviation larger than ±1/2 of a signal period must change the sine-cosine signal enough that pointer length monitoring detects an error. This error must be assessed by the measuring instrument manufacturer.
Additional requirements for rotary encoders with sin/cos output signals, analog signal generation				
12	Static signal on inputs and outputs, individual or on multiple signals, amplitude in the voltage supply range	None	-	The output signals (sine and cosine) must be generated independently. If this requirement is met, the error is detected by pointer length monitoring on the SafeMOTION module with a diagnostic coverage (DC) of 99%.
14	Swapping the sine and cosine output signal	Fault exclusion is permitted if no electronic components are used to select an output signal from multiple sources.	-	Fault exclusion is required by the measuring instrument manufacturer.
Additional requirements for encoders [b)] with synthetically generated output signals				

Table 174: Error list for movement and position sensors using the standardized error model per EN 61800-5-2:2007 (Table D.16)

No.	Fault description	Fault exclusion	Comment	Requirements that must be met by the measuring instrument manufacturer or machine manufacturer
21	Distortion of the output signals in any way	None	-	Synthetically generated output signals are not permitted to be used. Exception: Encoders with safety certification, as long as error detection in the encoder is safety-related.
Additional requirements for linear encoders				
23	Mounting for read head broken	FMEA and proof of fatigue strength of mechanical attachment	If fault exclusion is required, the sensor mounting usually withstands the excessive stress that takes place and specific maintenance information should be specified.	Fault exclusion based on appropriate mounting must be applied in all cases. Exceptions: In synchronous motors applications where the encoder is integrated in position control, errors can be localized using the safe lag error monitoring function in the SafeMOTION module.
24	Static offset of measuring element[a)] (e.g. optical encoder strips)	None	-	An error that would lead to a position deviation larger than ±1/2 of a signal period must change the sine-cosine signal enough that pointer length monitoring detects an error. This error must be assessed by the measuring instrument manufacturer.
25	Damaged measuring element[a)] (e.g. optical encoder strips)	None	Pulse shape changed. Pulses missing on incremental encoders	An error that would lead to a position deviation larger than ±1/2 of a signal period must change the sine-cosine signal enough that pointer length monitoring detects an error. This error must be assessed by the measuring instrument manufacturer.
NOTE: This table was written assuming the use of optical sensors. If other sensors are used (e.g. inductive sensors), then the respective errors apply.				

Table 174: Error list for movement and position sensors using the standardized error model per EN 61800-5-2:2007 (Table D.16)

a) Does not apply to resolvers.
b) Applies correspondingly to linear encoders.

Items not listed in table D.16 are covered by the safety-related evaluation of the sine and cosine signals on the ACOPOSmulti SafeMOTION SinCos inverter module with a diagnostic coverage of 99%!

EMC requirements for the SinCos measuring instrument

The necessary EMC tests must conform with the higher testing levels per IEC 61326-3-1. The measuring instrument manufacturer or machine manufacturer must provide proof that the measuring instrument conforms to the higher testing levels!

Safety-related values

The ACOPOSmulti SafeMOTION SinCos inverter module offers the possibility of using certified or non-certified SinCos measuring instruments. When determining the safety characteristics of the overall system, non-certified and certified encoders require different procedures.

Non-certified measuring instruments

In order to assess safety integrity, the measuring instrument manufacturer must provide one of the following characteristics. These values can then be used to calculate the PFH for the encoder via diagnostics and encoder evaluation and therefore assess the safety integrity of the overall system.

Value	Unit	Short name	Description
MTTF	[h]	Mean time to failure (mean time to failure)	The MTTF can be directly used to assess safety concepts per EN ISO 13849. The MTTF (mean time to failure) can be performed for components by analyzing field data or by predictive analysis. At a constant failure rate, the average of the failure-free operating time MTTF = 1/λ , where λ is the failure rate of the instrument. (Statistically, the assumption can be made that 63.2% of the respective components will experience failure after the MTTF has expired.)
λ λ_D λ_S	[10^{-9} 1/h],[FIT]	Failure rate (Failures In Time) Dangerous failure rate Safe failure rate	To assess the safe failure rate according to DIN EN 61508, the FIT value (reciprocal of the MTTF value) must be used as the failure rate. If no detailed breakdown of failure rates ($\lambda_F = \lambda_{F1} + \lambda_{F2} + ... + \lambda_{Fn}$) is specified for the measuring instrument being used, the default rate is equally distributed among the faults taken into account in the error model in table D.16 in DIN EN 61800-5-2. If no detailed breakdown of failure rates ($\lambda_F = \lambda_S + \lambda_D$) is specified for the measuring instrument being used, then 50% of the failures will be assumed dangerous per EN ISO 13849.

Table 175: Characteristics required for non-certified SinCos measuring instruments

Calculating the relevant characteristic values when using non-certified SinCos measuring instruments

PFH value of the encoder with diagnosis of encoder evaluation

The safety integrity level is determined based on the PFH value. There are two methods for determining the PFH value of the encoder with diagnosis of encoder evaluation:

⇨ **Method 1: Determining from the $MTTF_d$ (mean time to dangerous failure) of the encoder being used**
The probability of failure per hour (PFH) for the safety function is calculated from the $MTTF_d$ of the encoder being used and the DC of the SafeMOTION module.

$$PFH_{Encoder} = \frac{1-DC}{MTTF_d}$$

In the absence of more detailed information about the failure of the measuring instrument, it is assumed that 50% of errors are dangerous.

$$MTTF_d = 2MTTF$$

⇨ **Method 2: Determining from the λ_D (dangerous failure rate) of the encoder being used**
The probability of failure per hour (PFH) for the safety function is determined from the dangerous failure rate (λ_D) of the encoder and the DC of the SafeMOTION module.

$$PFH_{Encoder} = \lambda_D(1-DC)$$

The encoder evaluation of the ACOPOSmulti SafeMOTION SinCos inverter module has a DC of 99%.

Category (Cat.) of the encoder with diagnosis of encoder evaluation

Safe encoder evaluation can be assessed at Cat. 3 when using a non-certified measuring instrument. This is because the requirements from EN ISO 13849 for diagnostic coverage (DC) and common cause factor (CCF) are met through the named requirements and through the monitoring of the encoder power supply voltage in the evaluation logic.

Performance level (PL) of the encoder with diagnosis of encoder evaluation

The performance level of a system can be determined using the figures or tables provided in EN ISO 13849.

Depending on the $MTTF_d$ and PFH value of the SinCos encoder, up to PL d can be achieved (see figure 5 in EN ISO 13849).

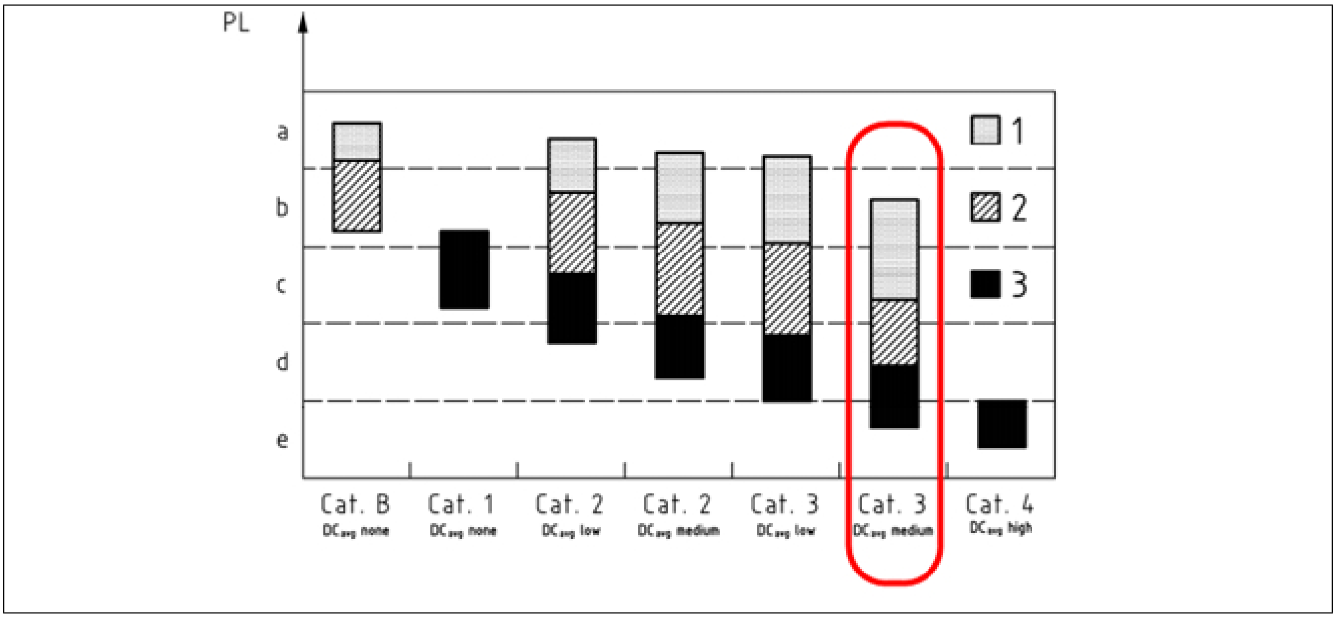


Figure 67: Relationship between DCavg, MTTFd of each channel and PL according to EN ISO 13849-1, figure 5

N10008**Legend:**

1 $MTTF_d$ of each channel = Low

2 $MTTF_d$ of each channel = Medium

3 $MTTF_d$ of each channel = High

PL Performance level

$MTTF_d$	
Name for each channel	**Range for each channel**
Low	3 years ≤ $MTTF_d$ < 10 years
Average	10 years ≤ $MTTF_d$ < 30 years
High	30 years ≤ $MTTF_d$ ≤ 100 years

Table 176: Mean time to dangerous failure (MTTFd) of each channel per EN ISO 13849-1, table 5

SIL capability of the encoder with diagnosis of encoder evaluation

The safety integrity level of a device depends on whether it is operated in a high demand mode of operation or low demand mode of operation.

When operating in a high demand mode of operation, it is assumed that the safety function will be requested continuously or an average of once per hour. For a continuous or high demand mode of operation, the PFH measure is used, which specifies the safety function's probability of failure per hour.

A position measuring instrument is evaluated as a device with a high demand mode of operation.

The maximum possible safety integrity level of a SinCos encoder can be determined as follows.

Safety integrity level (SIL)	**Average frequency of dangerous failure of the safety function [h^{-1}] (PFH)**
4	$\leq 10^{-9}$ to $<10^{-8}$
3	$\leq 10^{-8}$ to $<10^{-7}$
2	$\leq 10^{-7}$ to $<10^{-6}$
1	$\leq 10^{-6}$ to $<10^{-5}$

Table 177: Safety integrity levels and target failure measures for a safety function operating in high demand mode of operation or continuous mode of operation per EN 61508-1:2010, table 3

The following characteristic values are used to assess the SIL:

- **System type**
  As defined in DIN EN 61508, systems are classified as Type A and Type B. Since a SinCos encoder includes complex components (e.g. OPV), it is considered a Type B system.

- **Hardware fault tolerance (HFT)**
  A hardware fault tolerance of N means that N+1 faults could lead to a failure of the safety function. The hardware fault tolerance is determined based on the MooN architecture used. MooN stands for "M out of N channel architecture" and describes the architecture of a SIL device. For example, "1oo2" refers to an architecture with 2 channels where either of the channels is able to execute the safety function.
  In order to provide single fault tolerance, both signals (sine and cosine) must be generated independently and the safety function (position information) must be contained in both signals. The position information can only be obtained by evaluating both signals, however.
  The SinCos encoder input is to be viewed as single-channel with respect to the position and speed safety functions and can only be assessed as HFT = 0.

- **Safe Failure Fraction (SFF)**
  SFF is the fraction of safe failures. The higher the required SIL rating, the higher the SFF must be. A system's SFF is calculated from the failure rates (λ values) of the individual components.
  To determine the SFF of the SinCos encoder, pointer length monitoring of SinCos signals in the SafeMOTION module is used to increase diagnostic coverage. This additional diagnostics increases the DC level to HIGH.

Safe failure fraction of an element	Hardware fault tolerance		
	0	1	2
<60%	Not permitted	SIL 1	SIL 2
60% - <90%	SIL 1	SIL 2	SIL 3
90% - <99%	SIL 2	SIL 3	SIL 4
≥99%	SIL 3	SIL 4	SIL 4

Table 178: Maximum allowable safety integrity level for a safety function carried out by a type B safety-related element or subsystem per EN 61508-2:2010, table 3

Information:

When a safety-related system executes a safety function over a single channel, the maximum safety integrity level that can be claimed for the safety function under consideration shall be determined by the subsystem with the lowest requirements for hardware safety integrity.

Information:

The overall ACOPOSmulti SafeMOTION SinCos inverter module system is certified for a maximum safety integrity level of SIL 2 for evaluation of non-certified encoders.

Certified measuring instruments

For certified measuring instruments, the manufacturer must specify the necessary safety characteristics.

Verify that all specified diagnostic properties are fulfilled.

Value	Unit	Short name	Description
SIL SIL CL	[ ]	Safety integrity level (Safety Integrity Level) SIL Claim Level	The safety integrity level is one of four discrete levels used to specify the requirement for the safety integrity of the safety functions assigned to the safety-related system, with 4 being the highest level for safety integrity and 1 the lowest. The failure limits for the four safety integrity levels are defined in tables 2 and 3 of IEC 61508-1.
PFH	[10^{-9} 1/h], [FIT]	Probability of safety function failure per hour (Probability of failure per pour)	When operating in a high demand mode of operation, it is assumed that the safety function will be requested continuously or an average of once per hour. For a continuous or high demand mode of operation, the PFH measure is used, which specifies the safety function's probability of failure per hour.
PL	[ ]	Performance level	The ability to operate safety-related parts of control systems or to perform a safety function under foreseeable conditions is assigned a performance level (PL) from a scale of five levels. These performance levels are defined according to the probability of a dangerous failure per hour (see EN ISO 13849-1:2006, table 3).
Cat.	[ ]	Category	Assesses how well safety-related components in a control system behave when an error occurs.
DC	[%]	Diagnostic coverage (diagnostic coverage)	Partial reduction of the probability of dangerous hardware failures resulting from the use of automatic diagnostic tests Safe evaluation is based solely on the analog Sin/Cos signals. If the measuring instrument contains an internal diagnostics function, then the discovered errors must be reported through a violation of the SinCos interface specification on the subsequent electronics. Only then does it make sense to take into account the level of diagnostic coverage. If a DC is specified, then a provision must also be specified for the diagnostic test interval. Period between online tests to detect faults in a safety-related system with specified diagnostic coverage.
T_m	[years], [a]	Mission time (mission time)	The mission time must be determined by the device manufacturer and specifies the maximum amount of time an encoder can be used. The encoder must be replaced before the mission time expires!
T_l	[years], [a]	Proof test interval (proof test interval)	Recurring test for fault detection in a safety-related system, which can restore the system to a "like new" condition or as close to it as possible from a practical standpoint. A proof test is normally not possible for electronic devices. The mission time and proof test interval are therefore generally the same.

Table 179: Characteristic values required for certified SinCos measuring instruments

Category (Cat.) of the encoder with diagnosis of encoder evaluation

Danger!

Valid freezing only detected in movement with DC = 99%!

To exclude accumulation of faults at a standstill, movement must take place once a day by at least one signal period of the encoder.

The necessary movement can take place in the course of a functional positioning or homing procedure.

Safe encoder evaluation can be assessed at Cat. 4 when a suitable (certified) measuring instrument is used and the above limitations are taken into account.

Estimation of the achievable safety levels based on the example of a Heidenhain ECN 1313 / EQN 1325

Manufacturer specifications

According to an analysis of the document D662649-01-E-01 from Heidenhain, ECN 1313 and EQN 1325 encoders are deemed suitable for use with the ACOPOSmulti SafeMOTION SinCos inverter module.

The following MTTF / FIT values are specified:

Type	ID number	MTTF [h]	FIT [10^{-9}/h]
ECN 1313	586640-11	>1,666,667	<600
ECN 1313	586643-03	>1,666,667	<600
EQN 1325	586653-06	>1,666,667	<600
EQN 1325	586654-05	>1,666,667	<600

Table 180: MTTF values for Heidenhain ENC 1313 and EQN 1325 encoders according to Heidenhain document D662649-01-E-01

Calculating characteristic values of the encoder with diagnosis of encoder evaluation

Since ECN 1313 and EQN 1225 encoders have the same MTTF values, the following calculations apply to both encoder types.

Characteristic value	ECN 1313 / EQN 1325
MTTF	1,666,667 [h]
$MTTF_d$	3,333,334 [h] = 380 years = High
$PFH_{encoder}$	$3*10^{-9}$ [h^{-1}]
CAT / PL	Cat 3 / PL d
SIL	Max. SIL 2 since the encoder is not certified

Table 181: Calculated characteristic values for Heidenhain ECN 1313 and EQN 1325 with diagnosis of encoder evaluation of the ACOPOSmulti SafeMOTION SinCos inverter module

Calculating the characteristic values of the overall system

The following tables show an example of the safety characteristics for the safety functions of the ACOPOSmulti SafeMOTION SinCos inverter module, performance class XXX, in combination with a Heidenhain ECN 1313 or EQN 1325 encoder:

Safety function	PFH	CAT / PL / SIL
STO	$1*10^{-09}$ [h^{-1}]	Cat. 4 / PL e / SIL 3
STO1	$1*10^{-08}$ [h^{-1}]	Cat. 3 / PL d / SIL 2
SBC	$1*10^{-08}$ [h^{-1}]	Cat. 3 / PL d / SIL 2
SOS **SS1** **SS2** **SLS** **SMS** **SDI** **SLI** **Safe Speed**	$6*10^{-09}$ [h^{-1}] + $3*10^{-09}$ [h^{-1}] = $6*10^{-09}$ [h^{-1}]	Cat. 3 / PL d / SIL 2
Safe Homing **SLP** **SMP** **Safe Position**	$6*10^{-09}$ [h^{-1}] + $3*10^{-09}$ [h^{-1}] = $6*10^{-09}$ [h^{-1}] Only with safe encoder mounting (see table D.16, No. 8 and 9, fault exclusion)	Cat. 3 / PL d / SIL 2 Only with safe encoder mounting (see table D.16, No. 8 and 9, fault exclusion)
SBT	$2*10^{-08}$ [h^{-1}] + $3*10^{-09}$ [h^{-1}] = $2.3*10^{-08}$ [h^{-1}]	Cat. 3 / PL d / SIL 2

Table 182: Safety characteristics for 8BVIXXXXSA.XXX-X ACOPOSmulti SafeMOTION SinCos inverter modules in combination with a Heidenhain ECN 1313 or EQN 1325 encoder

6.2.3.3 Mechanical mounting

6.2.3.3.1 Status of the proof of fatigue strength of the encoder mounting

Information:

This functionality is only available in hardware upgrade 1.10.3.x or later!

For B&R motors, the status of the fatigue strength of the encoder mounting is saved in the motor data record.

By setting parameter "General settings - Encoder monitoring - Safe Encoder Mounting" to value "From motor data record", the status of the fatigue strength of the encoder mounting is read out and used to verify the available safety functions.

For motors that have not stored any mounting information in the motor data record, but for which the fatigue strength of the encoder mounting can still be verified, parameter "General settings - Encoder monitoring - Safe Encoder Mounting" must be set to value "Approved by user" so that all safety functions can be used.

For motors for which no proof of fatigue strength of the encoder mounting is provided, parameter "General settings - Encoder monitoring - Safe Encoder Mounting" must be set to value "From motor data record". In this case, proceed as described in 6.2.3.3.3 "Encoder mounting without proof of fatigue strength - Safe lag error monitoring" on page 309.

Information:

The status of the proof of fatigue strength of the encoder mounting stored in the motor data record is not reliable from the point of view of safety. Verification of the available safety function is a standard (non-safe) monitoring operation.

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Encoder monitoring - Safe Encoder Mounting (Hardware upgrade 1.10.3.x and later)</td><td>From motor data record / Approved by user</td><td>Status of the proof of fatigue strength of the encoder mounting<table><tr><th>Value</th><th>Description</th></tr><tr><td>From motor data record</td><td>The status of the encoder mounting is determined using the motor data record.</td></tr><tr><td>Approved by user</td><td>The user confirms safe encoder mounting / no mounting information available in the motor data record.</td></tr></table></td><td>From motor data record</td><td>R1.10</td></tr>
<tr><td>Encoder monitoring - Position error monitoring - Enable

(previously Encoder Position monitoring)</td><td>Enabled/
Disabled</td><td>Enables/Disables monitoring of the position lag error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error monitoring - Enable

(previously Encoder Speed monitoring)</td><td>Enabled/
Disabled</td><td>Activates/Deactivates monitoring of the speed error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position setpoint alive testing (SPA) - Enable

(previously Set position alive testing)</td><td>Enabled/
Disabled</td><td>Activates/Deactivates the monitor that detects whether the position setpoint generated on the SafeMOTION module is frozen.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Disabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position error tolerance

(previously Encoder monitoring Position tolerance (units))</td><td>[units]</td><td>Position lag error tolerance for shaft breakage monitoring</td><td>0</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error tolerance

(previously Encoder monitoring Speed tolerance (units/s))</td><td>[units/s]</td><td>Speed error tolerance for encoder monitoring</td><td>0</td><td>R1.3</td></tr>
</table>

Table 183: SafeMOTION parameter group: General settings - Encoder monitoring

6.2.3.3.2 Encoder mounting with proof of fatigue strength[5]

To prevent errors caused by encoder slippage or shaft breakage, the mechanical mounting of the encoder requires proof of fatigue strength.

This proof and the corresponding mounting guidelines can be provided either by the manufacturer of the measuring instrument or by the manufacturer of the machine.

Danger!

To ensure safe operation up to and including the motor shaft, any errors in the connection between the motor shaft and encoder must be identified and prevented.

Danger!

Proof of fatigue strength for the encoder's mechanical mounting is to be dimensioned to the maximum rotor acceleration. This acceleration value is not permitted to be exceeded in the worst case. The maximum acceleration is monitored on the SafeMOTION module and can be configured using parameter "EUS - Encoder acceleration limit".

Danger!

Mechanical tolerances in the encoder mounting must be taken into account when calculating the residual distance. This residual movement must be taken into account by the safety functions.

Danger!

To ensure safe operation up to and including the motor shaft, any errors in the connection between the motor shaft and encoder must be identified and prevented.
There are specific guidelines that must be followed when installing a functional safety encoder.
The motor manufacturer must ensure that these specifications are adhered to.

[5] This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR, SF_oS_MOTION_ScaledSpeed_BR, SF_oS_MOTION_Position_BR.

Danger!

The frictional connection between the cone-shaped shaft of the rotor and measuring instrument can be dimensioned for maximum rotor acceleration in accordance with the mounting instructions provided by the encoder manufacturer. This acceleration value is not permitted to be exceeded in the worst case. The maximum acceleration is monitored on the SafeMOTION module and can be configured using parameter "EUS - Encoder acceleration limit".

Danger!

If the terminal screw for the coupling ring becomes loose on installed measuring instruments, then the form-fit pin will be the only thing holding the encoder to the motor housing. A movement in accordance with the mounting tolerances is possible. The encoder is not able to register this movement. This residual movement must be taken into account by the safety functions.

6.2.3.3.3 Encoder mounting without proof of fatigue strength - Safe lag error monitoring[6)]

If "General settings - Encoder monitoring" is activated in the SafeMOTION module, in some applications the proof of fatigue strength for the mechanical mounting of the encoder is not required.

The following safety-related restrictions must be taken into account!

Danger!

Only safety functions in which no safe absolute position is monitored are permitted to be used (STO, SBC, SOS, SS1, SS2, SLS, SMS, SLI, SDI, SLA, SBT (only available for ACOPOSmulti SafeMOTION SinCos and ACOPOS P3 SafeMOTION), SLT (only available for ACOPOS P3 SafeMOTION) and Safe Speed).

Danger!

The application must meet the following requirements for safety-related monitoring of the encoder-motor connection:

- **Encoder connection monitoring is only permitted to be used for encoders that are integrated in position control.**
- **Encoder connection monitoring is only permitted to be used for drive systems with synchronous motors.**
- **The encoder must be protected against shearing in standstill (e.g. with encasement in the motor housing)!**
- **Monitoring for position lag errors, speed errors and position setpoints change (Alive Testing) must be enabled in the safety application, and sufficiently strict limits must be monitored!**
- **Safety functions Safe Position, SLP and/or SMP are not permitted to be not be used!**
- **Safe monitoring can only be guaranteed when closed-loop control is enabled.**

Danger!

- **An electrical offset of <90° will not be detected sufficiently.**
- **There is no way to monitor the encoder connection if the setpoint remains constant.**
- **An encoder connection error or an error in encoder evaluation is always assumed as the cause for the lag error.**
- **The error reaction in the standard application to a position lag error or speed error is disabled by the SafeMOTION module (overridden). When lag errors occur, only the error responses STO or STO1 with an induction stop are possible.**

Danger!

Note that an error can result in a forward movement. The maximum angle of rotation φ of the motor shaft during this forward movement depends on the motor being used.

For permanent magnet synchronous motors, φ = 360°/2p. For three-phase induction motors, there is a relatively small angle of rotation between 5° and 15°.

6) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR, SF_oS_MOTION_ScaledSpeed_BR, SF_oS_MOTION_Position_BR.

The maximum speed of the forward movement can be calculated as follows:

$$n_{Jolt} = \frac{1}{2\pi}\sqrt{\frac{6a_{max}}{p_z}}\left[\frac{U}{s}\right]$$

With the maximum acceleration $a_{max} = \frac{M_{max}}{J}\left[\frac{rad}{s^2}\right]$ **And number of motor pole pairs** p_z

Danger!

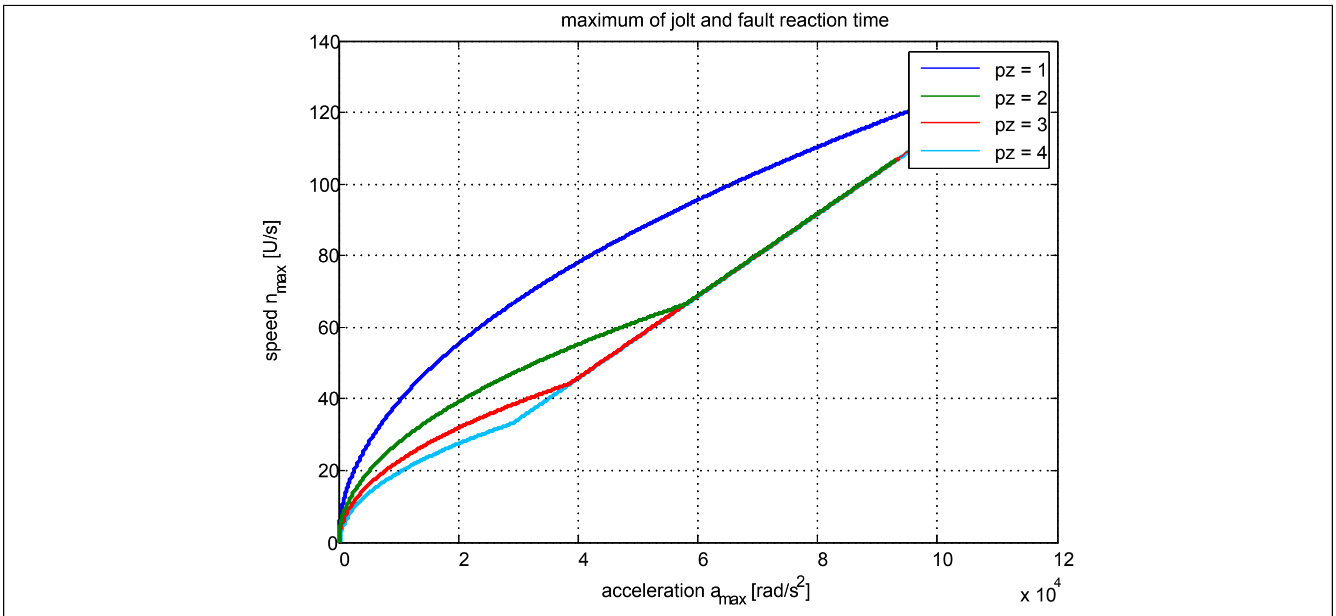
In the worst-case consideration of a safety function, the maximum achievable speed must be the maximum of maximum actuation speed n_{Jolt} **and the speed due to the maximum error response time** $n_{T_{worstcase}}$**.**

$$n_{max} = max(n_{Jolt}, n_{T_{worstcase}}) = max\left(\frac{1}{2\pi}\sqrt{\frac{6a_{max}}{p_z}}, \frac{T_{worstcase}}{2\pi}\cdot a_{max}\right)$$

With the maximum error response time $T_{worstcase} = 7.2[ms]$

The maximum speed n_{max} **resulting from this must be considered together with the speed when the safety function** n_{LIM} **is violated in order to determine the maximum possible speed** $n_{worstcase}$ **at the time of coasting to a stop.**

$$n_{worstcase} = n_{LIM} + n_{max}$$



Information:

In order to check the plausibility of setpoint selection after each power on, the axis must be moved by at least twice the configured lag error limit before the first request of a safety function, which requires a safe encoder evaluation, or at least within 15 min.
If this is not done, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state. The "S_NotErrFUNC" output on the function block is reset, and the drive loses all torque/power and coasts to a stop!
In the event of an error, a synchronous axis will no longer be synchronous.

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

Information:

A 24-hour timeout begins after successfully checking the plausibility of the setpoint.
The timeout is reset any time the position setpoint changes by more than twice the position lag error tolerance.
If the position setpoint does not change during 24 hours of continuous controller operation, then the SafeMOTION module will switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state. The "S_NotErrFUNC" output on the function block is reset, and the drive loses all torque/power and coasts to a stop! In the event of an error, a synchronous axis will no longer be synchronous.

The following parameters are relevant for safe monitoring of the encoder-motor shaft connection (Encoder Monitoring):

Group: General settings - Encoder monitoring (previously *Encoder Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Encoder monitoring - Safe Encoder Mounting (Hardware upgrade 1.10.3.x and later)</td><td>From motor data record / Approved by user</td><td>Status of the proof of fatigue strength of the encoder mounting<table><tr><th>Value</th><th>Description</th></tr><tr><td>From motor data record</td><td>The status of the encoder mounting is determined using the motor data record.</td></tr><tr><td>Approved by user</td><td>The user confirms safe encoder mounting / no mounting information available in the motor data record.</td></tr></table></td><td>From motor data record</td><td>R1.10</td></tr>
<tr><td>Encoder monitoring - Position error monitoring - Enable

(previously Encoder Position monitoring)</td><td>Enabled/ Disabled</td><td>Enables/Disables monitoring of the position lag error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error monitoring - Enable

(previously Encoder Speed monitoring)</td><td>Enabled/ Disabled</td><td>Activates/Deactivates monitoring of the speed error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position setpoint alive testing (SPA) - Enable

(previously Set position alive testing)</td><td>Enabled/ Disabled</td><td>Activates/Deactivates the monitor that detects whether the position setpoint generated on the SafeMOTION module is frozen.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Disabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position error tolerance

(previously Encoder monitoring Position tolerance (units))</td><td>[units]</td><td>Position lag error tolerance for shaft breakage monitoring</td><td>0</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error tolerance

(previously Encoder monitoring Speed tolerance (units/s))</td><td>[units/s]</td><td>Speed error tolerance for encoder monitoring</td><td>0</td><td>R1.3</td></tr>
</table>

Table 184: SafeMOTION parameter group: General settings - Encoder monitoring

Group: General settings - Encoder Unit System (previously *Encoder Unit System*)

Parameter	Unit	Description	Default value	Starting in Safety Release
EUS - Encoder acceleration limit (previously *Maximum acceleration (rad/s² or mm/s²)*)	[rad/s²] or [mm/s²]	Maximum permissible encoder acceleration	100000	R 1.4

Table 185: SafeMOTION parameter group: General settings - Encoder Unit System

Information:

The physical drive speed is not permitted to exceed the value set for parameter "EUS - Maximum speed to normalize speed range"; otherwise, the SafeMOTION module will switch to the error state!

Danger!

If the manufacturer of the measuring instrument specifies a limitation of the maximum acceleration, this must be monitored by the SafeMOTION module. The acceleration to be monitored can be configured using parameter "EUS - Encoder acceleration limit".

Danger!

Incorrectly configuring the unit system can result in dangerous situations.
When validating the application, the monitored speed limits must be intentionally violated and their physical values tested! The same must also be done for the monitored direction of rotation!

Danger!

The machine manufacturer is responsible for determining whether or not the application is suited for safe encoder connection monitoring if there is no mechanical mechanism for detecting encoder shaft breakage.
The machine manufacturer is responsible for ensuring that the safe encoder monitoring has been configured correctly!

Danger!

Encoder connection monitoring is only permitted to be used in a safety-related capacity if the aforementioned requirements for the application have been fulfilled!

6.2.3.3.3.1 Activating monitoring[7)]

The following parameters must be set to "Enabled" in SafeDESIGNER in order to enable safe encoder connection monitoring:

- "Encoder monitoring - Position error monitoring - Enable" = Enabled
- "Encoder monitoring - Speed error monitoring - Enable" = Enabled
- "Encoder monitoring - Position setpoint alive testing (SPA) - Enable" = Enabled

Danger!

In order to ensure safety-related monitoring of the encoder/motor connection, all three parameters "Encoder monitoring - Position error monitoring - Enable", "Encoder monitoring - Speed error monitoring - Enable" and "Encoder monitoring - Position setpoint alive testing (SPA) - Enable" must be set to "Enabled"!
If this is not the case, then the monitoring system cannot be used for safety purposes and a mechanical solution for detecting errors must be implemented!

6.2.3.3.3.2 Configuration rule for position lag error tolerance[8)]

The position lag error tolerance must be set large enough to ensure availability. This can be done by first measuring the position lag error under the highest influence of disturbance variables and at maximum acceleration and then setting the position lag error tolerance accordingly higher.

Danger!

The position lag error tolerance is not permitted to be higher than half of one pole length!

If the safety function is activated, the size of the position lag error tolerance value affects how long it will take to look for errors and therefore also the error response time and estimation of the residual distance.

This must be taken into account by the machine manufacturer in the risk analysis!

Information:

Due to rounding errors, a reserve of 1 unit should be taken into account with the parameter "Encoder monitoring - Position error tolerance".

7) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR, SF_oS_MOTION_ScaledSpeed_BR, SF_oS_MOTION_Position_BR.

8) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR, SF_oS_MOTION_ScaledSpeed_BR, SF_oS_MOTION_Position_BR.

6.2.3.3.3.3 Configuration rule for speed error tolerance[9)]

The speed error tolerance must be set large enough to ensure availability.
This can be done by first measuring the speed error under the highest influence of disturbance variables and reference variables (e.g. at maximum acceleration) and then setting the speed error tolerance accordingly higher.

Danger!

When the safety function is enabled, the size of the speed error tolerance value affects how long it will take to look for errors and therefore also the error response time and estimation of the residual distance.

This must be taken into account by the machine manufacturer in the risk analysis!

Information:

Due to rounding errors, a reserve of 1 unit/s should be taken into account with the parameter "Encoder monitoring - Speed error tolerance".

9) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR, SF_oS_MOTION_ScaledSpeed_BR, SF_oS_MOTION_Position_BR.

6.2.4 Safe speed observer

Information:

A non-safe encoder (onboard or plug-in card) is necessary to check the plausibility of the safely observed speed.

Information:

No safe position is determined. Safety functions that need a safe position cannot be used in combination with the safe speed observer.

The safe speed observer SSO monitors the actual speed of a synchronous motor. Safe evaluation of the phase currents and PWM pulse widths and knowledge of the motor characteristics ensures reliable evaluation of the motor speed.

For additional information, see 6.4.5 "Safe Speed Observer, SSO" on page 339.

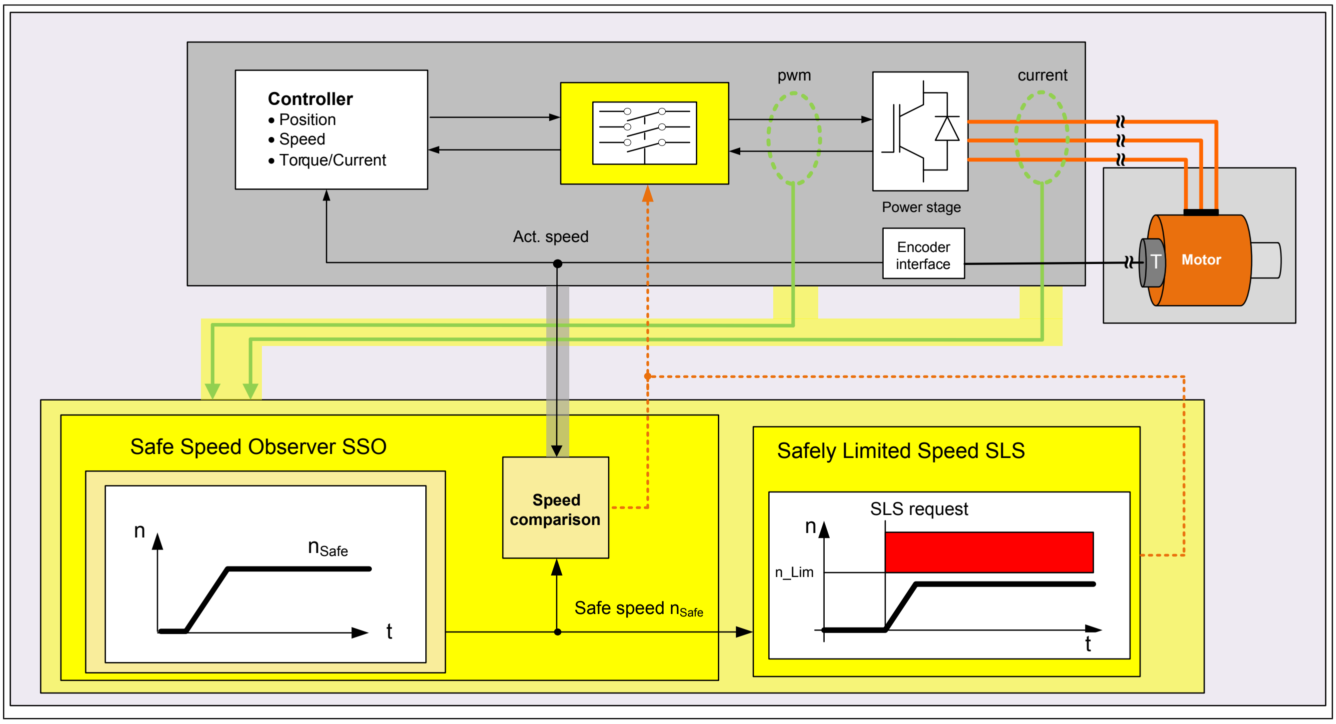


Figure 68: Safe Speed Observer (SSO) - General functional description

6.2.5 Safe current measurement

Safe current measurement is a component of safety functions SBT, SLT and SSO.

The safe current measurement determines stator-fixed current space vector i_S (i_α,i_β) from the measured phase currents using Clarke's transformation. The value of the current space vector |i_S (i_α,i_β)| is hereinafter referred to as safe current i_S.

6.2.5.1 Accuracy of the safe current

Accuracy of the safe current i_ε depends on the permissible measuring error of the current transformers. This is specific to the performance class of the inverter module used.

Danger!

The accuracy of the safe current indicates the maximum undetectable/undiagnosable error of the amount of the safe current space vector. This error must be taken into account in the configuration of safety functions SBT and SLT.

Danger!

The accuracy of the safe current only applies up to the continuous current of the performance class used. It is not permitted to use a safety function that should monitor or detect a current above the continuous current of the performance class used.

For ACOPOSmulti SafeMOTION SinCos, the following table applies to the accuracy of the safe current:

Performance class (ACOPOSmulti)	Continuous current [A]	Accuracy of the safe current
8BVI0014HxSA	1.9	108.6 mA
8BVI0028HxSA	3.8	293 mA
8BVI0055HxSA	7.6	488.2 mA
8BVI0110HxSA	15.1	976.6 mA
8BVI0220HxSA	22	1101.6 mA
8BVI0330HxSA	33	2406.4 mA
8BVI0440HxSA	44	2406.4 mA
8BVI0660HxSA	66	4.813 A
8BVI0880HxSA	88	4.813 A
8BVI1650HxSA	165	7.344 A

Information:

The accuracy of the safe current for the ACOPOS P3 SafeMOTION servo drive is specified in the respective data sheet.

6.3 Safety characteristics of integrated safety functions

The safety characteristics have been calculated for the individual safety functions and grouped together in the following blocks:

- Safe Torque Off (STO), Safe Stop 1 (SS1) time-monitored
→ The two safe pulse disabling channels and their activation are included in evaluation.

- Safe Torque Off (STO1) single-channel
→ Only one safe pulse disabling channel and its activation are included in evaluation.

- Safe Brake Control (SBC)
→ The safe motor brake output and its activation are included in the evaluation. The brake itself must be taken into account explicitly in the safety chain!

- Safe Operating Stop (SOS), Safe Stop 1 (SS1) speed-monitored, Safe Stop 2 (SS2), Safely Limited Speed (SLS), Safe Direction (SDI), Safely Limited Increment (SLI), Safely Limited Acceleration (SLA), Safe Maximum Speed (SMS), Safely Limited Position (SLP), Safe Maximum Position (SMP), Safe Homing, Remanent Safe Position (RSP)
→ The two safe pulse disabling channels and their activation are included in the evaluation. In addition, safe evaluation of the encoder and safe position detection are also taken into account.
The safety characteristics of the encoder itself must also be taken into account!

- Safe Brake Test (SBT)
→ Safe evaluation of the encoder, safe position detection, safe current measurement and the safe motor holding brake output and its activation are included in the evaluation.
The safety characteristics of the encoder itself must also be taken into account!
The brake itself must be taken into account explicitly in the safety chain.
- Safely Limited Torque (SLT) and Safely Limited Speed (SLS with SSO)
→ The two safe pulse disabling channels and their activation are included in the evaluation. The safe current measurement is also taken into account.

Danger!

To determine the overall PFH value for safety functions that require safe encoder evaluation, the PFH value of the encoder being used must be taken into account.

For a detailed description, see 6.2.3.1 "Assessing the safety integrity of the overall system" on page 298!

$\mathbf{PFH_{TOTAL} = PFH_{SOS,SS1,SS2,SLS,SMS,SDI,SLI,SLA,SLP,SMP} + PFH_{Encoder}}$

Danger!

It is the machine manufacturer's responsibility to read and adhere to the technical documentation (product catalog / user's manual) provided for the measuring instrument.

Danger!

If the technical documentation (product catalog / user's manual) for the measuring instrument explicitly specifies that the bit error rate must be verified, then the user needs to implement this verification procedure in the application. This verification is not necessary if using B&R EnDat 2.2 encoder cables and certain B&R motors.

6.3.1 Safety characteristics of integrated safety functions ACOPOSmulti SafeMOTION EnDat 2.2

Safety function	Criteria	Characteristic dependent on module width [1]			
		1	2	4	8
Safe Torque Off (STO), Safe Stop 1 (SS1), time-monitored	Maximum safety category per EN ISO 13849	Cat. 4			
	Maximum performance level per EN ISO 13849	PL e			
	Maximum safety integrity level per IEC 62061	SIL 3			
	Maximum safety integrity level per IEC 61508	SIL 3			
	PFH (probability of dangerous failure per hour)	$<5*10^{-10}$			
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<9*10^{-05}$			
	PTI (proof test interval) [2]	Max. 20 years			
	DC (diagnostic coverage)	>95%			
	MTTFd (mean time to dangerous failure) [3]	2500 years			

Table 186: Safety characteristics: Safe Torque Off (STO), Safe Stop 1 (SS1) time-monitored

1) ACOPOSmulti inverter modules have different module widths according to their performance class. Different components and/or switching elements are used depending on the performance class / module width, which has a direct effect on the characteristics of safe pulse disabling. The module width is listed in the technical data for the respective ACOPOSmulti inverter module.
2) Corresponds to the mission time of the module.
3) Value determined according to Apfeld, R.; Bömer, T.; Hauke, M.; Huelke, M.; Schaefer, M.: Practical experience with DIN EN ISO 13849-1.openautomation (2009) No. 6, p. 34-37 (www.dguv.de/ifa/de/pub/grl/pdf/2009_249.pdf).

Safety function	Criteria	Characteristic dependent on module width [1]			
		1	2	4	8
Safe Torque Off, single-channel (STO1)	Maximum safety category per EN ISO 13849	Cat. 3			
	Maximum performance level per EN ISO 13849	PL d			
	Maximum safety integrity level per IEC 62061	SIL 2			
	Maximum safety integrity level per IEC 61508	SIL 2			
	PFH (probability of dangerous failure per hour)	$<8*10^{-09}$			
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<1.4*10^{-03}$			
	PTI (proof test interval) [2]	Max. 20 years			
	DC (diagnostic coverage)	>94%			
	MTTFd (mean time to dangerous failure)	>167 years	>157 years	>143 years	>85 years

Table 187: Safety characteristics: Safe Torque Off single-channel (STO1)

1) ACOPOSmulti inverter modules have different module widths according to their performance class. Different components and/or switching elements are used depending on the performance class / module width, which has a direct effect on the characteristics of safe pulse disabling. The module width is listed in the technical data for the respective ACOPOSmulti inverter module.
2) Corresponds to the mission time of the module.

Safety function	Criteria	Characteristic dependent on module width [1]			
		1	2	4	8
Safe Brake Control (SBC)	Maximum safety category per EN ISO 13849	Cat. 3			
	Maximum performance level per EN ISO 13849	PL d			
	Maximum safety integrity level per IEC 62061	SIL 2			
	Maximum safety integrity level per IEC 61508	SIL 2			
	PFH (probability of dangerous failure per hour)	$<1*10^{-08}$			
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<1.75*10^{-03}$			
	PTI (proof test interval) [2]	Max. 20 years			
	DC (diagnostic coverage)	>95%			
	MTTFd (mean time to dangerous failure)	>153 years	>135 years	>117 years	>56 years

Table 188: Safety characteristics: Safe Brake Control (SBC)

1) ACOPOSmulti inverter modules have different module widths according to their performance class. Different components and/or switching elements are used depending on the performance class / module width, which has a direct effect on the characteristics of safe pulse disabling. The module width is listed in the technical data for the respective ACOPOSmulti inverter module.
2) Corresponds to the mission time of the module.

Safety function	Criteria	Characteristic dependent on module width 1)			
		1	2	4	8
Safe Operating Stop (SOS), Safe Stop 1 (SS1), Safe Stop 2 (SS2), Safely Limited Speed (SLS), Safe Direction (SDI), Safely Limited Increment (SLI), Safely Limited Acceleration (SLA), Safe Maximum Speed (SMS), Safely Limited Position (SLP), Safe Maximum Position (SMP), Safe Homing Remanent Safe Position (RSP)	Maximum safety category per EN ISO 13849	Cat. 3			
	Maximum performance level per EN ISO 13849	PL d			
	Maximum safety integrity level per IEC 62061	SIL 2			
	Maximum safety integrity level per IEC 61508	SIL 2			
	PFH (probability of dangerous failure per hour)	$<5*10^{-9}$			
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	Cannot be used since continuous encoder evaluation is required!			
	PTI (proof test interval) 2)	Max. 20 years			
	DC (diagnostic coverage)	>95%			
	MTTFd (mean time to dangerous failure)	>109 years	>100 years	>89 years	>49 years

Table 189: Safety characteristics: Safe Operating Stop (SOS), Safe Stop 1 (SS1), Safe Stop 2 (SS2), Safely Limited Speed (SLS), Safe Direction (SDI), Safely Limited Increment (SLI), Safely Limited Acceleration (SLA), Safe Maximum Speed (SMS), Safely Limited Position (SLP), Safe Maximum Position (SMP), Safe Homing

1) ACOPOSmulti inverter modules have different module widths according to their performance class. Different components and/or switching elements are used depending on the performance class / module width, which has a direct effect on the characteristics of safe pulse disabling. The module width is listed in the technical data for the respective ACOPOSmulti inverter module.
2) Corresponds to the mission time of the module.

6.3.2 Safety characteristics of integrated safety functions ACOPOSmulti SafeMOTION SinCos

Safety function	Criteria	Characteristic dependent on module width [1]		
		1	2	4
Safe Torque Off (STO), Safe Stop 1 (SS1), time-monitored	Maximum safety category per EN ISO 13849	Cat. 4		
	Maximum performance level per EN ISO 13849	PL e		
	Maximum safety integrity level per IEC 62061	SIL 3		
	Maximum safety integrity level per IEC 61508	SIL 3		
	PFH (probability of dangerous failure per hour)	$<1*10^{-09}$		
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<1.5*10^{-04}$		
	PTI (proof test interval) [2]	Max. 20 years		
	DC (diagnostic coverage)	>98%		
	MTTFd (mean time to dangerous failure) [3]	2200 years		

Table 190: Safety characteristics: Safe Torque Off (STO), Safe Stop 1 (SS1) time-monitored

1) ACOPOSmulti inverter modules have different module widths according to their performance class. Different components and/or switching elements are used depending on the performance class / module width, which has a direct effect on the characteristics of safe pulse disabling. The module width is listed in the technical data for the respective ACOPOSmulti inverter module.
2) Corresponds to the mission time of the module.
3) Value determined according to Apfeld, R.; Bömer, T.; Hauke, M.; Huelke, M.; Schaefer, M.: Practical experience with DIN EN ISO 13849-1.openautomation (2009) No. 6, p. 34-37 (www.dguv.de/ifa/de/pub/grl/pdf/2009_249.pdf).

Safety function	Criteria	Characteristic dependent on module width [1]		
		1	2	4
Safe Torque Off, single-channel (STO1)	Maximum safety category per EN ISO 13849	Cat. 3		
	Maximum performance level per EN ISO 13849	PL d		
	Maximum safety integrity level per IEC 62061	SIL 2		
	Maximum safety integrity level per IEC 61508	SIL 2		
	PFH (probability of dangerous failure per hour)	$<1*10^{-08}$		
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<1.5*10^{-03}$		
	PTI (proof test interval) [2]	Max. 20 years		
	DC (diagnostic coverage)	>97%		
	MTTFd (mean time to dangerous failure)	>220 years	>220 years	>180 years

Table 191: Safety characteristics: Safe Torque Off single-channel (STO1)

1) ACOPOSmulti inverter modules have different module widths according to their performance class. Different components and/or switching elements are used depending on the performance class / module width, which has a direct effect on the characteristics of safe pulse disabling. The module width is listed in the technical data for the respective ACOPOSmulti inverter module.
2) Corresponds to the mission time of the module.

Safety function	Criteria	Characteristic dependent on module width [1]		
		1	2	4
Safe Brake Control (SBC)	Maximum safety category per EN ISO 13849	Cat. 3		
	Maximum performance level per EN ISO 13849	PL d		
	Maximum safety integrity level per IEC 62061	SIL 2		
	Maximum safety integrity level per IEC 61508	SIL 2		
	PFH (probability of dangerous failure per hour)	$<1*10^{-08}$		
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<1*10^{-04}$		
	PTI (proof test interval) [2]	Max. 20 years		
	DC (diagnostic coverage)	>97%		
	MTTFd (mean time to dangerous failure)	>300 years	>300 years	>300 years

Table 192: Safety characteristics: Safe Brake Control (SBC)

1) ACOPOSmulti inverter modules have different module widths according to their performance class. Different components and/or switching elements are used depending on the performance class / module width, which has a direct effect on the characteristics of safe pulse disabling. The module width is listed in the technical data for the respective ACOPOSmulti inverter module.
2) Corresponds to the mission time of the module.

Safety function	Criteria	Characteristic dependent on module width 1)		
		1	2	4
Safe Operating Stop (SOS), Safe Stop 1 (SS1), Safe Stop 2 (SS2), Safely Limited Speed (SLS), Safe Direction (SDI), Safely Limited Increment (SLI), Safely Limited Acceleration (SLA), Safe Maximum Speed (SMS), Safely Limited Position (SLP), Safe Maximum Position (SMP), Safe Homing	Maximum safety category per EN ISO 13849	Max. Cat. 4 with certified measuring instrument Max. Cat. 3 with non-certified measuring instrument		
	Maximum performance level per EN ISO 13849	Max. PL e with certified measuring instrument Max. PL d with non-certified measuring instrument		
	Maximum safety integrity level per IEC 62061	Max. SIL 3 with certified measuring instrument Max. SIL 2 with non-certified measuring instrument		
	Maximum safety integrity level per IEC 61508	Max. SIL 3 with certified measuring instrument Max. SIL 2 with non-certified measuring instrument		
	PFH (probability of dangerous failure per hour)	$<5*10^{-9}$		
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	Cannot be used since continuous encoder evaluation is required!		
	PTI (proof test interval) 2)	Max. 20 years		
	DC (diagnostic coverage)	>95%		
	MTTFd (mean time to dangerous failure)	>90 years	>85 years	>80 years

Table 193: Safety characteristics: Safe Operating Stop (SOS), Safe Stop 1 (SS1), Safe Stop 2 (SS2), Safely Limited Speed (SLS), Safe Direction (SDI), Safely Limited Increment (SLI), Safely Limited Acceleration (SLA), Safe Maximum Speed (SMS), Safely Limited Position (SLP), Safe Maximum Position (SMP), Safe Homing

1) ACOPOSmulti inverter modules have different module widths according to their performance class. Different components and/or switching elements are used depending on the performance class / module width, which has a direct effect on the characteristics of safe pulse disabling. The module width is listed in the technical data for the respective ACOPOSmulti inverter module.
2) Corresponds to the mission time of the module.

Safety function	Criteria	Characteristic dependent on module width 1)		
		1	2	4
Safe Brake Test (SBT)	Maximum safety category per EN ISO 13849	Cat. 3		
	Maximum performance level per EN ISO 13849	PL d		
	Maximum safety integrity level per IEC 62061	SIL 2		
	Maximum safety integrity level per IEC 61508	SIL 2		
	PFH (probability of dangerous failure per hour)	$<1*10^{-08}$		
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	Cannot be used since continuous encoder evaluation is required!		
	PTI (proof test interval) 2)	Max. 20 years		
	DC (diagnostic coverage)	>97%		
	MTTFd (mean time to dangerous failure)	>65 years	>55 years	>45 years

Table 194: Safety characteristics: Safe Brake Test (SBT)

1) ACOPOSmulti inverter modules have different module widths according to their performance class. Different components and/or switching elements are used depending on the performance class / module width, which has a direct effect on the characteristics of safe pulse disabling. The module width is listed in the technical data for the respective ACOPOSmulti inverter module.
2) Corresponds to the mission time of the module.

6.3.3 Safety characteristics of integrated safety functions ACOPOSmotor SafeMOTION

Safety function	Criteria	Characteristic value
Safe Torque Off (STO), Safe Stop 1 (SS1), time-monitored	Maximum safety category per EN ISO 13849	Cat. 4
	Maximum performance level per EN ISO 13849	PL e
	Maximum safety integrity level per IEC 62061	SIL 3
	Maximum safety integrity level per IEC 61508	SIL 3
	PFH (probability of dangerous failure per hour)	$<9*10^{-10}$
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<1.5*10^{-04}$
	PTI (proof test interval) 1)	Max. 20 years
	DC (diagnostic coverage)	>95%
	MTTFd (mean time to dangerous failure) 2)	2500 years

Table 195: Safety characteristics: Safe Torque Off (STO), Safe Stop 1 (SS1) time-monitored

1) Corresponds to the mission time of the module.
2) Value determined according to Apfeld, R.; Bömer, T.; Hauke, M.; Huelke, M.; Schaefer, M.: Practical experience with DIN EN ISO 13849-1.openautomation (2009) No. 6, p. 34-37 (www.dguv.de/ifa/de/pub/grl/pdf/2009_249.pdf).

Safety function	Criteria	Characteristic value
Safe Torque Off, single-channel (STO1)	Maximum safety category per EN ISO 13849	Cat. 3
	Maximum performance level per EN ISO 13849	PL d
	Maximum safety integrity level per IEC 62061	SIL 2
	Maximum safety integrity level per IEC 61508	SIL 2
	PFH (probability of dangerous failure per hour)	$<1*10^{-08}$
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<1.75*10^{-03}$
	PTI (proof test interval) 1)	Max. 20 years
	DC (diagnostic coverage)	>94%
	MTTFd (mean time to dangerous failure)	>70 years

Table 196: Safety characteristics: Safe Torque Off single-channel (STO1)

1) Corresponds to the mission time of the module.

Safety function	Criteria	Characteristic value
Safe Brake Control (SBC)	Maximum safety category per EN ISO 13849	Cat. 3
	Maximum performance level per EN ISO 13849	PL d
	Maximum safety integrity level per IEC 62061	SIL 2
	Maximum safety integrity level per IEC 61508	SIL 2
	PFH (probability of dangerous failure per hour)	$<1*10^{-08}$
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<1.75*10^{-08}$
	PTI (proof test interval) 1)	Max. 20 years
	DC (diagnostic coverage)	>95%
	MTTFd (mean time to dangerous failure)	>153 years

Table 197: Safety characteristics: Safe Brake Control (SBC)

1) Corresponds to the mission time of the module.

Safety function	Criteria	Characteristic value
Safe Operating Stop (SOS), Safe Stop 1 (SS1), Safe Stop 2 (SS2), Safely Limited Speed (SLS), Safe Direction (SDI), Safely Limited Increment (SLI), Safely Limited Acceleration (SLA), Safe Maximum Speed (SMS), Safely Limited Position (SLP), Safe Maximum Position (SMP), Safe Homing Remanent Safe Position (RSP)	Maximum safety category per EN ISO 13849	Cat. 3
	Maximum performance level per EN ISO 13849	PL d
	Maximum safety integrity level per IEC 62061	SIL 2
	Maximum safety integrity level per IEC 61508	SIL 2
	PFH (probability of dangerous failure per hour) 1)	$<1*10^{-08}$
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<1.75*10^{-03}$
	PTI (proof test interval) 2)	Max. 20 years
	DC (diagnostic coverage)	>95%
	MTTFd (mean time to dangerous failure)	>45 years

Table 198: Safety characteristics: Safe Operating Stop (SOS), Safe Stop 1 (SS1), Safe Stop 2 (SS2), Safely Limited Speed (SLS), Safe Direction (SDI), Safely Limited Increment (SLI), Safely Limited Acceleration (SLA), Safe Maximum Speed (SMS), Safely Limited Position (SLP), Safe Maximum Position (SMP), Safe Homing

1) The encoder is not taken into consideration here! To determine the overall PFH value for safety functions that require safe encoder evaluation, the PFH value of the encoder being used must be taken into consideration. See 6.3 "Safety characteristics of integrated safety functions " on page 316.

2) Corresponds to the mission time of the module.

6.3.4 Safety characteristics of integrated safety functions ACOPOS P3 SafeMOTION

Safety function	Criteria	Characteristic value
Safe Torque Off (STO), Safe Stop 1 (SS1), time-monitored	Maximum safety category per EN ISO 13849	Cat. 4
	Maximum performance level per EN ISO 13849	PL e
	Maximum safety integrity level per IEC 62061	SIL 3
	Maximum safety integrity level per IEC 61508	SIL 3
	PFH (probability of dangerous failure per hour)	$<2.0*10^{-9}$
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<4.0*10^{-4}$
	PTI (proof test interval) 1)	Max. 20 years
	DC (diagnostic coverage)	>95%
	MTTFd (mean time to dangerous failure) 2)	150 years

Table 199: Safety characteristics: Safe Torque Off (STO), Safe Stop 1 (SS1) time-monitored

1) Corresponds to the mission time of the module.
2) Value determined according to Apfeld, R.; Bömer, T.; Hauke, M.; Huelke, M.; Schaefer, M.: Practical experience with DIN EN ISO 13849-1.openautomation (2009) No. 6, p. 34-37 (www.dguv.de/ifa/de/pub/grl/pdf/2009_249.pdf).

Safety function	Criteria	Characteristic value
Safe Torque Off, single-channel (STO1)	Maximum safety category per EN ISO 13849	Cat. 3
	Maximum performance level per EN ISO 13849	PL d
	Maximum safety integrity level per IEC 62061	SIL 2
	Maximum safety integrity level per IEC 61508	SIL 2
	PFH (probability of dangerous failure per hour)	$<3.5*10^{-9}$
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<6.0*10^{-4}$
	PTI (proof test interval) 1)	Max. 20 years
	DC (diagnostic coverage)	>95%
	MTTFd (mean time to dangerous failure)	150 years

Table 200: Safety characteristics: Safe Torque Off single-channel (STO1)

1) Corresponds to the mission time of the module.

Safety function	Criteria	Characteristic value
Safe Brake Control (SBC)	Maximum safety category per EN ISO 13849	Cat. 3
	Maximum performance level per EN ISO 13849	PL d
	Maximum safety integrity level per IEC 62061	SIL 2
	Maximum safety integrity level per IEC 61508	SIL 2
	PFH (probability of dangerous failure per hour)	$<1.0*10^{-9}$
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<2.0*10^{-4}$
	PTI (proof test interval) 1)	Max. 20 years
	DC (diagnostic coverage)	>95%
	MTTFd (mean time to dangerous failure)	200 years
	Maximum output current	See the technical data for the ACOPOS P3 8EI SafeMOTION servo drive.

Table 201: Safety characteristics: Safe Brake Control (SBC)

1) Corresponds to the mission time of the module.

Safety function	Criteria	Characteristic value
Safe Operating Stop (SOS), Safe Stop 1 (SS1), Safe Stop 2 (SS2), Safely Limited Speed (SLS), Safe Direction (SDI), Safely Limited Increment (SLI), Safely Limited Acceleration (SLA), Safe Maximum Speed (SMS), Safely Limited Position (SLP), Safe Maximum Position (SMP), Safe Homing Remanent Safe Position (RSP)	Maximum safety category per EN ISO 13849	Cat. 3
	Maximum performance level per EN ISO 13849	PL d
	Maximum safety integrity level per IEC 62061	SIL 2
	Maximum safety integrity level per IEC 61508	SIL 2
	PFH (probability of dangerous failure per hour) [1)]	$<2.5*10^{-8}$
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<3.5*10^{-3}$
	PTI (proof test interval) [2)]	Max. 20 years
	DC (diagnostic coverage)	>95%
	MTTFd (mean time to dangerous failure)	50 years

Table 202: Safety characteristics: Safe Operating Stop (SOS), Safe Stop 1 (SS1), Safe Stop 2 (SS2), Safely Limited Speed (SLS), Safe Direction (SDI), Safely Limited Increment (SLI), Safely Limited Acceleration (SLA), Safe Maximum Speed (SMS), Safely Limited Position (SLP), Safe Maximum Position (SMP), Safe Homing

1) The encoder is not taken into account here! To determine the overall PFH value for safety functions that require safe encoder evaluation, the PFH value of the encoder being used must be taken into account. See 6.3 "Safety characteristics of integrated safety functions " on page 316.
2) Corresponds to the mission time of the module.

Safety function	Criteria	Characteristic value
Safe Brake Test (SBT)	Maximum safety category per EN ISO 13849	Cat. 3
	Maximum performance level per EN ISO 13849	PL d
	Maximum safety integrity level per IEC 62061	SIL 2
	Maximum safety integrity level per IEC 61508	SIL 2
	PFH (probability of dangerous failure per hour)	$<2.5*10^{-8}$
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<4.0*10^{-3}$
	PTI (proof test interval)	Max. 20 years
	DC (diagnostic coverage)	>95%
	MTTFd (mean time to dangerous failure)	30 years

Table 203: Safety characteristics: Safe Brake Test (SBT)

1) Corresponds to the mission time of the module.

Safety function	Criteria	Characteristic value
Safely Limited Torque (SLT)	Maximum safety category per EN ISO 13849	Cat. 3
	Maximum performance level per EN ISO 13849	PL d
	Maximum safety integrity level per IEC 62061	SIL 2
	Maximum safety integrity level per IEC 61508	SIL 2
	PFH (probability of dangerous failure per hour)	$<2.5*10^{-8}$
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<3.5*10^{-3}$
	PTI (proof test interval)	Max. 20 years
	DC (diagnostic coverage)	>95%
	MTTFd (mean time to dangerous failure)	30 years

Table 204: Safety characteristics: Safely Limited Torque (SLT)

1) Corresponds to the mission time of the module.

Safety function	Criteria	Characteristic value
Safely Limited Speed (SLS with SSO)	Maximum safety category per EN ISO 13849	Cat. 3
	Maximum performance level per EN ISO 13849	PL d
	Maximum safety integrity level per IEC 62061	SIL 2
	Maximum safety integrity level per IEC 61508	SIL 2
	PFH (probability of dangerous failure per hour)	$<2.5*10^{-8}$
	PFD (probability of dangerous failure on demand) with a proof test interval of 20 years	$<3.5*10^{-3}$
	PTI (proof test interval)	Max. 20 years
	DC (diagnostic coverage)	>95%
	MTTFd (mean time to dangerous failure)	30 years

Table 205: Safety characteristics: Safely Limited Speed (SLS with SSO)

1) Corresponds to the mission time of the module.

6.4 Integrated safety functions

Information:

If a safety function is not used in the application, then the respective input must remain open.

The following safety functions are supported by the SafeMOTION module:

Safety function	ACOPOSmulti SafeMOTION		EN ISO 13849-1		EN 61508 / EN 62061		Safe Encoder evaluation Necessary
	EnDat 2.2	SinCos	EnDat 2.2	SinCos	EnDat 2.2	SinCos	
	Starting in Safety Release						
Safe Torque Off (STO)	R 1.3	R 1.4	PL e / Cat. 4	PL e / Cat. 4	SIL 3	SIL 3	No
Safe Torque Off One Channel (STO1)	R 1.3	R 1.4	PL d / Cat. 3	PL d / Cat. 3	SIL 2	SIL 2	No
Safe Operation Stop (SOS)	R 1.3	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safe Stop 1 (SS1)	R 1.3	R 1.4	Time-based monitoring: PL e / Cat. 4 Ramp-based monitoring: PL d / Cat. 3	Time-based monitoring: PL e / Cat. 4 Ramp-based monitoring: Max. PL e / Cat. 4, depends on the encoder used	Time-based monitoring: SIL 3 Ramp-based monitoring: SIL 2	Time-based monitoring: SIL 3 Ramp-based monitoring: Max. SIL 3, Depends on the encoder used	Time-based monitoring: No Ramp-based monitoring: Yes
Safe Stop 2 (SS2)	R 1.3	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safely Limited Speed (SLS)	R 1.3	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safe Maximum Speed (SMS)	R 1.3	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safe Direction (SDI)	R 1.3	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safely Limited Increment (SLI)	R 1.3	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safely Limited Acceleration (SLA)	R 1.9	R 1.9	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safe Brake Control (SBC)	R 1.3	R 1.4	PL d / Cat. 3	PL d / Cat. 3	SIL 2	SIL 2	No
Safely Limited Position (SLP)	R 1.4	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safe Maximum Position (SMP)	R 1.4	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safe Homing	R 1.4	R 1.4	PL d / Cat. 3	Max. PL e / Cat. 4, depends on the encoder used	SIL 2	Max. SIL 3, Depends on the encoder used	Yes
Safe Brake Test (SBT)	-	R 1.7	-	Max. PL d / Cat. 3, depends on the encoder used	-	Max. SIL 2, Depends on the encoder used	Yes
Remanent Safe Position (RSP)	R 1.9	-	PL d / Cat. 3	-	SIL 2	-	Yes

Table 206: ACOPOSmulti SafeMOTION: Safety functions and associated safety levels

Safety function	ACOPOSmotor SafeMOTION	EN ISO 13849-1	EN 61508 / EN 62061	Safe Encoder evaluation Necessary
	Starting in Safety Release			
Safe Torque Off (STO)	R 1.10	PL e / Cat. 4	SIL 3	No
Safe Torque Off One Channel (STO1)	R 1.10	PL d / Cat. 3	SIL 2	No
Safe Operation Stop (SOS)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Stop 1 (SS1)	R 1.10	Time-based monitoring: PL e / Cat. 4 Ramp-based monitoring: PL d / Cat. 3	Time-based monitoring: SIL 3 Ramp-based monitoring: SIL 2	Time-based monitoring: No Ramp-based monitoring: Yes
Safe Stop 2 (SS2)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safely Limited Speed (SLS)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Maximum Speed (SMS)	R 1.10	PL d / Cat. 3	SIL 2	Yes

Table 207: ACOPOSmotor SafeMOTION: Safety functions and associated safety levels

Safety function	ACOPOSmotor SafeMOTION	EN ISO 13849-1	EN 61508 / EN 62061	Safe Encoder evaluation Necessary
Safe Direction (SDI)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safely Limited Increment (SLI)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safely Limited Acceleration (SLA)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Brake Control (SBC) [1]	R 1.10	PL d / Cat. 3	SIL 2	No
Safely Limited Position (SLP)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Maximum Position (SMP)	R 1.10	PL d / Cat. 3	SIL 2	Yes
Safe Homing	R 1.10	PL d / Cat. 3	SIL 2	Yes
Remanent Safe Position (RSP)	R 1.10	PL d / Cat. 3	SIL 2	Yes

Table 207: ACOPOSmotor SafeMOTION: Safety functions and associated safety levels

1) Safety function SBC does not apply to the motor holding brake integrated in the ACOPOSmotor SafeMOTION; it is not safety-related.

Safety function	ACOPOS P3 SafeMOTION	EN ISO 13849-1	EN 61508 / EN 62061	Safe Encoder evaluation Necessary
	EnDat 2.2			
	Starting with hardware upgrade			
Safe Torque Off (STO)	1.10.x.x	PL e / Cat. 4	SIL 3	No
Safe Torque Off One Channel (STO1)	1.10.x.x	PL d / Cat. 3	SIL 2	No
Safe Operation Stop (SOS)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safe Stop 1 (SS1)	1.10.x.x	Time-based monitoring: PL e / Cat. 4 Ramp-based monitoring: PL d / Cat. 3	Time-based monitoring: SIL 3 Ramp-based monitoring: SIL 2	Time-based monitoring: No Ramp-based monitoring: Yes
Safe Stop 2 (SS2)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safely Limited Speed (SLS)	1.10.x.x[2]	PL d / Cat. 3	SIL 2	Yes[1]
Safe Maximum Speed (SMS)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safe Direction (SDI)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safely Limited Increment (SLI)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safely Limited Acceleration (SLA)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safe Brake Control (SBC)	1.10.x.x	PL d / Cat. 3	SIL 2	No
Safely Limited Position (SLP)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safe Maximum Position (SMP)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safe Homing	1.10.x.x	PL d / Cat. 3	SIL 2	Yes
Safe Brake Test (SBT)	1.10.2.x	PL d / Cat. 3	SIL 2	Yes
Safely Limited Torque (SLT)	1.10.2.x	PL d / Cat. 3	SIL 2	No
Remanent Safe Position (RSP)	1.10.x.x	PL d / Cat. 3	SIL 2	Yes

Table 208: ACOPOS P3 SafeMOTION: Safety functions and associated safety levels

1) Safe encoder evaluation is not necessary in conjunction with SSO.
2) Supported in hardware upgrade 1.10.2.x and later in conjunction with SSO.

Guidelines for using the integrated safety functions

ACOPOSmulti SafeMOTION and ACOPOSmotor SafeMOTION

At least the "Activate" and "S_AxisID" inputs must be connected. Otherwise, the SafeMOTION module will not be operated by the SafeLOGIC controller. As a result, pulse disabling and the motor holding brake output will be permanently set to 0 V, which means that the controller cannot be switched on.

ACOPOS P3 SafeMOTION

For each axis used, at least the inputs "Activate", "S_AxisID", and "S_Control_Activate" must be connected to the function block SF_oS_MOTION_Basic_BR or SF_oS_MOTION_BR.

Danger!

All of the safety functions that are being used must be tested.
A function is considered to be "in use" if the corresponding input is connected or the safety function has been configured!

The following libraries and function blocks are available in SafeDESIGNER for creating a safe application.

Drive system	Library
ACOPOSmulti SafeMOTION EnDat 2.2 ACOPOSmulti SafeMOTION SinCos ACOPOSmotor SafeMOTION EnDat 2.2	7 "PLCopen_Motion_SF_2" on page 494
ACOPOS P3 SafeMOTION EnDat 2.2	8 "openSAFETY_BuR_Motion_SF" on page 733

6.4.1 FAIL SAFE state

6.4.1.1 Parameters

None

6.4.1.2 Behavior

If a hardware or firmware error occurs, then the SafeMOTION module switches to a non-acknowledgeable error state – the FAIL SAFE state. The logbook entry in Automation Studio provides more detailed information about the pending error. This logbook can also be evaluated in the standard application.
If the hardware is defective, the entire ACOPOSmulti SafeMOTION inverter module, entire ACOPOS P3 SafeMOTION servo drive or entire ACOPOSmotor SafeMOTION module must be replaced.

Information:

SafeMOTION modules cannot be replaced! The SafeMOTION module forms a unit with the ACOPOSmulti SafeMOTION inverter module, ACOPOS P3 SafeMOTION servo drive or inverter unit in the ACOPOSmotor SafeMOTION module. In the event of an error, the entire module must be replaced.

An error may also have been caused by a configuration mistake, however. If this is the case, then the safe configuration must be checked and reloaded to the SafeLOGIC controller. This must then be followed by a power off/on cycle to bring the module back to the OPERATIONAL state.

Danger!

In state "FAIL SAFE", safe pulse disabling is always active, i.e. the drive is not supplied with power; the motor therefore no longer exerts torque or force. The motor holding brake output is always switched to 0 V in this state!

Danger!

Constantly lit "SE" LEDs indicate a non-acknowledgeable FAIL SAFE state. The cause of this could be a defective module or faulty configuration.
Check the entries in the logbook! If you are able to rule out a faulty configuration, then the module is defective and must be replaced immediately.

It is your responsibility to ensure that all necessary repair measures or corrections to the configuration are initiated after an error occurs since subsequent errors can result in dangerous situations!

Danger!

ACOPOSmulti SafeMOTION inverter modules

If connected, the motor holding brake engages in the FAIL SAFE state. The motor holding brake will suffer mechanical wear if the motor is in motion just before the safe state is triggered. This must be taken into account when selecting and dimensioning the motor holding brake (emergency stop capability).

6.4.2 FUNCTIONAL FAIL SAFE state

6.4.2.1 Parameters

Parameter	Unit	Description	Default value	Starting in Safety Release
STO1 - Channel (previously *Channel selection for One Channel STO (STO1)*)	High-side/ Low-side	Selects the high-side or low-side IGBT in the STO1 function **Value** – **Description** High-side – The high-side IGBTs are actuated with the function STO1. Low-side – The low-side IGBTs are actuated with the function STO1.	High-side	R 1.3

Table 209: SafeMOTION parameter group: Basic functions - STO1

Parameter	Unit	Description	Default value	Used Starting in Safety Release
FFS - Mode (previously *Behavior of Functional Fail Safe*)	STO / STO1 and STO with time delay	In the FUNCTIONAL FAIL SAFE state, STO and SBC are activated immediately, or STO1 is activated and then STO after a delay. **Value** – **Description** STO – In the FUNCTIONAL FAIL SAFE state, STO and SBC are activated immediately. STO1 and STO with time delay – In the FUNCTIONAL FAIL SAFE state, STO1 and SBC are activated first, and then STO after a delay.	STO	R 1.3
FFS - STO Enable delay time (previously *Delay for STO in Functional Fail Safe [µs]*)	[µs]	Delay time between STO1 and STO (and SBC) in the FUNCTIONAL FAIL SAFE state	0	R 1.3
FFS - Delay time until brake engages (previously *Delay time until the brake engages [µs]*)	[µs]	**Delay time before the brake engages** The second enable channel is activated after this delay time if STO1 and time-delayed STO and SBC are configured for FUNCTIONAL FAIL SAFE.	0	R 1.3
FFS - Caused by encoder error *(1.10.1.x for ACOPOSmulti SafeMOTION and hardware upgrade 1.10.2.x or later for ACOPOS P3 SafeMOTION)*	Always / Only if safety functions requiring an encoder are enabled	Enable FUNCTIONAL FAIL SAFE on encoder error: Always: FFS occurs if at least one safety function that requires an encoder is used and an encoder error is present. Only if safety functions requiring an encoder are enabled: FFS occurs if at least one safety function that requires an encoder is active and an encoder error is present.	Always	R 1.10.1

Table 210: SafeMOTION parameter group: General settings - Behavior of Functional Fail Safe (FFS)

6.4.2.2 Behavior

If a monitored limit is exceeded or an encoder error occurs during operation – and as long as the safe encoder is required for the safety functions being used – then the SafeMOTION module switches to an acknowledgeable error state – the FUNCTIONAL FAIL SAFE state.

For information about any errors that occur, see the logbook entry in Automation Studio. This logbook can also be evaluated in the standard application.

Danger!

The motor holding brake is engaged in the FUNCTIONAL FAIL SAFE state. The motor holding brake will suffer mechanical wear if the motor is in motion just before the safe state is triggered. This must be taken into account when selecting and dimensioning the motor holding brake (emergency stop capability).

Danger!

The error response time specified in the manual affects the residual movement in the event of error! This must be taken into account when planning the safety equipment (e.g. distances, monitored limits, etc.)

"FFS - Mode" = "STO"

Pulse disabling is requested (low-side and high-side) immediately after the error is detected and the safe motor holding brake output is set to 0 V.

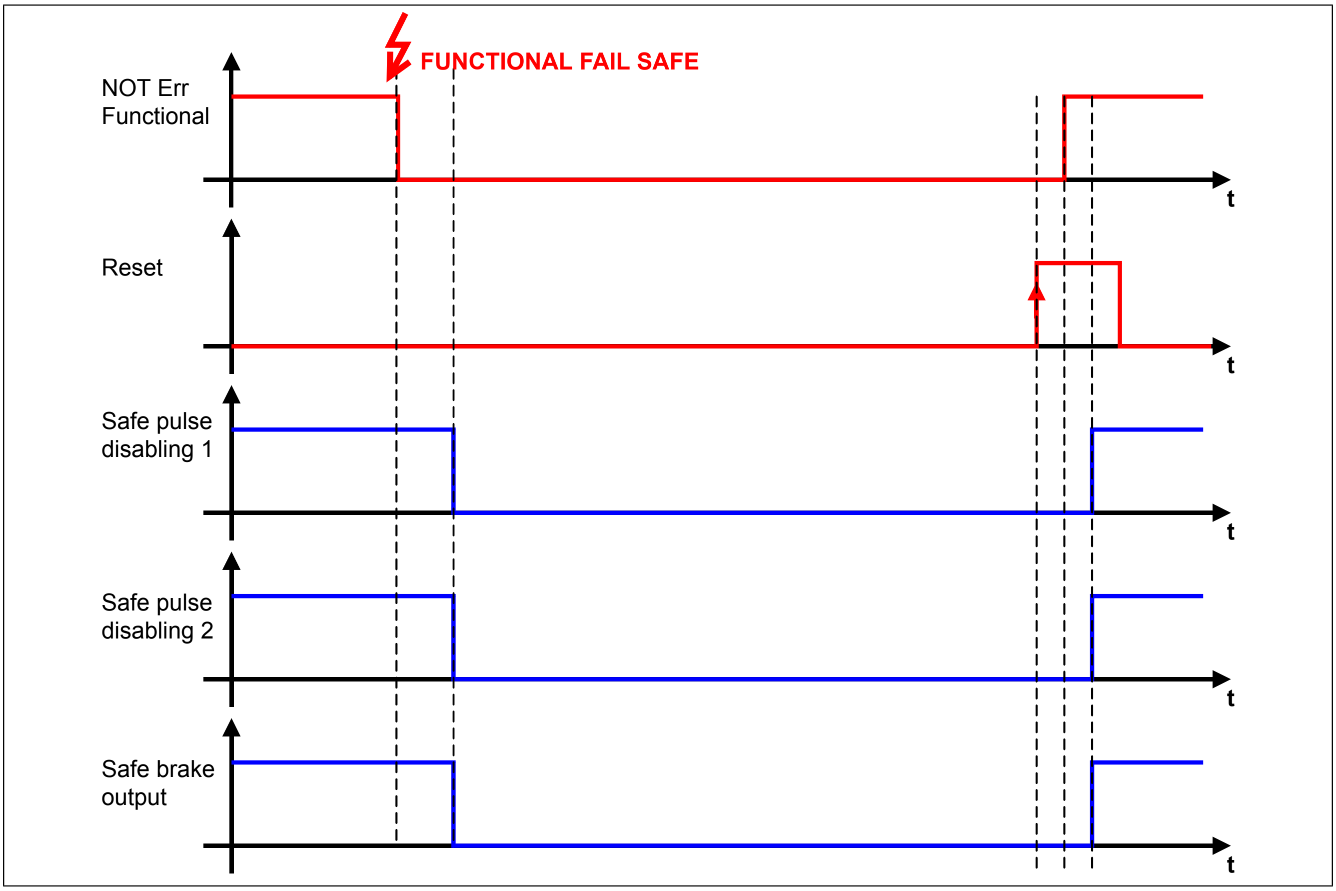


Figure 69: FUNCTIONAL FAIL SAFE - STO configuration

"FFS - Mode" = "STO1 and STO with time delay"

Either the low-side or high-side of the pulse disabling is switched to 0 V immediately after the error is detected. The safe motor holding brake output is set to 0 V after the configured "FFS - STO Enable delay time" (t_{FFS_STO}) has expired.
The second channel of the pulse disabling is also switched to 0 V after the configured "FFS - STO Enable delay time until brake engages" (t_{FFS_BRAKE}) has expired.

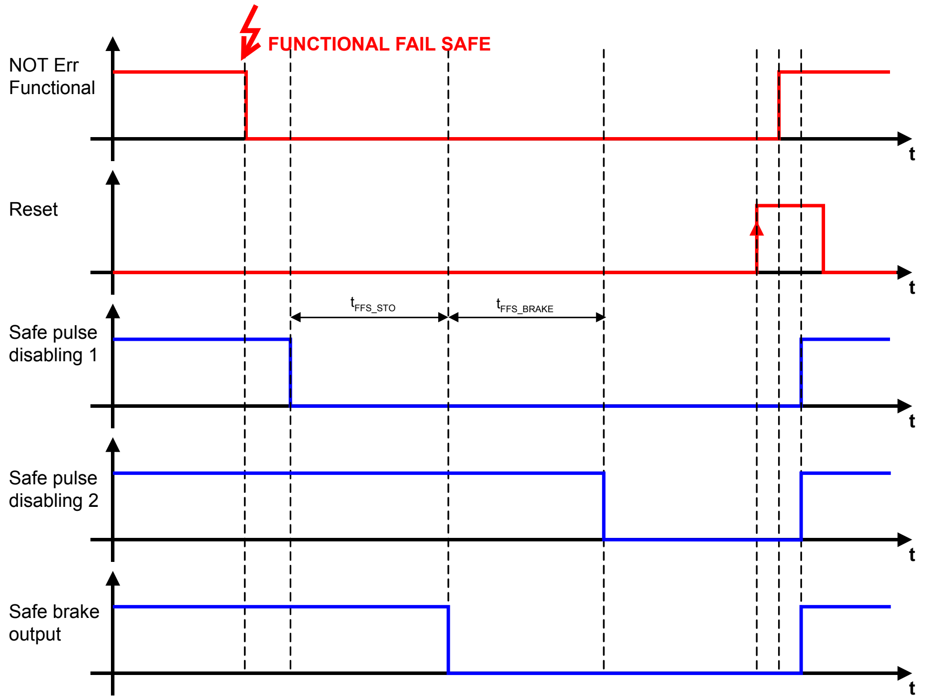


Figure 70: FUNCTIONAL FAIL SAFE - STO1 and STO configuration with time delay

This makes it possible for the drive to be decelerated via the short circuit braking integrated in the inverter unit for the amount of time in which just one pulse disabling channel is active.
In this case, the time t_{FFS_BRAKE} serves to incorporate this brake engage time. This means that the second pulse disabling channel will only be switched to 0 V after the motor holding brake has actually engaged.

Danger!

Short circuit braking in the inverter unit is not suitable for safety purposes and can therefore only be used to protect the machine. If the release of motor energy could result in dangerous situations (e.g. with hanging loads), then a mechanical safeguard must also be installed.

"FFS - Caused by encoder error"

This parameter makes it possible to disable the FUNCTIONAL FAIL SAFE reaction to an encoder error if no safety function is active that requires an encoder (safe position and/or safe speed).

6.4.3 Blackout mode

Information:

This functionality is only available in hardware upgrade 1.10.2.x or later!

Information:

The use of blackout mode in connection with DNA is not permitted. Static addresses must be used.

Information:

If safety functions are configured for blackout mode, they are used as configured in SafeDESIGNER. The danger warnings of individual safety functions also apply when used in blackout mode.

Danger!

Enabling blackout mode can lead to dangerous situations since pulse disabling is only enabled when the safety function is triggered or after delay time "BM - Delay time to FFS" has elapsed and not immediately when the network fails.

Information:

In the event of network failure of the servo drive, it is no longer possible to react to error behavior of the drive in the standard application. The standard default error response in the event of network failure is to abort the movement. An active standard reaction is only possible if safety communication fails.

Danger!

Parameter "Automatic reset on start" enables/disables the restart interlock during startup or when a network failure occurs on a reestablished network connection.

If parameter "Automatic reset on start" is set to "Enabled", then the module automatically changes to state OPERATIONAL state (i.e. pulse disabling and the motor holding brake are enabled)!

Configuring an automatic restart can result in critical safety conditions. Take additional measures to ensure proper safety-related functionality.

Information:

Resuming the network connection does not interrupt blackout mode functionality. Short interruptions and disturbances of the network connection therefore also result in the enabling of blackout mode.

6.4.3.1 Parameter

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Used starting with Safety Release</th></tr>
<tr><td>BM - Mode
(hardware upgrade 1.10.2.x and later)</td><td>Off /
Prev. enabled SF /
Prev. enabled and configured SF /
Configured SF</td><td>The blackout mode defines the behavior in case of network failure.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Off</td><td>In the event of a network failure, as before the axis enters state IDLE of the SafeMOTION module's state machine.</td></tr>
<tr><td>Prev. enabled SF</td><td>The safety functions requested at the time of the network failure remain active during the blackout mode.</td></tr>
<tr><td>Prev. enabled and configured SF</td><td>The safety functions requested at the time of the network failure remain active during the blackout mode; in addition, the safety functions configured in "BM - Configured safety functions" are requested.</td></tr>
<tr><td>Configured SF</td><td>At the time of the network failure, the safety functions configured in "BM - Configured safety functions" are requested.</td></tr>
</table></td><td>Off</td><td>R 1.10</td></tr>
<tr><td>BM - Delay time to FFS
(hardware upgrade 1.10.2.x and later)</td><td>[µs]</td><td>Delay time between start of blackout mode (detection of network failure) and the change to state FUNCTIONAL FAIL SAFE</td><td>0</td><td>R 1.10</td></tr>
<tr><td>BM - Configured safety functions
(hardware upgrade 1.10.2.x and later)</td><td>-</td><td>Configuration mask of the safety functions (additionally) requested in blackout mode.
Control bit = 0 ... Safety function requested
Control bit = 1 ... Safety function not requested</td><td>4294967295
(0xFFFF FFFF)</td><td>R 1.10</td></tr>
</table>

Table 211: SafeMOTION parameter group: General settings - Blackout Mode

6.4.3.2 Behavior

If no valid openSAFETY telegrams are received during operation, either the configured blackout mode with subsequent FUNCTIONAL FAIL SAFE state is enabled or the system changes immediately to state IDLE of the state machine of the SafeMOTION module; this depends on the configuration of parameter "BM - Mode". In the event of failure of the safety communication, this function makes it possible to start a retraction movement in the standard application and to monitor it using suitable safety functions, for example.

6.4.3.2.1 Configuration of parameter "BM - Mode"

BM - Mode = Off

This is the default setting. As before, the module changes to state IDLE of the state machine of the SafeMOTION module immediately after no more valid openSAFETY telegrams are received. In state IDLE, the motor holding brake output and pulse disabling are enabled.

BM - Mode = Prev. enabled SF

If no more valid openSAFETY telegrams are received, the safety functions requested at the time of the last valid telegrams remain active for the configured time "BM - Delay time to FFS". If a monitored limit is exceeded during this time, the module immediately changes to state FUNCTIONAL FAIL SAFE. Otherwise, the module changes to state FUNCTIONAL FAIL SAFE only after the time "BM - Delay time to FFS" has elapsed. The FUNCTIONAL FAIL SAFE error response is initiated as described above (see 6.4.2 "FUNCTIONAL FAIL SAFE state" on page 329).

BM - Mode = Prev. enabled and configured SF

If no more valid openSAFETY telegrams are received, the safety functions requested at the time of the last valid telegrams remain active for the configured time "BM - Delay time to FFS". In addition, the safety functions configured under "BM - Configured safety functions" are requested. If a monitored limit is exceeded during the active safety functions, the module immediately changes to state FUNCTIONAL FAIL SAFE. Otherwise, the module changes to state FUNCTIONAL FAIL SAFE only after the time "BM - Delay time to FFS" has elapsed. The FUNCTIONAL FAIL SAFE error response is initiated as described above (see 6.4.2 "FUNCTIONAL FAIL SAFE state" on page 329).

BM - Mode = Configured SF

If no more valid openSAFETY telegrams are received, the safety functions configured under "BM - Configured safety functions" remain activated for the configured "BM - Delay time to FFS" time. If a monitored limit is exceeded during this time, the module immediately changes to state FUNCTIONAL FAIL SAFE. Otherwise, the module changes to state FUNCTIONAL FAIL SAFE only after the time "BM - Delay time to FFS" has elapsed. The FUNCTIONAL FAIL SAFE error response is initiated as described above (see 6.4.2 "FUNCTIONAL FAIL SAFE state" on page 329).

6.4.3.2.2 Configuration of parameter BM - Configured safety functions

Parameter "BM - Configured safety functions" can be used to configure the safety functions that are requested (additionally) when blackout mode is active.

The following must be taken into account during configuration:

- Only functions that are also used in the safe application are permitted to be configured; the corresponding input on the function block must be connected and the function parameters must be set correctly. If this is not observed, the SafeMOTION module changes to state FAIL SAFE after startup.
- A function is configured by setting the corresponding bit in the control word to 0; unused bits must have the value 1. By default, all bits are set to 1, i.e. no function is configured!
- Safety functions that are not contained in the control word remain enabled/disabled as configured.
- The following control bits are not permitted (these are not evaluated):
  "Control reset", "Control activate", "Control SBT", "Control homing", "Control RefSwitch", "Control SwitchHomingMode" and all "Reserved" bits.

The assignment of safety functions to the respective control bit is shown in the tables:

- Tab. 305 "Control bits - Byte 0" on page 481
- Tab. 306 "Control bits - Byte 1" on page 481
- Tab. 307 "Control bits - Byte 2" on page 481
- Tab. 308 "Control bits - Byte 3" on page 482

6.4.4 Safe Position, Safe Speed

6.4.4.1 Parameters

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>EUS - Encoder type

(previously Encoder Type)
(SSO starting with hardware upgrade 1.10.2.x)</td><td>Rotary encoder / Linear encoder / Encoder used / Encoder not used / Safe Speed Observer - Rotatory / Safe Speed Observer - Linear</td><td>Determines the type of encoder used:
ACOPOSmulti SafeMOTION SinCos (Safety Release 1.7 and later)
Rotary encoder
Linear encoder
Encoder not used: No encoder being used
ACOPOSmulti SafeMOTION EnDat 2.2 (Safety Release 1.9 or later)
ACOPOSmotor SafeMOTION (Safety Release 1.10 or later)
Encoder used: Safe encoder evaluation enabled
Encoder not used: Safe encoder evaluation disabled
ACOPOS P3 SafeMOTION (Safety Release 1.10 and later)
Encoder used: Safe encoder evaluation enabled
Encoder not used: Safe encoder evaluation disabled
Safe Speed Observer - Rotatory: SSO enabled for rotary systems (hardware upgrade 1.10.2.x and later)
Safe speed observer - Linear: SSO enabled for linear systems (hardware upgrade 1.10.2.x and later)</td><td>Rotary encoder (SinCos)

Encoder used (EnDat 2.2)</td><td>R 1.7

R 1.9</td></tr>
<tr><td>EUS - Number of signal periods

(previously Number of signal periods)
(only with ACOPOSmulti SafeMOTION SinCos)</td><td>-</td><td>Number of signal periods per revolution (rotary encoder) or length of the physical reference system (linear encoder)</td><td>1</td><td>R 1.7</td></tr>
<tr><td>EUS - Count of physical reference system

(previously Count of physical reference system)</td><td>-</td><td>Rotary encoder unit scale: X revolutions
Linear encoder unit scale: X reference lengths (reference length = length of the physical reference system)

Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration). For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.</td><td>1</td><td>R 1.4</td></tr>
<tr><td>EUS - Units per count of physical reference system

(previously Units per count of physical reference system [units])</td><td>[units]</td><td>Rotary encoder unit scale: Units per x revolutions
Linear encoder unit scale: Units per x reference lengths

Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration). For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.</td><td>1000</td><td>R 1.4</td></tr>
<tr><td>EUS - Counting direction

(previously Counting direction)</td><td>Standard /
Inverse</td><td>Counting direction of the position or speed<table><tr><th>Value</th><th>Description</th></tr><tr><td>Default</td><td>Encoder counting direction is equal to the counting direction of the unit system.</td></tr><tr><td>Inverse</td><td>Encoder counting direction is negative to the counting direction of the unit system.</td></tr></table></td><td>Default</td><td>R 1.3</td></tr>
<tr><td>EUS - Length of physical reference system for linear encoder

(previously Length of physical reference system for linear encoder (nm))</td><td>[nm]</td><td>For linear measurement systems, the length of a physical reference system is defined here.
This value is not used for rotary encoders, where the reference system is a single revolution.</td><td>1000000000</td><td>R 1.4</td></tr>
<tr><td>EUS - Maximum speed to normalize speed range

(previously Maximum speed to normalize the speed range (units/s))</td><td>[units/s]</td><td>Maximum speed to which the displayed speed should be normalized</td><td>32767</td><td>R 1.3</td></tr>
<tr><td>EUS - Encoder acceleration limit

(previously Maximum acceleration (rad/s² or mm/s²))</td><td>[rad/s²] or [mm/s²]</td><td>Maximum permissible encoder acceleration</td><td>100000</td><td>R 1.4</td></tr>
</table>

Table 212: SafeMOTION parameter group: General settings - Encoder Unit System

Information:

The physical drive speed is not permitted to exceed the value set for parameter "EUS - Maximum speed to normalize speed range"; otherwise, the SafeMOTION module will switch to the error state!

Danger!

If the manufacturer of the measuring instrument specifies a limitation of the maximum acceleration, this must be monitored by the SafeMOTION module. The acceleration to be monitored can be configured using parameter "EUS - Encoder acceleration limit".

Danger!

Incorrectly configuring the unit system can result in dangerous situations.
When validating the application, the monitored speed limits must be intentionally violated and their physical values tested! The same must also be done for the monitored direction of rotation!

6.4.4.2 Behavior

These parameters (see 6.4.4.1 "General settings - Encoder Unit System" on page 335) can be used to configure the safe unit system.

The safe speed and safe position are transferred in the safety frame. The process data is only permitted to be used together with the corresponding status bit. If the respective status bit is FALSE, then the corresponding data is invalid.

Function blocks are available that can link the process data to a specific axis in order to use it in the safety application.

Safe Position

The safe position is transferred in the [units] defined by the configured units system. After successful homing, status bit "S_SafePositionValid" or "S_Status_Homing" is set.

Danger!

If the position signal is not validated, then an invalid position could be used in the safety application. This can result in hazardous situations!

Danger!

The safe encoder evaluation can only detect a transmission or positioning error if:

- **A path is traversed greater than the angular deviation of the safe position specified in the encoder manufacturer's product information (*applies to ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION or ACOPOSmotor SafeMOTION*).**
- **A distance is traversed that is greater than ±½ of the signal period of the SinCos measuring instrument *(applies to ACOPOSmulti SafeMOTION SinCos)*.**

The resulting maximum error in the safe position also depends on the length of the physical reference system (revolutions, length of the scale, etc.).

The error affects the minimum clearance required to prevent pinching/crushing (e.g. of fingers) and must be taken into account when dimensioning the safety function.

Danger!

For a frictionally engaged connection with fault exclusion, there is no additional mechanical offset that would need to be considered for the safe position.

If fault exclusion is fulfilled only by a mechanical stop with backlash, this maximum possible offset must be calculated into the safe position. This is done by adding the values for the measuring instrument and for the mechanical coupling.

Safe Speed

The safe speed is scaled to 2 bytes due to the limited bandwidth available in the safety frame. The scaled speed (v_{Scaled}) is calculated as follows:

$$v_{scaled} = \frac{v_{physical} \cdot 32767}{v_{EUS\_MAX\_NORM}} \left[\frac{scaled\ units}{s}\right]$$

$v_{Physical}$ (physical speed) corresponds to the actual physical value and is calculated in [units/s] using the configured units system.

With the default configuration of parameter "EUS - Maximum speed to normalize speed range" = $v_{EUS\_MAX\_NORM}$ = 32767, the scaled speed equals the physical speed!

The maximum speed is never permitted to exceed the configured value of "EUS - Maximum speed to normalize speed range"; otherwise, the module switches to the FUNCTIONAL FAIL SAFE state.

Information:

The speed limits of safety functions are configured in [units/s] of physical speed. The safety functions monitor the scaled speeds [scaled units/s] internally, which can cause scaling errors to occur.

Example

The following configuration results in the speed tolerance for standstill monitoring being scaled internally to 0 [scaled units/s].

Configuration:
"EUS - Maximum speed to normalize speed range" = $v_{EUS\_MAX\_NORM}$ = 3276700
"Standstill monitoring - Speed tolerance" = v_{SM_T} = 20

$$Scaled\ v_{SM\_T} = \frac{v_{SM\_T} \cdot INT16MAX}{v_{EUS\_MAX\_NORM}} = \frac{20 \cdot 32767}{3276700} = 0$$

If Safe Operating Stop is activated, a speed tolerance of 0 is monitored internally [scaled units/s]. This can wrongly result in a speed limit violation while at a standstill.

Information:

The configured unit system has a significant impact on the maximum physical speed that is achieved.

When changing the configured unit system, it is important to consider how this will affect parameter "EUS - Maximum speed to normalize speed range".

Danger!

If the module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state, then the drive loses all torque/power and coasts to a stop! In the event of an error, a synchronous axis will no longer be synchronous. Output "S_NotErrFUNC" or "S_Status_NotErrFunc" of the function block is reset!

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

Danger!

If the speed signal is not validated, then an invalid speed value could be used in the safety application. This can result in hazardous situations!

Danger!

The safe encoder evaluation can only detect a transmission or positioning error if:

- **A path is traversed greater than the angular deviation of the safe position specified in the encoder manufacturer's product information (*applies to ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION or ACOPOSmotor SafeMOTION*).**
- **A distance is traversed that is greater than ±½ of the signal period of the SinCos measuring instrument *(applies to ACOPOSmulti SafeMOTION SinCos)*.**

The resulting maximum error in the safe position also depends on the length of the physical reference system (revolutions, length of the scale, etc.).

The error influences the error response time and must be taken into account when dimensioning the safety function.

6.4.5 Safe Speed Observer, SSO

Information:

This functionality is only available for ACOPOS P3 SafeMOTION with hardware upgrade 1.10.2.x or later!

The function is approved starting with a defined hardware revision; for older hardware revisions, using the safety function leads directly to state FAIL SAFE. The necessary hardware revision is noted in the servo drive data sheet.

6.4.5.1 Parameter

Parameter	Unit	Description	Default value	Starting in Safety Release

EUS - Encoder type
 	
(previously *Encoder Type*)
(SSO starting with hardware upgrade 1.10.2.x)
	Rotary encoder / Linear encoder / Encoder used / Encoder not used / Safe Speed Observer - Rotatory / Safe Speed Observer - Linear	Determines the type of encoder used:
		• ACOPOSmulti SafeMOTION SinCos *(Safety Release 1.7 and later)*
		  ° Rotary encoder
		  ° Linear encoder
		  ° Encoder not used: No encoder being used
		• ACOPOSmulti SafeMOTION EnDat 2.2 *(Safety Release 1.9 or later)*
		ACOPOSmotor SafeMOTION *(Safety Release 1.10 or later)*
		  ° Encoder used: Safe encoder evaluation enabled
		  ° Encoder not used: Safe encoder evaluation disabled
		• ACOPOS P3 SafeMOTION *(Safety Release 1.10 and later)*
		  ° Encoder used: Safe encoder evaluation enabled
		  ° Encoder not used: Safe encoder evaluation disabled
		  ° Safe Speed Observer - Rotatory: SSO enabled for rotary systems (hardware upgrade 1.10.2.x and later)
		  ° Safe speed observer - Linear: SSO enabled for linear systems (hardware upgrade 1.10.2.x and later)
			Rotary encoder (SinCos)
			
			Encoder used (EnDat 2.2)
				R 1.7
				
				R 1.9

EUS - Number of signal periods (previously *Number of signal periods*) (only with ACOPOSmulti SafeMOTION SinCos)	-	Number of signal periods per revolution (rotary encoder) or length of the physical reference system (linear encoder)	1	R 1.7
EUS - Count of physical reference system (previously *Count of physical reference system*)	-	Rotary encoder unit scale: X revolutions Linear encoder unit scale: X reference lengths (reference length = length of the physical reference system) Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration). For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.	1	R 1.4
EUS - Units per count of physical reference system (previously *Units per count of physical reference system [units]*)	[units]	Rotary encoder unit scale: Units per x revolutions Linear encoder unit scale: Units per x reference lengths Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration). For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.	1000	R 1.4

Table 213: SafeMOTION parameter group: General settings - Encoder Unit System

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>EUS - Counting direction

(previously Counting direction)</td><td>Standard / Inverse</td><td>Counting direction of the position or speed<table><tr><th>Value</th><th>Description</th></tr><tr><td>Default</td><td>Encoder counting direction is equal to the counting direction of the unit system.</td></tr><tr><td>Inverse</td><td>Encoder counting direction is negative to the counting direction of the unit system.</td></tr></table></td><td>Default</td><td>R 1.3</td></tr>
<tr><td>EUS - Length of physical reference system for linear encoder

(previously Length of physical reference system for linear encoder (nm))</td><td>[nm]</td><td>For linear measurement systems, the length of a physical reference system is defined here.
This value is not used for rotary encoders, where the reference system is a single revolution.</td><td>1000000000</td><td>R 1.4</td></tr>
<tr><td>EUS - Maximum speed to normalize speed range

(previously Maximum speed to normalize the speed range (units/s))</td><td>[units/s]</td><td>Maximum speed to which the displayed speed should be normalized</td><td>32767</td><td>R 1.3</td></tr>
<tr><td>EUS - Encoder acceleration limit

(previously Maximum acceleration (rad/s² or mm/s²))</td><td>[rad/s²] or [mm/s²]</td><td>Maximum permissible encoder acceleration</td><td>100000</td><td>R 1.4</td></tr>
</table>

Table 213: SafeMOTION parameter group: General settings - Encoder Unit System

Information:

Parameter "EUS - Encoder acceleration limit" does not have to be configured when using the safe speed observer since acceleration is not monitored.

Parameter	Unit	Description	Default value	Starting in Safety Release
Motor - Number of pole pairs (hardware upgrade 1.10.2.x and later)	-	Number of pole pairs on the rotor circumference	1	1.10
Motor - Direction*) (hardware upgrade 1.10.2.x and later)	Standard / Inverse	Direction of rotation of the motor	Standard	1.10
Motor - Stator resistance (hardware upgrade 1.10.2.x and later)	mOhm	Ohmic stator resistance measured between two connections (phase - phase) of the motor	0	1.10
Motor - Stator inductance (hardware upgrade 1.10.2.x and later)	µH	Stator inductance measured between two connections (phase - phase) of the motor	0	1.10
Motor - Torque constant (hardware upgrade 1.10.2.x and later)	µNm / A	Torque constant of the motor	0	1.10
Motor - Rated speed (hardware upgrade 1.10.2.x and later)	units/s	Nominal speed of the motor	0	1.10
Motor - Stall current (hardware upgrade 1.10.2.x and later)	mA	Stall current of the motor	0	1.10
Motor - Rated current (hardware upgrade 1.10.2.x and later)	mA	Nominal current of the motor	0	1.10
Motor - Peak current (hardware upgrade 1.10.2.x and later)	mA	Peak current of the motor	0	1.10
Motor - Stall torque (hardware upgrade 1.10.2.x and later)	mNm	Stall torque of the motor that is output when the stall current is applied	0	1.10
Motor - Peak torque (hardware upgrade 1.10.2.x and later)	mNm	Peak torque of the motor that is briefly output when the peak current is applied	0	1.10
Motor - Moment of inertia (optional) (hardware upgrade 1.10.2.x and later)	µkgm²	Mass moment of inertia of the motor. Consists of the sum of the inertias of the rotor, encoder and holding brake.	0	1.10
Motor - External moment of inertia (optional) (hardware upgrade 1.10.2.x and later)	µkgm²	External mass moment of inertia, depends on the total external load	0	1.10

Table 214: SafeMOTION parameter group: General settings - Motor

*) The direction of rotation of the motor is not related to the counting direction of the speed ("EUS - Counting direction"), i.e. the direction of rotation of the motor can be changed explicitly in the non-safe application and must therefore also be taken into account in SafeDESIGNER.

Information:

Parameters "Motor - Peak torque", "Motor - Moment of inertia" and "Motor - External moment of inertia" are optional for the safe speed observer! The quality of the safe speed can be improved by configuring it.

Information:

An incorrect configuration ("Motor - Peak torque" too small, "Motor - Moment of inertia" or "Motor - External moment of inertia" too large) can lead to a deceleration of the observed speed and thus influence the "SSO - Speed tolerance safe speed".

Information:

If the direction of rotation of motor "Motor - Direction" is inverted, the commutation offset of the motor must be newly determined by single-phase.

Parameter	Unit	Description	Default value	Starting in Safety Release
SSO - Speed tolerance safe speed (hardware upgrade 1.10.2.x and later)	‰ of the nominal speed of the motor	Permissible deviation of the observed safe speed from the actual encoder speed	10	1.10
SSO - Inverter switching frequency (hardware upgrade 1.10.2.x and later)	Hz	Switching frequency of the servo drive	5000	1.10
SSO - Inverter adjustment amplification factor (hardware upgrade 1.10.2.x and later)	10^{-3}	Correction of the normalized gain factor of the inverter characteristic curve	0	1.10
SSO - Inverter adjustment exponent (hardware upgrade 1.10.2.x and later)	10^{-3} / A	Correction of the exponent of the inverter characteristic curve	0	1.10
SSO - External load - Enable (hardware upgrade 1.10.2.x and later)	Enabled/Disabled	Uses external energies (external load or suspended axes) with an enabled observer **Value** – **Description** Enabled – An external load / suspended load is used. Disabled – No external load / suspended load is used.	Enabled	1.10

Table 215: SafeMOTION parameter group: General settings - SSO

Information:

Parameters "SSO - Inverter adjustment amplification factor" and "SSO - Inverter adjustment exponent" must be determined using a parameter identification procedure (see 6.4.5.2.2.2 "Parameter identification for determining parameters "SSO - Inverter adjustment amplification factor" and "SSO - Inverter adjustment exponent"" on page 345)! Both parameters are used to correct the power inverter losses in the phase voltages.

Group: General settings - Encoder monitoring (previously *Encoder Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Encoder monitoring - Safe Encoder Mounting (Hardware upgrade 1.10.3.x and later)</td><td>From motor data record / Approved by user</td><td>Status of the proof of fatigue strength of the encoder mounting<table><tr><th>Value</th><th>Description</th></tr><tr><td>From motor data record</td><td>The status of the encoder mounting is determined using the motor data record.</td></tr><tr><td>Approved by user</td><td>The user confirms safe encoder mounting / no mounting information available in the motor data record.</td></tr></table></td><td>From motor data record</td><td>R1.10</td></tr>
<tr><td>Encoder monitoring - Position error monitoring - Enable

(previously Encoder Position monitoring)</td><td>Enabled/ Disabled</td><td>Enables/Disables monitoring of the position lag error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error monitoring - Enable

(previously Encoder Speed monitoring)</td><td>Enabled/ Disabled</td><td>Activates/Deactivates monitoring of the speed error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position setpoint alive testing (SPA) - Enable

(previously Set position alive testing)</td><td>Enabled/ Disabled</td><td>Activates/Deactivates the monitor that detects whether the position setpoint generated on the SafeMOTION module is frozen.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Disabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position error tolerance

(previously Encoder monitoring Position tolerance (units))</td><td>[units]</td><td>Position lag error tolerance for shaft breakage monitoring</td><td>0</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error tolerance

(previously Encoder monitoring Speed tolerance (units/s))</td><td>[units/s]</td><td>Speed error tolerance for encoder monitoring</td><td>0</td><td>R1.3</td></tr>
</table>

Table 216: SafeMOTION parameter group: General settings - Encoder monitoring

Information:

Velocity lag error monitoring "Encoder monitoring - Speed error monitoring - Enable" must be enabled for the safe speed observer, and tolerance "Encoder monitoring - Speed error tolerance" must be configured.

Information:

Speed lag error monitoring compares the speed setpoint with the measured actual speed in order to rule out an error in the encoder mounting. The following regulation applies to speed error tolerance "Encoder monitoring - Speed error tolerance":
"Encoder monitoring - Speed error tolerance" ≤ "EUS - Maximum speed to normalize speed range"
It makes sense that "Encoder monitoring - Speed error tolerance" should be less than "SSO - Speed tolerance safe speed".

Information:

Position lag error monitoring "Encoder monitoring - Position error monitoring - Enable" is not permitted to be enabled for the safe speed observer.

6.4.5.2 Behavior

For certain applications, it is possible to use the safe speed observer (SSO) instead of a safe encoder. The speed of an axis is determined by means of electrical signals and checked for plausibility with the measured values of non-safe encoder.

It is guaranteed that the speed determined and output by the safe speed observer is within the specified tolerance window of ±"SSO - Speed tolerance safe speed" around the actual speed and can therefore be used to monitor a speed limit using safety function SLS.

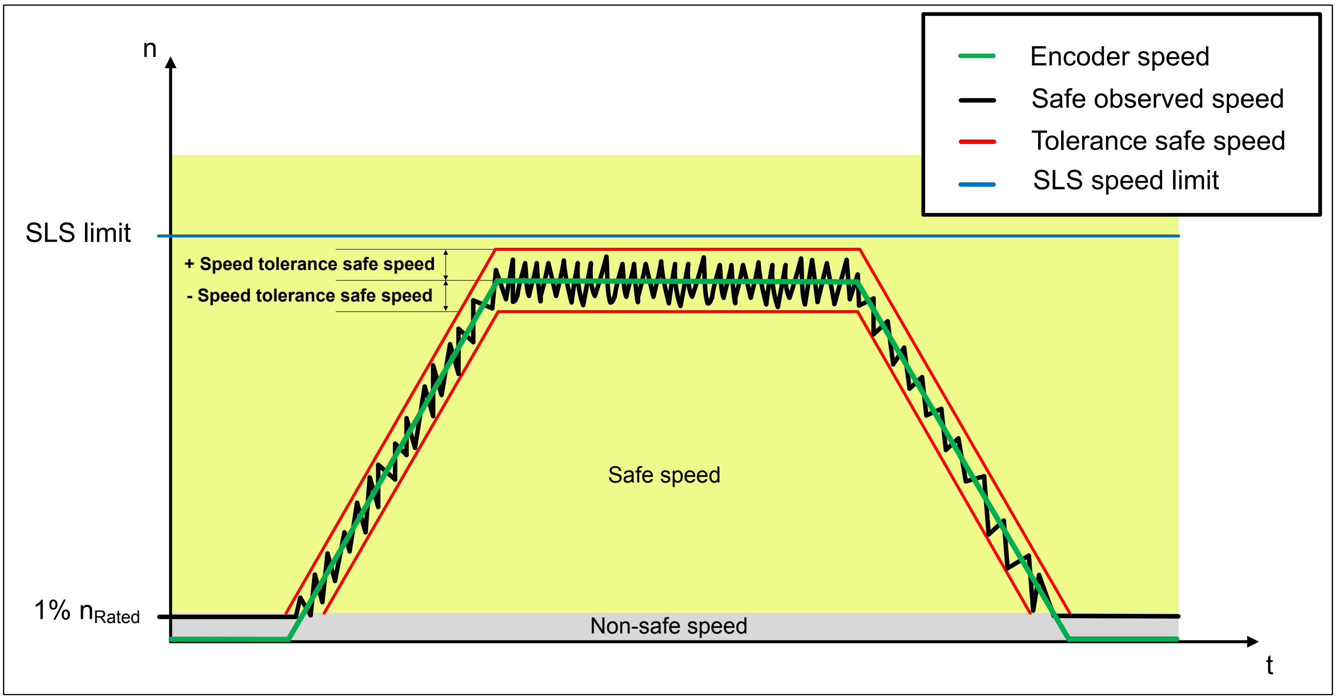


Figure 71: Comparison of the safely observed speed with the actual speed

Information:

The minimum safe speed output corresponds to 1% of the configured nominal speed of the motor!

The observable minimum speed is approx. 1% of the nominal speed. The tolerance, i.e. ±"SSO - Speed tolerance safe speed", depends on the motor used and the dynamics of the application and is typically ~2% of the nominal speed for rotary motors and ~20% for linear motors.

Information:

The minimum configurable tolerance "SSO - Speed tolerance safe speed" corresponds to 1% of the configured nominal speed of the motor! If the size selected for the parameter is too small, the availability of the axis is reduced.

Information:

The minimum configurable speed limit is not permitted to be less than the configured tolerance "SSO - Speed tolerance safe speed"!

The following rule applies:

1% n_{rated} ≤ Tolerance safe speed ≤ LIM_{SOS} ≤ LIM_{SLS4} ≤ LIM_{SLS3} ≤ LIM_{SLS2} ≤ LIM_{SLS1} ≤ EUS - Maximum speed to normalize speed range

Information:

Safety function Safe Maximum Speed "Speed functions - SMS/SLS - SMS - Enable" is not permitted to be used in combination with the safe speed observer. Safety function SMS is active immediately after changing to state OPERATIONAL. However, the SSO can only form a safe speed after the controller has been switched on for the first time and a safety-critical time window would be created.

Danger!

The permissible speed tolerance "SSO - Speed tolerance safe speed" must be determined by the user and configured in SafeDESIGNER.

Together with the safely configured nominal speed, the minimum, safely observable speed is thus defined. The speed determined in this way also corresponds to the error to be assumed.

When creating the safe application, this must be taken into account in such a way that the speed limit to be monitored is selected correspondingly lower!

Only the Safe Speed can be determined, but not the Safe Position, see 6.4.4 "Safe Position, Safe Speed" on page 335. Together with the achievable tolerance, this results in a limitation of the permissible safety functions when using the safe speed observer. Safe monitoring of the standstill is **not** possible!

The safe speed observer adds the SLS safety function to the permissible safety functions without a safe encoder.

The necessary requirements for using the safe speed observer are as follows:

- Use of a synchronous motor (linear or rotary) and knowledge of the motor characteristics
- Evaluation of a non-safe encoder
    - The encoder must be supported by the drive (onboard or option board).
    - Using a crosslink axis encoder is not permitted.
    - Network encoders are not permitted.
    - Use of a standard observer (encoderless control) is not permitted.
- Control modes such as current control mode and V/f control mode are not permitted.
- Load impacts can only be observed by the observer under certain circumstances; they usually have a direct effect on permissible speed tolerance "SSO - Speed tolerance safe speed".

6.4.5.2.1 External energies / External loads / Suspended axes / Vertical axes

External energies / Suspended loads must be explicitly configured when using SSO ("SSO - External load - Enable" → Enabled/Disabled). The following must be observed:

SSO - External load - Enabled

A safety function that requires a safe speed can only be requested when the controller is switched on. If SLS is requested and the controller is switched off, for example, the SafeMOTION module immediately changes to state FUNCTIONAL FAIL SAFE since the safe speed loses its validity.

> **Information:**
>
> **When using an external load, safety function Safe Stop 1 (SS1) is only permitted to be used with pure time monitoring. A ramp-monitored stopping procedure ("SS1 - Ramp monitoring - Enable") and early limit monitoring ("Early limit monitoring - Enable") are not permitted to be enabled.**

SSO - External load - Disabled

When the controller is switched off, the current safe speed is "frozen". This is permitted since the system cannot accelerate without external energy.

If the speed limit to be monitored is greater than the "frozen" speed, the safety function can be requested as usual.

If this is not the case, a request from the safety function leads to a violation of the monitored speed and the SafeMOTION module changes to state FUNCTIONAL FAIL SAFE.

> **Danger!**
>
> **The user is responsible for ensuring that the requirements for the safe observer (SSO) are met.**
>
> **Otherwise, the use of the safe speed observer is not permitted!**

Before using the Safe Speed Observer, the necessary safety functions and their limits must be defined. Subsequently, it must be decided whether the requirements of the safety functions can be fulfilled by means of SSO.

6.4.5.2.2 Commissioning

Before using the safe speed observer, the necessary parameters must first be determined. To do this, make the following settings in SafeDESIGNER:

- The use of an encoder must be disabled ("EUS - Encoder type" → Encoder not used)
- No safety function is permitted to be activated.

The following setting must be changed in the encoder configuration of the servo drive:

- Drive configuration → Encoder configuration → Encoder X4x → Interface type:
  The encoder type used must be configured here. Setting "EnDat SafeMOTION" must be deselected; otherwise, the standard (non-safe) firmware expects a safe encoder and therefore returns an error.

6.4.5.2.2.1 Reading parameters in Automation Studio

Information:

For a B&R motor with an EnDat interface type, the motor parameter set can be read out in the encoder memory using ParIDs. Before reading, make sure that interface type "EnDat" (see 6.4.5.2.2 "Commissioning " on page 344) is selected when configuring the plug-in module, otherwise the motor parameter set of the simulation is read out incorrectly.

The motor parameters and inverter switching frequency can be read out in Automation Studio using ParIDs. Some of them can also be found on the nameplate or in the motor data sheet.

Parameter	Necessary unit	Description	Configuration in SafeDESIGNER
Motor - Number of pole pairs	-	Number of pole pairs on the rotor circumference	**ParID 47**
Motor - Stator resistance	mOhm	Ohmic stator resistance measured between two connections (phase - phase) of the motor	**ParID 60** * 10^3
Motor - Stator inductance	µH	Stator inductance measured between two connections (phase - phase) of the motor	**ParID 61** * 10^6
Motor - Torque constant	µNm/A	Torque constant	**ParID 55** * 10^6
Motor - Rated speed	units/s	Nominal speed of the motor	*)
Motor - Peak torque	mNm	Peak torque of the motor that is briefly output when the peak current is applied	**ParID 54** * 10^3
Motor - Moment of inertia (optional)	µkgm²	Mass moment of inertia of the motor. Consists of the sum of the inertias of the rotor, encoder and holding brake.	**ParID 62** * 10^6

*) $= \frac{ParID50 \cdot \text{"EUS - Units per count of physical reference system"}}{60 \cdot \text{"EUS - Count of physical reference system"}}$

6.4.5.2.2.2 Parameter identification for determining parameters "SSO - Inverter adjustment amplification factor" and "SSO - Inverter adjustment exponent"

Due to the non-ideal switching behavior of the servo drive, the output voltage is falsified. Parameters "SSO - Inverter adjustment amplification factor" and "SSO - Inverter adjustment exponent" are needed to correct the resulting switching losses.

Both parameters must first be determined using an identification procedure and can only be read out afterwards.

- The controller must be tuned in Automation Studio as usual ("Controller - Autotuning")
- Parameter identification is started by writing the following ParIDs:

Parameter ID name	ParID	Value	Description
PIDENT_MOTOR_TYPE	975	2 (for SM)	Motor: Type
PIDENT_MODE	995	20	Main identification mode
PIDENT_SUB_MODE	1125	10	Sub-identification mode
CMD_PIDENT	997	ncStart (= 260)	Command

- After setting CMD_PIDENT to ncStart, the parameters for the inverter losses are determined and can be read out as follows:

Parameter ID Name	ParID	Range of values	Units	Description
PIDENT_FIT*)	998	0.0 .. 100.0	%	Quality of the identification procedure
PIDENT_INVCL_A1**)	992	0.0 .. 40.0	---	Inverter: Gain factor
PIDENT_INVCL_A2***)	993	0.0..FLT_MAX	1/A	Inverter: Exponent

*) The quality of identification is assessed as follows:
80% < PIDENT_FIT ≤ 100% Good
60% < PIDENT_FIT ≤ 80% Tolerable
0% < PIDENT_FIT ≤ 60% Unusable
0% Invalid
**) "SSO - Inverter adjustment amplification factor" ≙ PIDENT_INVCL_A1 * 10^3
***) "SSO - Inverter adjustment exponent" ≙ PIDENT_INVCL_A2 * 10^3

Danger!

Determined parameters PIDENT_INVCL_A1 and PIDENT_INVCL_A2 depend on switching frequency F_SWITCH of the inverter! If the switching frequency is changed, the parameters must be determined again!

6.4.5.2.2.3 Configuration in SafeDESIGNER

- The SSO must be enabled in the encoder unit system ("EUS - Encoder unit system") "EUS - Encoder type" → Safe speed observer - Rotatory/Linear
- The remaining encoder unit system must be configured (if not yet carried out).
- The determined motor and SSO parameters must be configured.
- Speed lag error monitoring must be enabled and tolerance "Encoder monitoring - Speed error tolerance" configured.
- The settings for SSO must be tested with the standard application.
- Speed tolerance "SSO - Speed tolerance safe speed" must be determined by measuring the deviation, see 6.4.5.2.2.4 "Determining the tolerance - Speed tolerance safe speed" on page 346.

Information:

The parameters determined in Automation Studio can have a different scaling than those that must be configured in SafeDESIGNER!

Example of a stator resistance read out in Automation Studio:[Ω]
Stator resistance to be configured in SafeDESIGNER: [mΩ]

Information:

The SafeMOTION Help Tool can be used to support the conversion of parameters into the correct system of units! The results must be verified!

6.4.5.2.2.4 Determining the tolerance - Speed tolerance safe speed

- To determine the optimal speed tolerance "SSO - Speed tolerance safe speed", it must first be configured to a very high value (>50% of the nominal speed) in SafeDESIGNER.
- If a safety function should be activated that monitors the speed, the speed limit to be monitored must be set higher than the configured tolerance
(1% n_{Rated} ≤ Tolerance safe speed ≤ LIM_{SOS} ≤ LIM_{SLS4} ≤ LIM_{SLS3} ≤ LIM_{SLS2} ≤ LIM_{SLS1} ≤ EUS - Maximum speed to normalize speed range).
- A movement must be made with the motor and the following parameter IDs recorded via Trace:

	ParID name	Value	Description
Safely observed speed	SAFEMC_SPEED_ACT	6	(INT) SafeMC: Actual speed (sUnits/s)
Non-safe actual speed (speed controller)	SCTRL_SPEED_ACT	251	(REAL) CTRL Speed controller: Actual speed (1/s)
Non-safe actual speed (position controller)	PCTRL_V_ACT	92	(REAL) CTRL Position controller: Actual speed (units/s)

- Either "SCTRL_SPEED_ACT" or "PCTRL_V_ACT" can be recorded as unsafe actual speed.
- The recorded speeds must be rescaled to the same system of units for comparison.
- The necessary tolerance can be determined by comparing the two speeds.
Note: When comparing using "Trace", a time offset of approximately 3.2 ms occurs and must be taken into account.
- In the stationary state, the deviation between "SAFEMC_SPEED_ACT" and "SCTRL_SPEED_ACT/PCTRL_V_ACT" is typically less than in the dynamic state. Therefore, the tolerance in the dynamic case should be determined.
- The determined tolerance must be configured in SafeDESIGNER.
- The speed limits used for the safety functions must be checked.

Danger!

The greater the speed tolerance "SSO - Speed tolerance safe speed" is configured, the greater the speed error that can occur!

Information:

The two recorded speeds "SAFEMC_SPEED_ACT" and "SCTRL_SPEED_ACT/PCTRL_V_ACT" are scaled differently.

Information:

When using "Trace" to compare the gray actual speed with the safely observed speed, a time offset of about 3.2 ms occurs.

6.4.5.3 Safety functions in combination with SSO

The following safety functions can be used in combination with the safe speed observer:

- STO
- SBC
- SS1
- SLS1 - SLS4
- STO1
- SLT

6.4.6 Safe Torque

Information:

This functionality is only available for ACOPOS P3 SafeMOTION!

The function is approved starting with a defined hardware revision; for older hardware revisions, using the safety function leads directly to state FAIL SAFE. The necessary hardware revision is noted in the servo drive data sheet.

6.4.6.1 Parameter

Parameter	Unit	Description	Default value	Starting in Safety Release
Motor - Number of pole pairs (hardware upgrade 1.10.2.x and later)	-	Number of pole pairs on the rotor circumference	1	1.10
Motor - Direction*) (hardware upgrade 1.10.2.x and later)	Standard / Inverse	Direction of rotation of the motor	Standard	1.10
Motor - Stator resistance (hardware upgrade 1.10.2.x and later)	mOhm	Ohmic stator resistance measured between two connections (phase - phase) of the motor	0	1.10
Motor - Stator inductance (hardware upgrade 1.10.2.x and later)	µH	Stator inductance measured between two connections (phase - phase) of the motor	0	1.10
Motor - Torque constant (hardware upgrade 1.10.2.x and later)	µNm / A	Torque constant of the motor	0	1.10
Motor - Rated speed (hardware upgrade 1.10.2.x and later)	units/s	Nominal speed of the motor	0	1.10
Motor - Stall current (hardware upgrade 1.10.2.x and later)	mA	Stall current of the motor	0	1.10
Motor - Rated current (hardware upgrade 1.10.2.x and later)	mA	Nominal current of the motor	0	1.10
Motor - Peak current (hardware upgrade 1.10.2.x and later)	mA	Peak current of the motor	0	1.10
Motor - Stall torque (hardware upgrade 1.10.2.x and later)	mNm	Stall torque of the motor that is output when the stall current is applied	0	1.10
Motor - Peak torque (hardware upgrade 1.10.2.x and later)	mNm	Peak torque of the motor that is briefly output when the peak current is applied	0	1.10
Motor - Moment of inertia (optional) (hardware upgrade 1.10.2.x and later)	µkgm²	Mass moment of inertia of the motor. Consists of the sum of the inertias of the rotor, encoder and holding brake.	0	1.10
Motor - External moment of inertia (optional) (hardware upgrade 1.10.2.x and later)	µkgm²	External mass moment of inertia, depends on the total external load	0	1.10

Table 217: SafeMOTION parameter group: General settings - Motor

*) The direction of rotation of the motor is not related to the counting direction of the speed ("EUS - Counting direction"), i.e. the direction of rotation of the motor can be changed explicitly in the non-safe application and must therefore also be taken into account in SafeDESIGNER.

6.4.6.2 Behavior

Safe electrical motor torque T_{ST} (Safe Torque) is determined by the amount of the stator-fixed current space vector $|i_S(i_\alpha, i_\beta)|$ and the configured motor torque characteristic curve.

The motor torque characteristic curve is approximated by piecewise continuous linear function $T_{MC}\left(\frac{i_S}{\sqrt{2}}\right)$ or $T^{-1}_{MC}(T)$ and indicates the relationship between motor torque and the amount of the stator-fixed safe current space vector.

$$T = T_{MC}\left(\frac{i_S}{\sqrt{2}}\right) = \min\left(K_T \cdot \frac{i_S}{\sqrt{2}}; T_0 + \frac{T_P - T_0}{I_P - I_0} \cdot \left(\frac{i_S}{\sqrt{2}} - I_0\right)\right)$$

or

$$i_S = T^{-1}_{MC}(T) = \sqrt{2} \cdot \max\left(\frac{T}{K_T}; I_0 + \frac{T - T_0}{\frac{T_P - T_0}{I_P - I_0}}\right)$$

K_T Torque constant of the motor
I_0 Stall current of the motor
I_P Peak current of the motor
T_0 Stall torque of the motor
T_P Peak torque of the motor

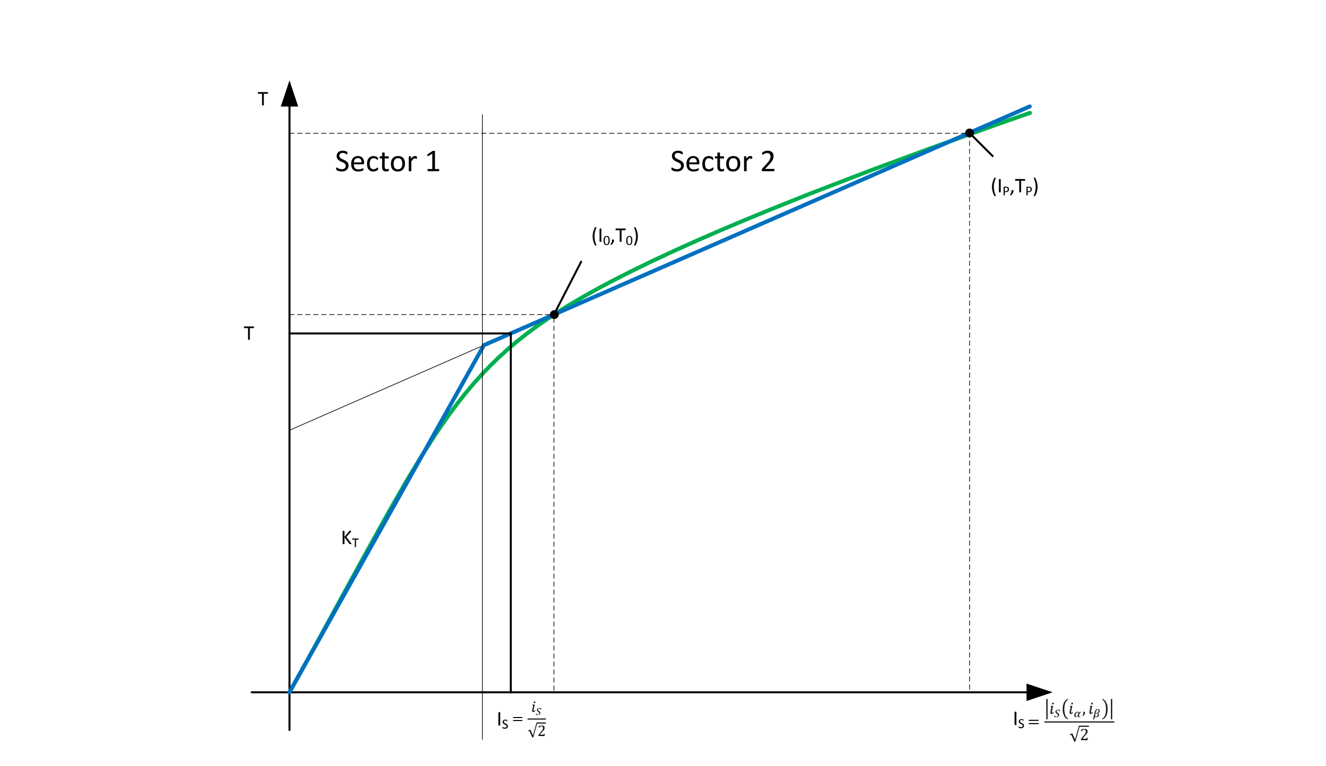


Figure 72: Configured motor torque characteristic curve

Information:

The safe electrical torque is based on the safe current measurement; therefore, the notes and information about the safe current measurement are also valid for the safe torque. See Safe current measurement.

Information:

When calculating the accuracy of the safe electrical torque, the accuracy of safety function SLT specified in the respective data sheet of the inverter module must be used.

Danger!

The actual torque of the motor can always be less than the safe electrical torque. This must be taken into account when using the safe electrical torque.

Danger!

The safe electrical torque specifies the maximum amount of electrical motor torque. This must be taken into account when using the safe electrical torque.

Danger!

Due to an error in the motor (commutation error, demagnetization, etc.), the amount of actual electric motor torque can be less than the determined safe torque.

This must be taken into account when using the safe electrical torque.

Danger!

Overheating of the motor can change torque constant K_T and therefore negatively influence the safe torque. Ensure that the motor has been sized so as to prevent overheating.

Danger!

The safe electrical torque can only be used for synchronous motors with undefined poles (L_d=L_q)!

Danger!

If the accuracy of the safe current is not taken into account, a current value or torque that is too low can be monitored under certain circumstances. In this case, it cannot be guaranteed that the target torque will be reached or that the torque limit will be correctly monitored; the result of the safety function is therefore invalid!

Danger!

The accuracy of the safe current only applies up to the continuous current of the performance class used. It is not permitted to use a safety function that should monitor or detect a current above the continuous current of the performance class used.

Danger!

The configuration parameters of the motor torque characteristic must be determined and configured according to the motor manufacturer's specifications, taking into account the unfavorable case to be assumed (rotor position-dependent fluctuations, manufacturing tolerances, linearization errors, etc.)!

6.4.6.3 Accuracy of Safe Torque

The following accuracies must be taken into account when configuring Safe Torque.

Accuracy of the safe current

For valid general information about current measurement and its accuracy, see Accuracy of the safe current. The following additional instructions apply to safe electrical motor torque.

In order to calculate the motor torque, the accuracy of the safe current must be taken into account. Only this guarantees a valid safe electrical motor torque even with the maximum permissible measuring error of the current transformers.

6.4.6.4 Calculating the safe electrical motor torque with a maximum measurement error (worst case)

Safe electrical motor torque T_{ST} must be converted to corresponding current i_{ST} using piecewise continuous linear function $T_{MC}^{-1}(T)$ in order to apply accuracy of the safe current for SLT $i_{\varepsilon SLT}$. i_{ST_WC} must then be calculated back to a torque.

i_{ST} is calculated according to Safe Torque / Behavior as follows:

$$i_{ST} = T_{MC}^{-1}(T_{ST})$$

Accuracy of the safe current SLT $i_{\varepsilon SLT}$ of the power classes of the servo drive must then be added.

$$i_{ST\_WC} = i_{ST} + i_{\varepsilon SLT}$$

Transformed back into a torque, safe electrical motor torque at maximum measuring error (worst case) T_{ST_WC} results.

$$T_{ST\_WC} = T_{MC}(i_{ST\_WC})$$

6.4.7 Safe Torque Off (STO)

6.4.7.1 Parameters

None

6.4.7.2 Behavior

STO is the fundamental safety function of the SafeMOTION module since it represents the "idle current principle". A request from the STO safety function activates safe pulse disabling and switches off the torque and power to the drive. Activation of safe pulse disabling is performed actively by the SafeMOTION module.

Danger!

A STO request causes synchronized axes to no longer be synchronous.

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

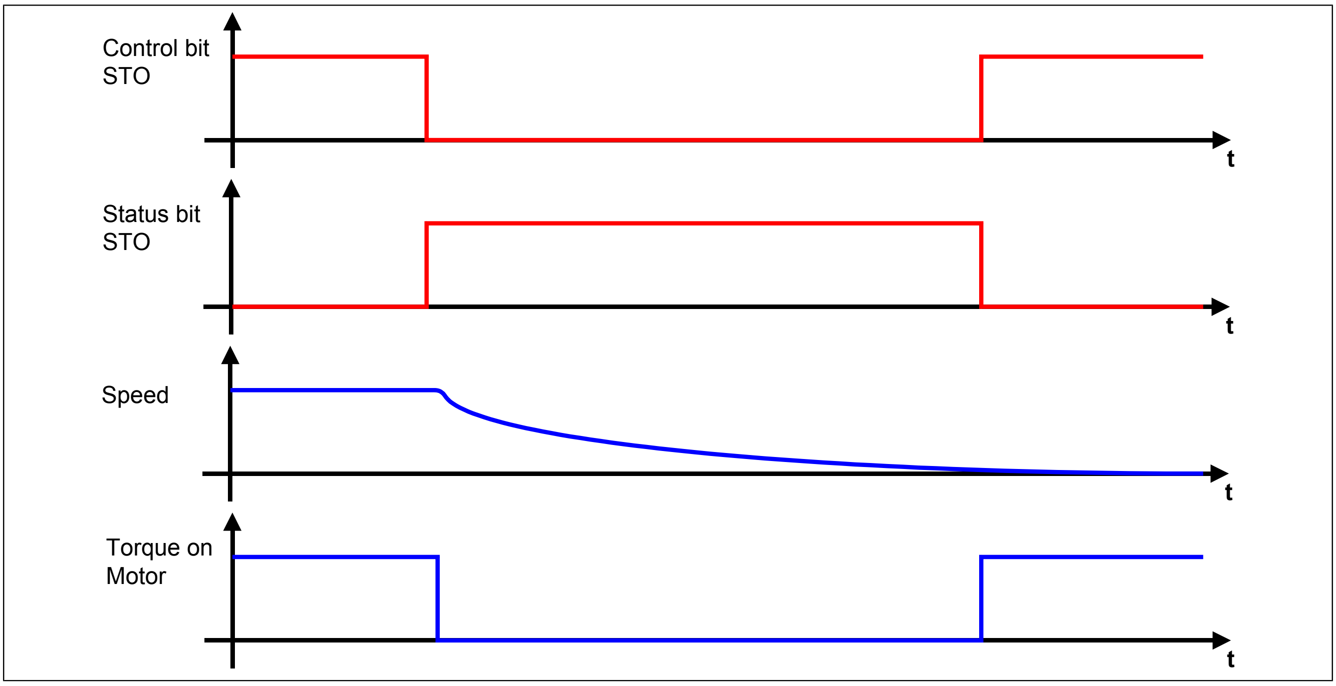


Figure 73: Safe Torque Off (STO)

Information:

The functional safe state of the STO safety function has been achieved when the pulse disabling outputs are switched to 0 V. The respective bit is set when the functional safe state has been achieved.

Danger!

If the drive is in motion at the time STO is requested, it will coast to a stop. The resulting residual movement and time depends on the properties of the machine and must always be considered when dimensioning the safety equipment.
The maximum possible (worst case) movement must be assumed.

The maximum possible speed is determined by the current operating mode. If there is no active safety function, the maximum speed that is physically possible for the motor must be assumed.

Danger!

If the SMS or SLS safety function is active, the assumed maximum speed can be reduced to the currently active configured speed limit plus the maximum possible acceleration during the error response time.

Information:

The resulting residual movement and time determines the clearances that must be observed for the safety features and therefore the overall size of the machine.

Information:

The STO safety function does not require safe encoder evaluation.

Danger!

If the STO safety function is used in the safety application, then it must be tested when commissioning the machine by selecting and deselecting it!

6.4.8 Safe Torque Off, single-channel (STO1)

6.4.8.1 Parameters

Group: Basic functions - STO1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th colspan="2">Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td rowspan="4">STO1 - Channel

(previously Channel selection for One Channel STO (STO1))</td><td rowspan="4">High-side/
Low-side</td><td colspan="2">Selects the high-side or low-side IGBT in the STO1 function</td><td rowspan="4">High-side</td><td rowspan="4">R 1.3</td></tr>
<tr><td>Value</td><td>Description</td></tr>
<tr><td>High-side</td><td>The high-side IGBTs are actuated with the function STO1.</td></tr>
<tr><td>Low-side</td><td>The low-side IGBTs are actuated with the function STO1.</td></tr>
</table>

Table 218: SafeMOTION parameter group: Basic functions - STO1

6.4.8.2 Behavior

The STO1 safety function works in the same way as STO. The only difference is that either only the high-side or only the low-side IGBTs are switched off depending on the configuration. The two configuration options (High-side/Lowside) are equivalent with regard to safety technology.

Information:

The functional safe state of the STO1 safety function has been achieved when the configured pulse disabling output is switched to 0 V.
The respective bit is set when the functional safe state has been achieved.

Information:

The two-channel aspect is lost because either only the low-side or only the high-side of the pulse disabling is activated with the STO1 safety function.
This results in a lower SIL and performance level!

Information:

The STO1 safety function does not require safe encoder evaluation.

Danger!

If the safety function STO1 is used in the safety application, then it must be tested when commissioning the machine by selecting and deselecting it!

If safe pulse disabling is only cut off on one side, then the short circuit braking integrated in the inverter unit can be used for deceleration.

Danger!

Short circuit braking in the inverter unit is not suitable for safety purposes and can therefore only be used to protect the machine. If the release of motor energy could result in dangerous situations (e.g. with hanging loads), then a mechanical safeguard must also be installed.

6.4.9 Safe Brake Control (SBC)

6.4.9.1 Parameters

Group: Basic functions - SBC (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBC - Enable delay time (previously *Delay time to start SBC (us)*)	[µs]	Delay time between the SBC request and activation of the safety function	0	R 1.3

Table 219: SafeMOTION parameter group: Basic functions - SBC

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

6.4.9.2 Behavior

The SBC safety function is a safe (time-delayed) output that can be used to safely control a motor holding brake.

Information:

To achieve a defined SIL level, the controlled holding brake must also have at least the same SIL level and errors in the wiring must be ruled out.

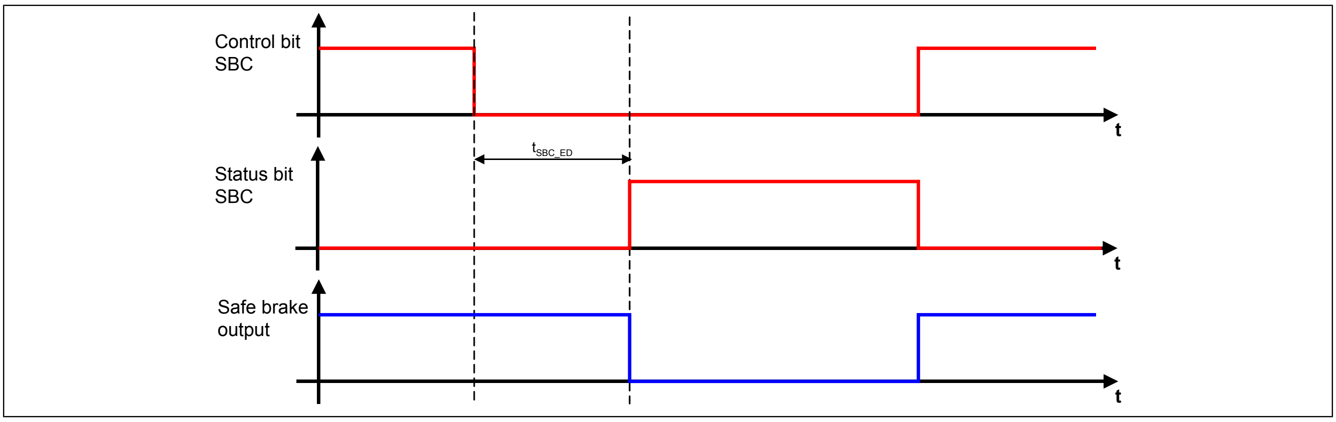


Figure 74: Safe Brake Control (SBC)

Only the actuation of the motor holding brake output by the SafeMOTION module is rated SIL 2.

The SafeMOTION module does not provide safe monitoring of the braking procedure.

Information:

The functional safe state of the SBC safety function has been achieved when the safe motor holding brake output has been switched to 0 V.
The respective bit is set when the functional safe state has been achieved.

The purpose of the delay time t_{SBC_ED} is to compensate for the different runtimes of the standard and safety applications.

Information:

The SBC safety function does not require safe encoder evaluation.

Danger!

If the SBC safety function is used in the safety application, then it must be tested when commissioning the machine by selecting and deselecting it!

Information:

Functional errors will occur (e.g. 6029: Holding brake: Control signal on and output status off), if the holding is released by the standard application but the motor holding brake output is switched to 0 V by the SafeMOTION module.

6.4.10 Safe Operating Stop (SOS)

6.4.10.1 Parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 220: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

6.4.10.2 Behavior

An enabled SOS safety function monitors the drive to ensure that it stops safely. The SafeMOTION module does not control pulse disabling.
The drive can remain active and must be kept at standstill by the standard application.

Information:

The SOS safety function requires safe evaluation of the speed and position.
If the function is programmed in the safety application and if an error is detected in the safe encoder evaluation, then the SafeMOTION module immediately switches to the FUNCTIONAL FAIL SAFE state after the function block is activated!

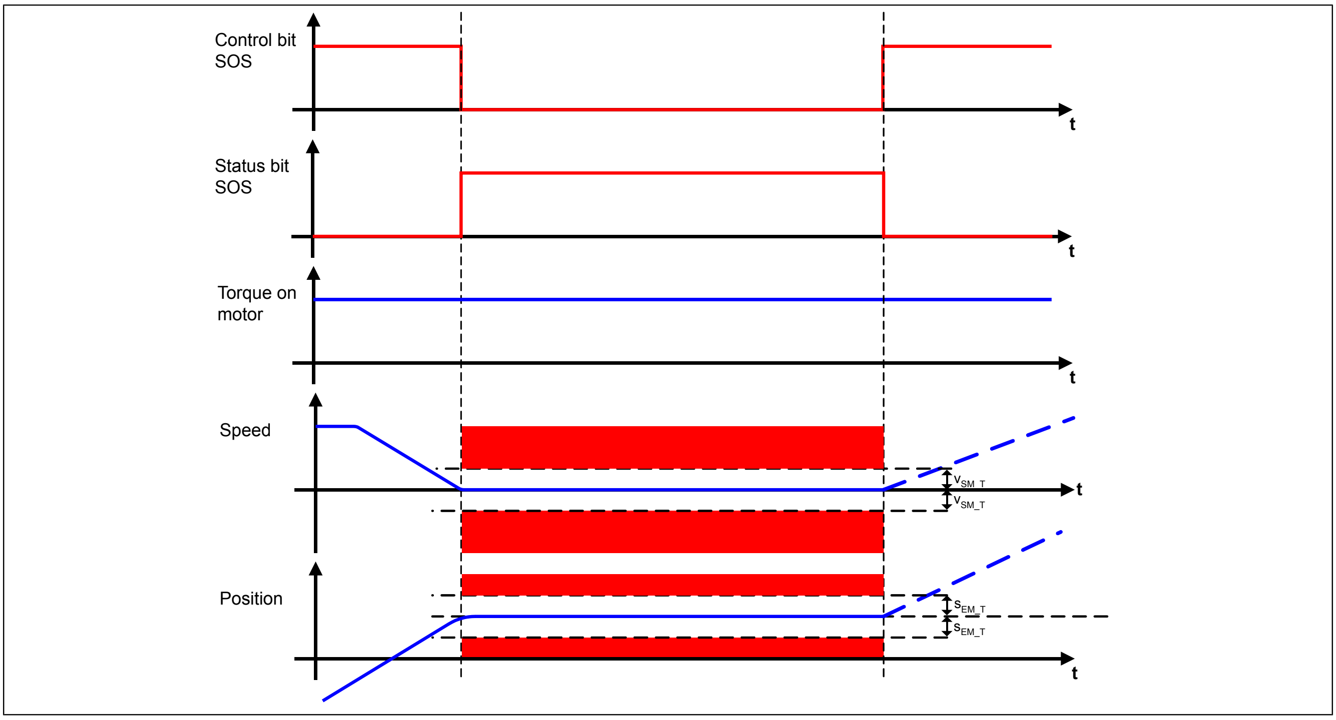


Figure 75: Safe Operating Stop (SOS)

To prevent the axis from drifting, both the speed and position are monitored with standstill tolerance limits. The position window is generated when the safety function is requested. If the request is withdrawn, then monitoring of the standstill tolerance window will also be terminated. The next time a request is made, the standstill tolerance position window is regenerated based on the current position.

Information:

The functional safe state of the SOS safety function has been achieved when the drive is stopped and the standstill is being safety-monitored.
The respective bit is set when the functional safe state has been achieved.

The standstill tolerances can be configured for each axis in SafeDESIGNER.

Danger!

In the event of an error, forward movement can occur during the error response time when monitoring the standstill tolerance window. During this time, the drive can accelerate to its maximum before coasting to a stop.
The speed and position limits being monitored must be set in a manner so that the calculated forward movement does not cause any danger.
The dangerous movement must be determined by a risk analysis.

If the stop monitoring limits are violated, safe pulse disabling is activated and the drive switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state. An error will cause a synchronous axis to no longer be synchronous.

Danger!

If a standstill limit (position or speed) is violated, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state. The drive loses all torque/power and coasts to a stop! In the event of an error, a synchronous axis will no longer be synchronous. The "S_NotErrFUNC" output on the function block is reset.

Danger!

If the SOS safety function is used in the safety application, then it must be tested when commissioning the machine by selecting and deselecting it!
The configured limits must be violated with the function enabled and the error response must be tested accordingly!

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

6.4.11 Safe Stop 1 (SS1)

6.4.11.1 Parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 221: SafeMOTION parameter group: General settings - Ramp monitoring

> # Danger!
>
> **The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!**

Group: Basic functions - SS1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS1 - Ramp monitoring - Enable

(previously Rampmonitoring for SS1)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SS1 function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When transitioning to the safe state of the SS1 function, a deceleration ramp is monitored in addition to the configurable time.</td></tr>
<tr><td>Disabled</td><td>When transitioning to the safe state of the SS1 function, only a configurable time is monitored.</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS1</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 222: SafeMOTION parameter group: Basic functions - SS1

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr>
<tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr>
</table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 223: SafeMOTION parameter group: General settings - Early limit monitoring

> # Danger!
>
> **The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.**
>
> **The dangerous movement must be determined by a risk analysis.**

6.4.11.2 Behavior

When requesting the SS1 safety function, the deceleration process of the axis is monitored until standstill after the ramp delay time passes. After decelerating, safe pulse disabling is activated and switches off the torque/power to the drive.

Danger!

Synchronous axes will no longer be synchronous when SS1 is in a safe state.

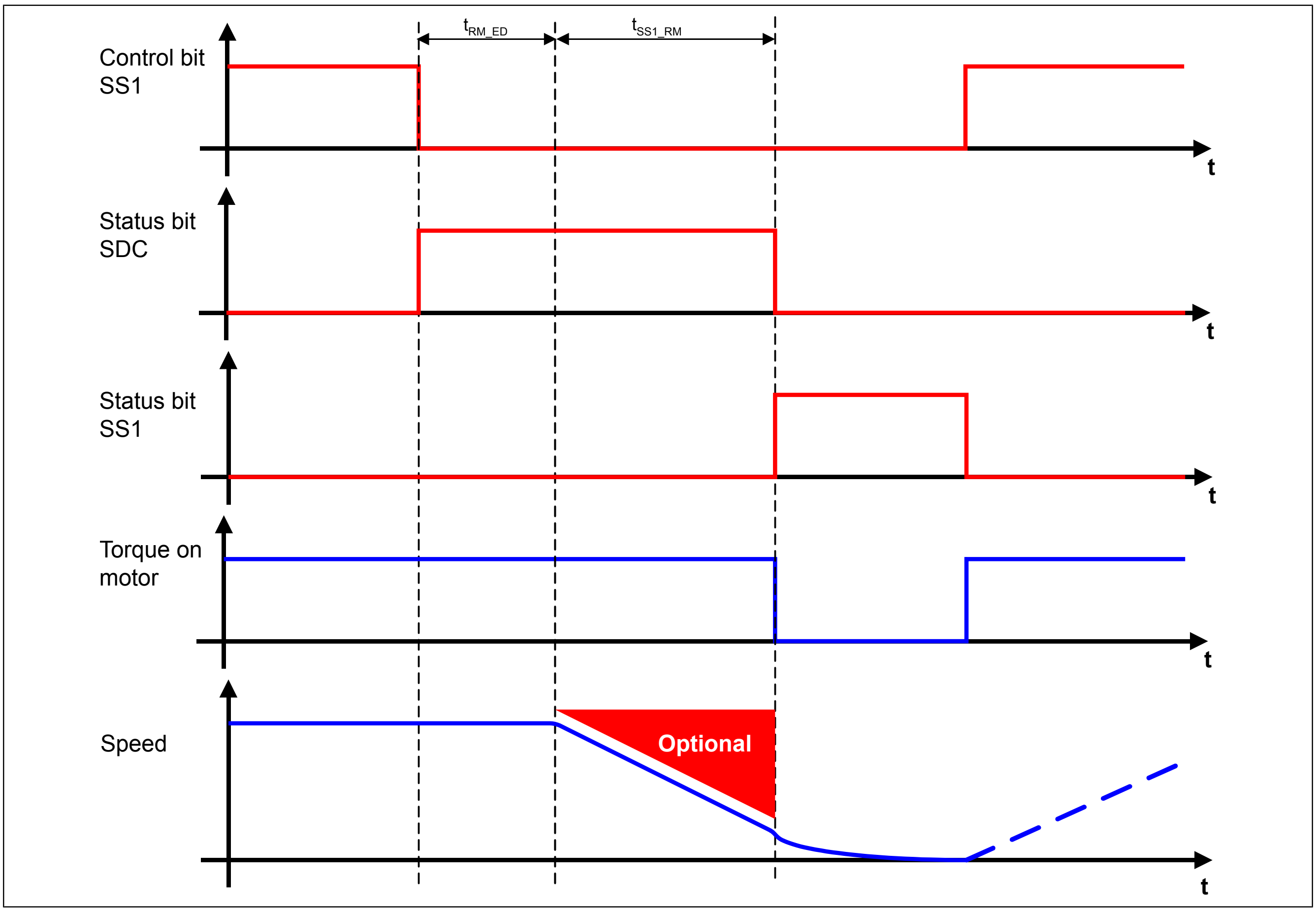


Figure 76: Safe Stop 1 (SS1)

The deceleration itself is controlled by the non-safety-related standard application.

The purpose of the ramp delay time parameter "Ramp monitoring - Enable delay time" (t_{RM_ED}) is to compensate for the different runtimes of standard and safety applications.

Information:

The functional safe state of the SS1 safety function has been achieved when the pulse disabling outputs are switched to 0 V. The respective bit is set when the functional safe state has been achieved.

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

Depending on the requirements for the safety function and its parameter settings, it is possible to monitor either only the deceleration time t_{SS1_RM} or the deceleration ramp as well.
If the monitoring limits are violated during deceleration, then an acknowledgeable error state is entered.

The "SS1 - Ramp monitoring - Time" (t_{SS1_RM}) parameter configures the ramp monitoring behavior.

6.4.11.3 SS1 - Stopping procedure with ramp-based monitoring

"SS1 - Ramp monitoring - Enable" = Enabled

With this setting, the configurable deceleration ramp is monitored in addition to time-based monitoring. In the event of an error, this provides the advantage that a lower maximum speed can be assumed when entering the safe state. During deceleration ramp monitoring, the standard application must ensure that the stopping procedure for a hazardous situation is handled accordingly.

The slope of the monitoring ramp can be set using the "Ramp monitoring - Speed deceleration limit" (a_{RM_L}) parameter.

A timer is started when the safety function is requested. After the "Ramp monitoring - Enable delay time" (t_{RM_ED}) has expired, monitoring of the deceleration ramp begins. The monitored ramp always begins at the currently monitored limit and is calculated using the configured slope. If the monitoring ramp reaches the configurable standstill speed limit "Standstill monitoring - Speed tolerance" (v_{SM_T}) or if the monitoring time "SS1 - Ramp monitoring - Time" (t_{SS1_RM}) has expired, then safe pulse disabling is activated and torque is switched off on the drive.

Setting "Early limit monitoring" to "Enable" makes it possible to configure an early enabling of the safe state. If the setting above has been made, then the safe state of the safety function will be started when the current speed falls below the standstill speed limit for at least the amount of time defined by "Early limit monitoring - Time" (t_{ELM}) during deceleration ramp monitoring.

If the active limit is violated during monitoring of the deceleration procedure, then the drive will immediately switch to the acknowledgeable Functional Fail Safe error state.

Information:

If ramp monitoring is configured for the safety function SS1, then the speed must be safely evaluated.
If the function is programmed in the safety application and if an error is detected in the safe encoder evaluation, then the SafeMOTION module immediately switches to the FUNCTIONAL FAIL SAFE state after the function block is activated!

Danger!

If safe pulse disabling is activated (coast to stop) and the safety function is in its functional safe state, the maximum speed at the end of the deceleration ramp must be used to calculate the residual distance.
To determine the maximum possible speed, it must be assumed that in the event of error, the drive will accelerate to its maximum during the error response time starting from the standstill speed limit.
The spin-out movement or residual distance is not permitted to result in a hazard!

Danger!

If the monitored ramp is exceeded, the residual distance must be calculated based on the error response time, starting with the currently monitored speed limit.
The spin-out movement or residual distance is not permitted to result in a hazard!

Danger!

If the SS1 safety function with ramp-based monitoring is used in the safety application, then it must be tested when commissioning the machine by selecting and deselecting it!
The test should include at least one violation of the monitored ramp, and the error response must be tested accordingly!

6.4.11.4 SS1 - Stopping procedure with time-based monitoring

"SS1 - Ramp monitoring - Enable" = Disabled

This configuration provides true time-based monitoring of the deceleration.
A timer is started when the safety function is requested. Within this time frame, the drive must implement a stopping procedure via the standard application that is appropriate for the respective dangerous situation.
After the delay time of the request "Ramp monitoring - Enable delay time" (t_{RM_ED}) plus the monitoring time "SS1 - Ramp monitoring - Enable" have expired, safe pulse disabling is activated and the drive loses all torque.

Information:

With this configuration of the Safe Stop 1 safety function, only the time frame is monitored.
No speed limit or position window is monitored.
The function can therefore also be used in this configuration without safe encoder evaluation!

Danger!

If safe pulse disabling is activated (coast to stop), the maximum speed after the time frame has expired must be used to calculate the residual distance!
The drive can move at its maximum physical speed during this time window (plus the response time of the safe pulse disabling). If SMS is active, then the speed limit plus the error tolerance can be assumed as the maximum speed.
The spin-out movement or residual distance is not permitted to result in a hazard!

Danger!

If the SS1 safety function with true time-monitoring is used in the safety application, then it must be tested when commissioning the machine by selecting and deselecting it!
The drive should be accelerated to its maximum during the monitored time frame and the error response tested accordingly!

6.4.12 Safe Stop 2 (SS2)

6.4.12.1 Parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 224: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SS2 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS2 - Ramp monitoring - Enable

(previously Rampmonitoring for SS2)</td><td>Enabled/
Disabled</td><td>Activates ramp monitoring (in addition to time-based monitoring) when the SS2 function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When changing to the safe state of the SS2 function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr><tr><td>Disabled</td><td>When changing to the safe state of the SS2 function, only a configurable time is monitored</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>Ramp Monitoring Time for SS2 (us)</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS2</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 225: SafeMOTION parameter group: Speed functions - SS2

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr><tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr></table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 226: SafeMOTION parameter group: General settings - Early limit monitoring

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 227: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

6.4.12.2 Behavior

With SS2, the deceleration process is monitored until standstill after the ramp delay time passes. The drive must then be kept at standstill by the standard application. As with SOS, this standstill is monitored by the SafeMOTION module according to the configured standstill tolerance window "Standstill monitoring - Speed tolerance" (v_{SM_T}) and "Standstill monitoring - Position tolerance" (s_{SM_T}).

The delay itself must be generated by the non-safety-related, standard application by halting the drive in response to the dangerous situation.

Information:

The Safe Stop 2 safety function requires safe evaluation of the speed and position.
If the function is programmed in the safety application and if an error is detected in the safe encoder evaluation, then the SafeMOTION module immediately switches to the FUNCTIONAL FAIL SAFE state after the function block is activated!

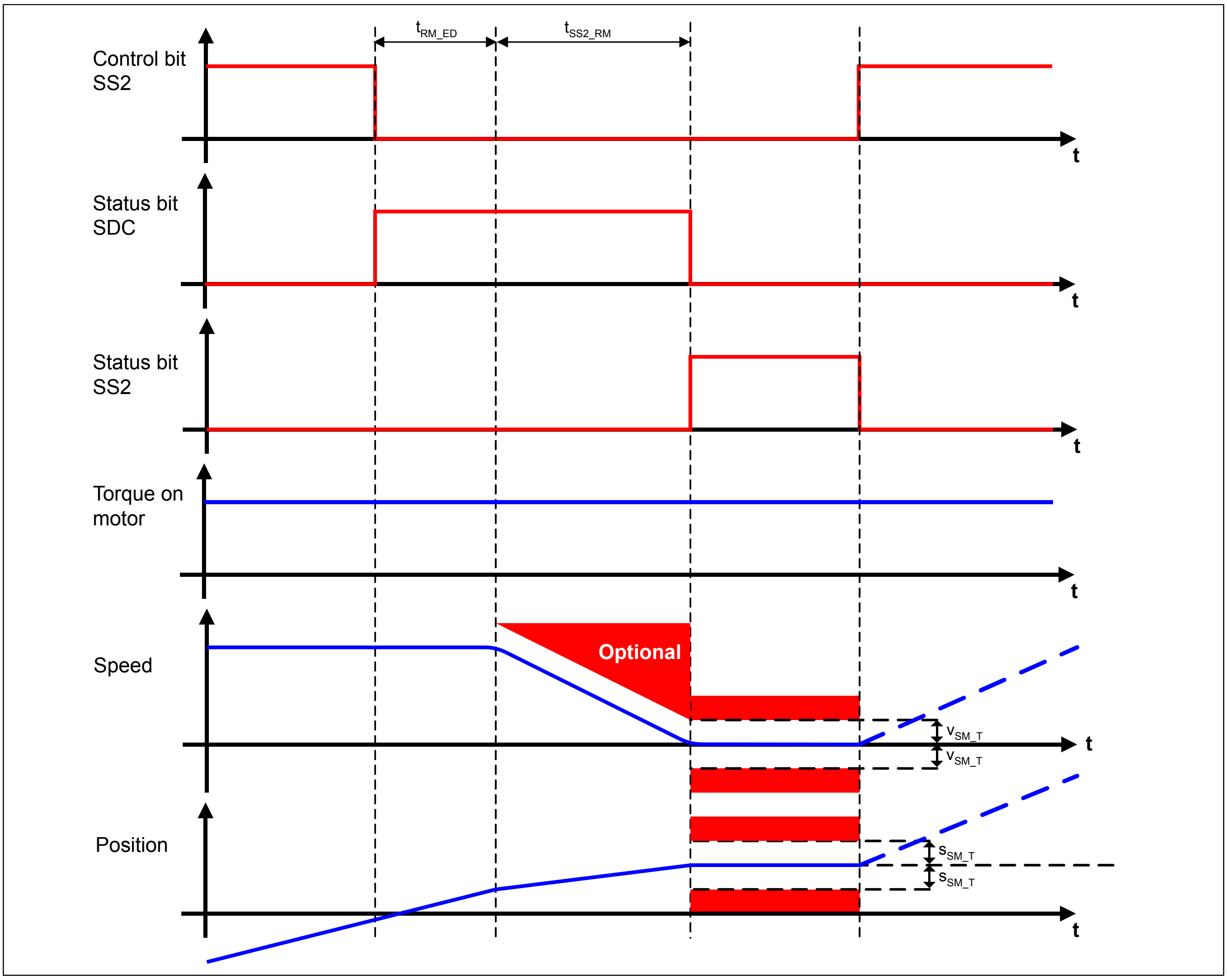


Figure 77: Safe Stop 2 (SS2)

Danger!

If a standstill limit (position or speed) is violated, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state. The drive loses all torque/power and coasts to a stop! In the event of an error, a synchronous axis will no longer be synchronous.
Output "S_NotErrFUNC" or "S_Status_NotErrFunc" of the function block is reset!

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

The purpose of the ramp delay time parameter "Ramp monitoring - Enable delay time" (t_{RM_ED}) is to compensate for the different runtimes of standard and safety applications.

Information:

The functional safe state of the SS2 function has been achieved when the drive is stopped and the standstill is being safety-monitored.
The respective bit is set when the functional safe state has been achieved.

As with SS1, it is possible to monitor either only the deceleration time or also the deceleration ramp depending on the requirements of the safety function.

The "SS2 - Ramp monitoring - Time" (t_{SS2_RM}) parameter configures the ramp monitoring behavior.

6.4.12.3 SS2 - Stopping procedure with ramp-based monitoring

"SS2 - Ramp monitoring - Enable" = Enabled

With this setting, the configurable deceleration ramp is monitored in addition to time-based monitoring. In the event of an error, this provides the advantage that a lower maximum speed can be assumed when entering the safe state. During deceleration ramp monitoring, the standard application must ensure that the stopping procedure for a hazardous situation is handled accordingly.

The slope of the monitoring ramp can be set using the "Ramp monitoring - Speed deceleration limit" (a_{RM_L}) parameter.

A timer is started when the safety function is requested. After the "Ramp monitoring - Enable delay time" (t_{RM_ED}) has expired, monitoring of the deceleration ramp begins. The monitored ramp always begins at the currently monitored limit and is calculated using the configured slope. If the monitoring ramp reaches the configurable standstill speed limit "Standstill monitoring - Speed tolerance" (v_{SM_T}) or if the monitoring time "SS2 - Ramp monitoring - Time" (t_{SS2_RM}) has expired, then a position window is established and monitoring of the standstill tolerances is started.

Setting "Early limit monitoring" to "Enable" makes it possible to configure an early enabling of the safe state. If the setting above has been made, then the safe state of the safety function will be started when the current speed falls below the standstill speed limit for at least the amount of time defined by "Early limit monitoring - Time" (t_{ELM}) during deceleration ramp monitoring.

If the active limit or standstill window is violated during monitoring of the deceleration procedure or standstill, then the drive will immediately switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Danger!

When the monitored ramp or standstill tolerance window is exceeded, the residual distance must be calculated based on the error response time, starting with the currently monitored speed limit.
The spin-out movement or residual distance is not permitted to result in a hazard!

Danger!

In the event of an error, forward movement can occur during the error response time when monitoring the standstill tolerance window. During this time, the drive can accelerate to its maximum before coasting to a stop.
The speed and position limits being monitored must be set in a manner so that the calculated forward movement does not cause any danger.
The dangerous movement must be determined by a risk analysis.

Danger!

If the SS2 safety function with ramp-based monitoring is used in the safety application, then it must be tested when commissioning the machine by selecting and deselecting it!
The test should contain at least one violation of the monitored ramp and standstill tolerance window.
The error response must be tested accordingly!

6.4.12.4 SS2 - Stopping procedure with time-based monitoring

"SS2 - Ramp monitoring - Enable" = Disabled

This configuration provides true time-based monitoring of the deceleration.
A timer is started when the safety function is requested. Within this time frame, the drive must implement a stopping procedure via the standard application that is appropriate for the respective dangerous situation.

After the delay time of the request "Ramp monitoring - Enable delay time" (t_{RM_ED}) plus the monitoring time "SS2 - Ramp monitoring - Time" (t_{SS2_RM}) have expired, the standstill tolerance window is safety-monitored.

Danger!

If the standstill tolerance window is exceeded, the residual distance must be calculated based on the error response time, starting with the currently monitored speed limit.
The spin-out movement or residual distance is not permitted to result in a hazard!

Danger!

In the event of an error, forward movement can occur during the error response time when monitoring the standstill tolerance window. During this time, the drive can accelerate to its maximum before coasting to a stop.
The speed and position limits being monitored must be set in a manner so that the calculated forward movement does not cause any danger.
The dangerous movement must be determined by a risk analysis.

Danger!

If the SS2 safety function with time-monitored stopping procedure is used in the safety application, then it must be tested when commissioning the machine by selecting and deselecting it!
The test should contain at least one violation of the standstill tolerance window. The error response must be tested accordingly!

6.4.13 Safely Limited Speed (SLS)

6.4.13.1 Parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 228: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr>
<tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr>
</table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 229: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SMS - Enable

(previously Safe Maximum Speed)</td><td>Enabled/
Disabled</td><td>Activates the SMS safety function by configuration
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>SMS activated</td></tr>
<tr><td>Disabled</td><td>SMS deactivated</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SMS - Speed limit

(previously Maximum Speed for SMS (units/s))</td><td>[units/s]</td><td>Speed limit of the maximum speed (SMS)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS1 - Speed limit

(previously Safe Speedlimit 1 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 1 for SLS (SLS1)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Speed limit

(previously Safe Speedlimit 2 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 2 for SLS (SLS2)</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 230: SafeMOTION parameter group: Speed functions - SMS/SLS

Parameter	Unit	Description	Default value	Starting in Safety Release
SLS3 - Speed limit (previously *Safe Speedlimit 3 for SLS (units/s)*)	[units/s]	Speed limit 3 for SLS (SLS3)	0	R 1.3
SLS4 - Speed limit (previously *Safe Speedlimit 4 for SLS (units/s)*)	[units/s]	Speed limit 4 for SLS (SLS4)	0	R 1.3
SLS - Ramp monitoring - Enable (previously *Rampmonitoring for SLS*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested **Value** – **Description** Enabled – When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time Disabled – When changing to the safe state of the SLS function, only a configurable time is monitored	Enabled	R 1.3
SLS1 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS1 (us)*)	[µs]	Deceleration ramp monitoring time for SLS1	0	R 1.3
SLS2 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS2 (us)*)	[µs]	Deceleration ramp monitoring time for SLS2	0	R 1.3
SLS2 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS3 (us)*)	[µs]	Deceleration ramp monitoring time for SLS3	0	R 1.3
SLS4 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS4 (us)*)	[µs]	Deceleration ramp monitoring time for SLS4	0	R 1.3

Table 230: SafeMOTION parameter group: Speed functions - SMS/SLS

Danger!

The respective monitored speed limit must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous speed cannot be exceeded in the event of error.
The dangerous speed must be determined by a risk analysis.

Information:

The following application rule must be observed:

$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS} \leq$ EUS - Maximum speed to normalize speed range

This is required for setting priority of the safety functions on the SafeMOTION module.

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

6.4.13.2 Behavior

The purpose of the SLS safety function is to monitor a specified speed limit: Parameters "SLS1 - Speed limit", "SLS2 - Speed limit", "SLS3 - Speed limit", "SLS4 - Speed limit" ($v_{SLS\mathbf{\mathit{x}}\_L}$). It is also possible to monitor deceleration until the limit is reached if needed by the application.

Four different speed limits can be monitored on the SafeMOTION module. All limits can also be monitored in parallel. If a request is made to monitor multiple speed limits at the same time, then the lowest limit value will always be monitored. To make this possible, the function block includes four different inputs "S_RequestSLS*X*" or "S_Control_SLS-*X*" [***X*** = 1..4].

The standard (non-safety-related) application must implement a closed-loop control appropriate for the level of danger to decelerate the movement and ensure adherence to the respective speed limit.

Information:

The SLS safety function requires safe evaluation of the speed. If the function is programmed in the safety application and if an error is detected in the safe encoder evaluation, then the SafeMOTION module immediately switches to the FUNCTIONAL FAIL SAFE state after the function block is activated!

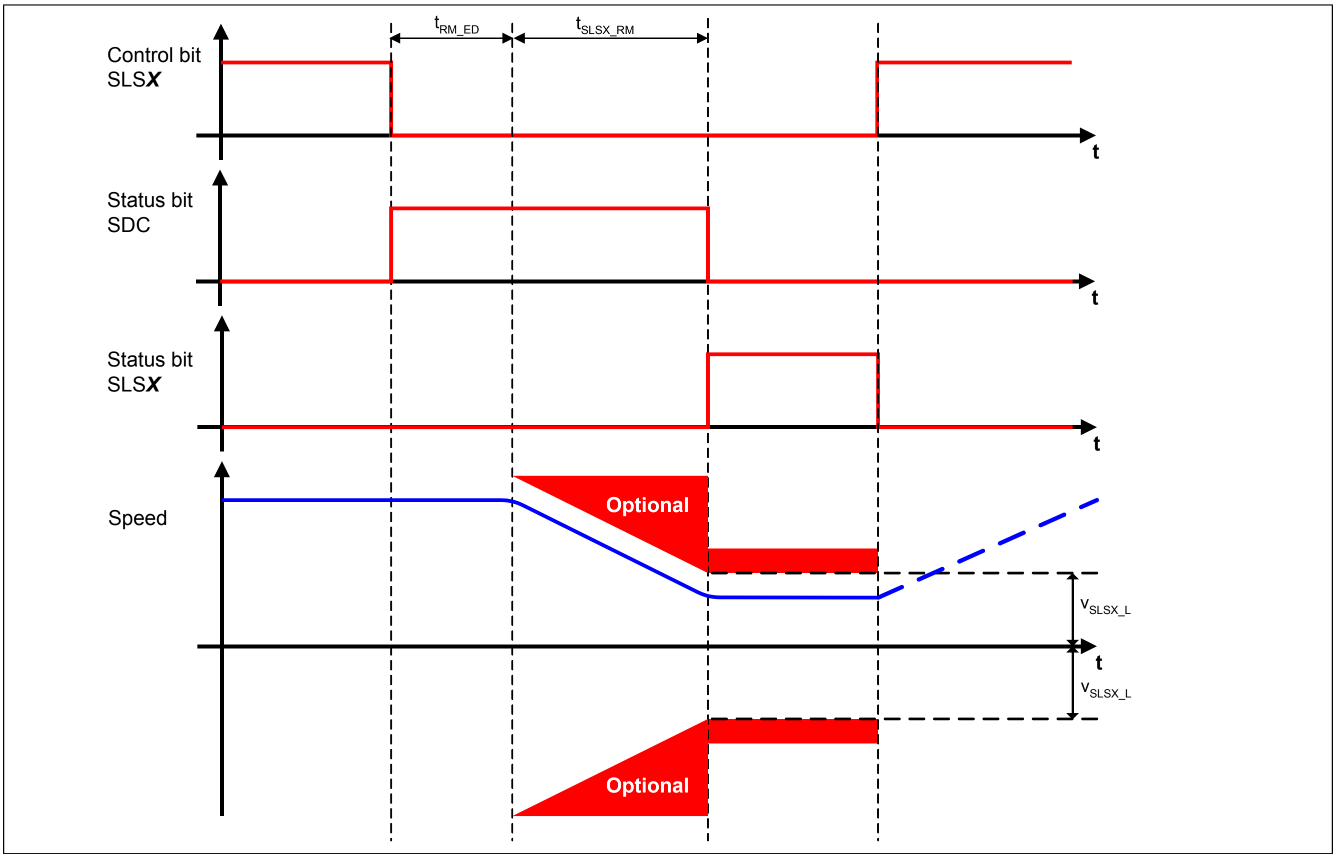


Figure 78: Safely Limited Speed (SLS)

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

Danger!

If a speed limit is violated, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.
Torque and power to the drive are switched off, causing the drive to spin out!
An error will cause a synchronous axis to no longer be synchronous! Output "S_NotErrFUNC" or "S_Status_NotErrFunc" of the function block is reset!

The purpose of the ramp delay time t_{RM_ED} is to compensate for runtime differences between the standard and safety applications.

If the delay time ("SLS1 - Ramp monitoring - Time", "SLS2 - Ramp monitoring - Time", "SLS3 - Ramp monitoring - Time", "SLS4 - Ramp monitoring - Time" (t_{SLSx_RM})) is set to zero, then the speed limit will be monitored immediately after the request is made for the safety function.

Information:

The functional safe state of the SLS safety function has been achieved if the drive has not exceeded a defined speed limit and this limit is being safety-monitored. The respective bit is set when the functional safe state has been achieved.

Like with SS1 and SS2, the deceleration ramp monitoring can be adjusted according to the requirements, so that either only the deceleration time or both the deceleration time and the deceleration ramp are monitored.
Parameter "SLS - Ramp monitoring - Enable" configures the ramp monitoring behavior.

6.4.13.3 SLS - Stopping procedure with ramp-based monitoring

"SLS - Ramp monitoring - Enable" = Enabled

With this setting, the configurable deceleration ramp is monitored in addition to time-based monitoring. In the event of an error, this provides the advantage that a lower maximum speed can be assumed when entering the safe state.
During deceleration ramp monitoring, a deceleration procedure must be adjusted to the dangerous situation by the standard application.

The slope of the monitoring ramp can be set using the "Ramp monitoring - Speed deceleration limit" (a_{RM_L}) parameter.

A timer is started when the safety function is requested. After the "Ramp monitoring - Enable delay time" (t_{RM_ED}) has expired, monitoring of the deceleration ramp begins. The monitored ramp always begins at the currently monitored limit and is calculated using the configured slope.
If the monitored ramp reaches the corresponding speed limit ("SLS1 - Speed limit", "SLS2 - Speed limit", "SLS3 - Speed limit", "SLS4 - Speed limit" (v_{SLSx_L})) or the monitoring time ("SLS1 - Ramp monitoring - Time", "SLS2 - Ramp monitoring - Time", "SLS3 - Ramp monitoring - Time", "SLS4 - Ramp monitoring - Time" (t_{SLSx_RM})) has expired, then the status of the safety function is set and the selected speed limit is monitored.

Setting "Early limit monitoring" to "Enable" makes it possible to configure an early enabling of the safe state. If the setting above has been made, then the safe state of the safety function will be started when the current speed falls below the monitored speed limit for at least the amount of time defined by "Early limit monitoring - Time" (t_{ELM}) during deceleration ramp monitoring.

Danger!

When the monitored ramp or the enabled safe speed is exceeded, the residual distance must be calculated based on the error response time, starting with the currently monitored speed limit. The spin-out movement or residual distance is not permitted to result in a hazard!

Danger!

In the event of an error when monitoring the safe reduced speed, a dynamic forward movement that goes beyond the monitored limit can occur during the error response time.
During this time, the drive can accelerate to its maximum before coasting to a stop.
The speed limit being monitored must be set in a manner so that the calculated forward movement will not cause any danger. The dangerous movement must be determined by a risk analysis.

Danger!

If the safety function SLS with ramp-based monitoring is used in the safety application, then it must be tested when commissioning the machine by selecting and deselecting it!
The test should contain at least one violation of the monitored ramp and of each speed limit being used. The error response must be tested accordingly!

6.4.13.4 SLS - Stopping procedure with time-based monitoring

"SLS - Ramp monitoring - Enable" = Disabled

This configuration provides true time-based monitoring of the deceleration.
A timer is started when the safety function is requested. Within this time frame, the drive must implement a stopping procedure via the standard application that is appropriate for the respective dangerous situation. After the delay time of the request "Ramp monitoring - Speed deceleration limit" plus the monitoring time "SLS1 - Ramp monitoring - Time", "SLS2 - Ramp monitoring - Time", "SLS3 - Ramp monitoring - Time", "SLS4 - Ramp monitoring - Time" ($t_{SLS\boldsymbol{x}\_RM}$) have expired, the speed limit is safety-monitored.

Danger!

When the speed limit is exceeded, the residual distance must be calculated based on the error response time, starting with the currently monitored speed limit.
The spin-out movement or residual distance is not permitted to result in a hazard!

Danger!

In the event of an error when monitoring the safe reduced speed, a dynamic forward movement that goes beyond the monitored limit can occur during the error response time.
During this time, the drive can accelerate to its maximum before coasting to a stop.
The speed limit being monitored must be set in a manner so that the calculated forward movement will not cause any danger.
The dangerous movement must be determined by a risk analysis.

Danger!

If the safety function SLS without ramp-based monitoring is used in the safety application, then it must be tested when commissioning the machine by selecting and deselecting it!
The test should contain at least one violation of each speed limit being used.
The error response must be tested accordingly!

6.4.14 Safe Maximum Speed (SMS)

6.4.14.1 Parameters

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SMS - Enable

(previously Safe Maximum Speed)</td><td>Enabled/ Disabled</td><td>Activates the SMS safety function by configuration<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>SMS activated</td></tr><tr><td>Disabled</td><td>SMS deactivated</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SMS - Speed limit

(previously Maximum Speed for SMS (units/s))</td><td>[units/s]</td><td>Speed limit of the maximum speed (SMS)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS1 - Speed limit

(previously Safe Speedlimit 1 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 1 for SLS (SLS1)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Speed limit

(previously Safe Speedlimit 2 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 2 for SLS (SLS2)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS3 - Speed limit

(previously Safe Speedlimit 3 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 3 for SLS (SLS3)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS4 - Speed limit

(previously Safe Speedlimit 4 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 4 for SLS (SLS4)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS - Ramp monitoring - Enable

(previously Rampmonitoring for SLS)</td><td>Enabled/ Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr><tr><td>Disabled</td><td>When changing to the safe state of the SLS function, only a configurable time is monitored</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SLS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS1</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS2 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS2</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS3 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS3</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS4 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS4 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS4</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 231: SafeMOTION parameter group: Speed functions - SMS/SLS

Danger!

The respective monitored speed limit must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous speed cannot be exceeded in the event of error.
The dangerous speed must be determined by a risk analysis.

Information:

The following application rule must be observed:

$LIM_{SOS} \le LIM_{SLS4} \le LIM_{SLS3} \le LIM_{SLS2} \le LIM_{SLS1} \le LIM_{SMS} \le$ EUS - Maximum speed to normalize speed range

This is required for setting priority of the safety functions on the SafeMOTION module.

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

6.4.14.2 Behavior

The difference between SMS and SLS is that SMS cannot be actively requested. It is either enabled (parameter "SMS - Enable" = Enabled) or disabled (parameter "SMS - Enable" = Disabled) in the configuration.

When enabled, the current speed is constantly monitored according to a defined limit ("SMS - Speed limit" (v_{SMS_L}) parameter).

Information:

The SMS safety function requires safe evaluation of the speed.
If the function is programmed in the safety application and if an error is detected in the safe encoder evaluation, then the SafeMOTION module immediately switches to the FUNCTIONAL FAIL SAFE state after the function block is activated!

Danger!

When the monitored speed limit is exceeded, the residual distance must be calculated based on the error response time.
The spin-out movement or residual distance is not permitted to result in a hazard!

Danger!

In the event of an error when monitoring the safe maximum speed, a dynamic forward movement that goes beyond the monitored limit can occur during the error response time.
During this time, the drive can accelerate to its maximum before coasting to a stop. The speed limit being monitored must be set in a manner so that the calculated forward movement will not cause any danger.
The dangerous movement must be determined by a risk analysis.

Danger!

If the SMS safety function is used in the safety application, then it must be tested when commissioning the machine!
The configured limit must be exceeded! The error response must be tested accordingly!

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

6.4.15 Safely Limited Increment (SLI)

6.4.15.1 Parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 232: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SLI (previously *Safely Limited Increment*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLI - Position limit (previously *Safe Increments (units)*)	[units]	Maximum movable increments when SLI is active	0	R 1.3
SLI - Disable delay time (previously *SLI Off Delay (µs)*)	[µs]	Switch off delay of SLI	0	R 1.3

Table 233: SafeMOTION parameter group: Advanced functions - SLI

Danger!

The maximum increment range must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

6.4.15.2 Behavior

With the SLI safety function, the movement is monitored for a defined number of increments ("SLI - Position limit" (s_{SLI_L}) parameter).

Information:

The SLI safety function requires safe evaluation of the speed and position.
If the function is programmed in the safety application and if an error is detected in the safe encoder evaluation, then the SafeMOTION module immediately switches to the FUNCTIONAL FAIL SAFE state after the function block is activated!

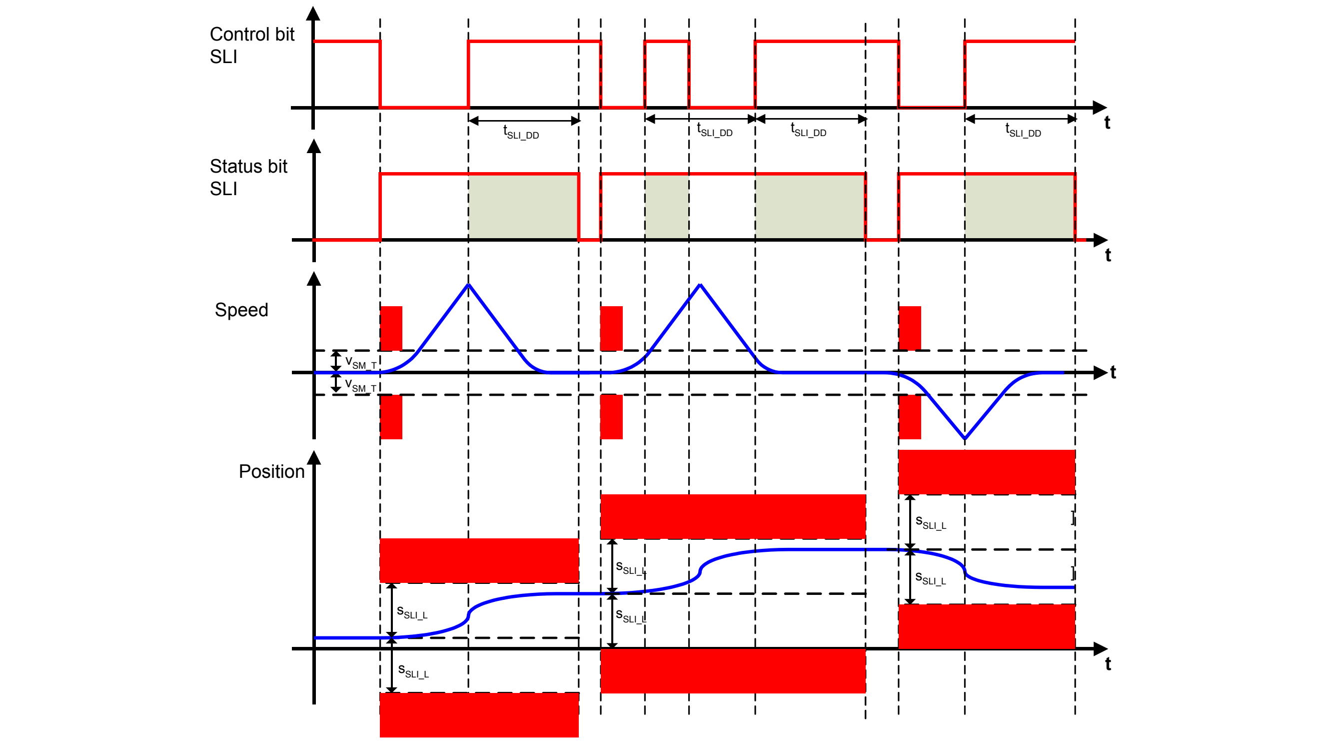


Figure 79: Safely Limited Increment (SLI)

Information:

The SLI safety function is only effective when used in combination with at least a second safety function. The SOS, SS2, or SLS safety functions are possible, for example.

Information:

The functional safe state of the SLI safety function has been achieved if the drive has not exceeded a defined increment size and this limit is being safety-monitored.
The respective bit is set when the functional safe state has been achieved.

The safe axis must be at a standstill when this function is enabled. To do this, the speed is monitored for adhering to the speed standstill tolerance (parameter "Standstill monitoring - Speed tolerance" (v_{SM_T}).

A position window is then generated that is safety-monitored. This position window depends on the configured safe increment size ("SLI - Position limit" (s_{SLI_L} parameter). The standard application must guarantee that this position window is not exceeded.

After the safety function is disabled, monitoring continues for the configured period of time ("SLI - Disable delay time"(t_{SLI_DD}) parameter). This prevents continuous movement caused by constant jogging.

Danger!

If a speed limit for requesting the function or the position window is violated, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.
The drive loses all torque/power and coasts to a stop! In the event of an error, a synchronous axis will no longer be synchronous.
Output "S_NotErrFUNC" or "S_Status_NotErrFunc" of the function block is reset!

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

Danger!

In the event of an error when monitoring the safe increments, a dynamic forward movement that goes beyond the monitored limit can occur during the error response time.
During this time, the drive can accelerate to its maximum before coasting to a stop.
The resulting residual distance must be taken into account when configuring the permissible increments and is not permitted to present any danger.
The dangerous movement must be determined by a risk analysis.

Danger!

If the SLI safety function is used in the safety application, then it must be tested when commissioning the machine by selecting and deselecting it!
The test should contain at least one violation of the standstill speed limit when enabled and the permissible increments. The error response must be tested accordingly!

6.4.16 Safe Direction (SDI)

6.4.16.1 Parameters

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 234: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*)	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 235: SafeMOTION parameter group: Advanced functions - SDI

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

6.4.16.2 Behavior

The SDI safety function monitors the defined direction of movement.

Either the positive or the negative direction can be monitored. The two inputs "S_RequestSDIpos" or "S_Control_SDI-P" and "S_RequestSDIneg" or "S_Control_SDI-N" are available on the function block for this purpose.

Information:

The SDI safety function requires safe evaluation of the position.
If the function is programmed in the safety application and if an error is detected in the safe encoder evaluation, then the SafeMC module immediately switches to the FUNCTIONAL FAIL SAFE state after the function block is activated!

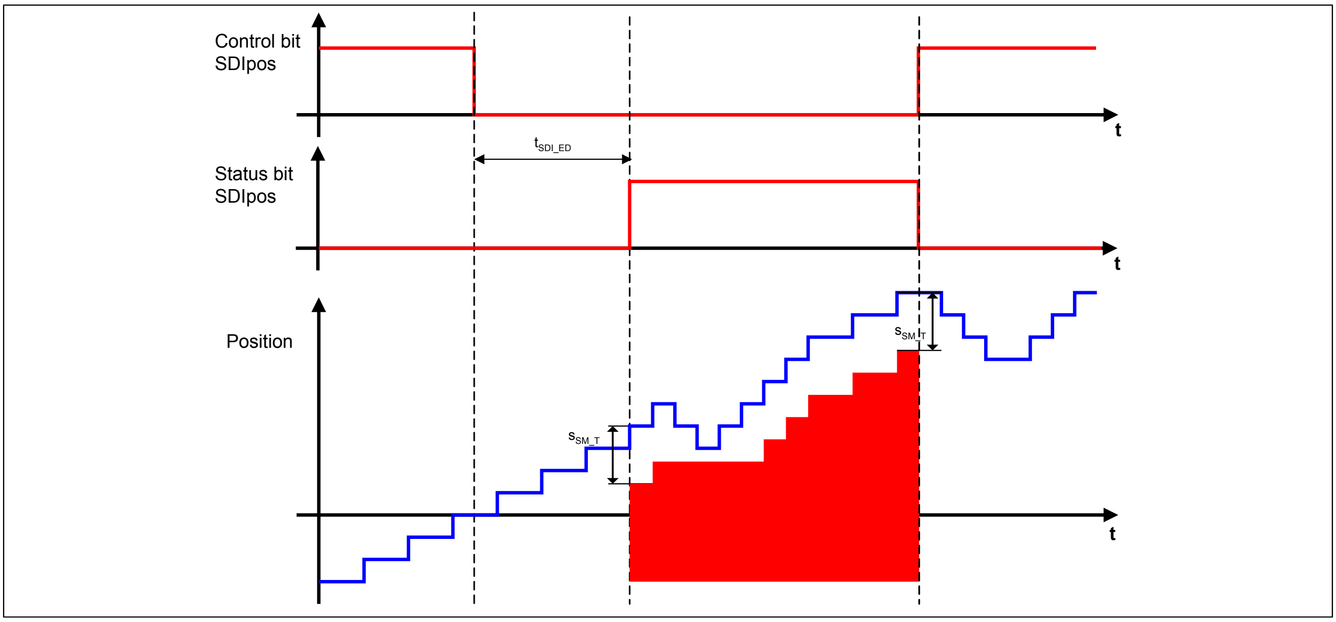


Figure 80: Safe Direction (SDI) - Positive direction of rotation allowed

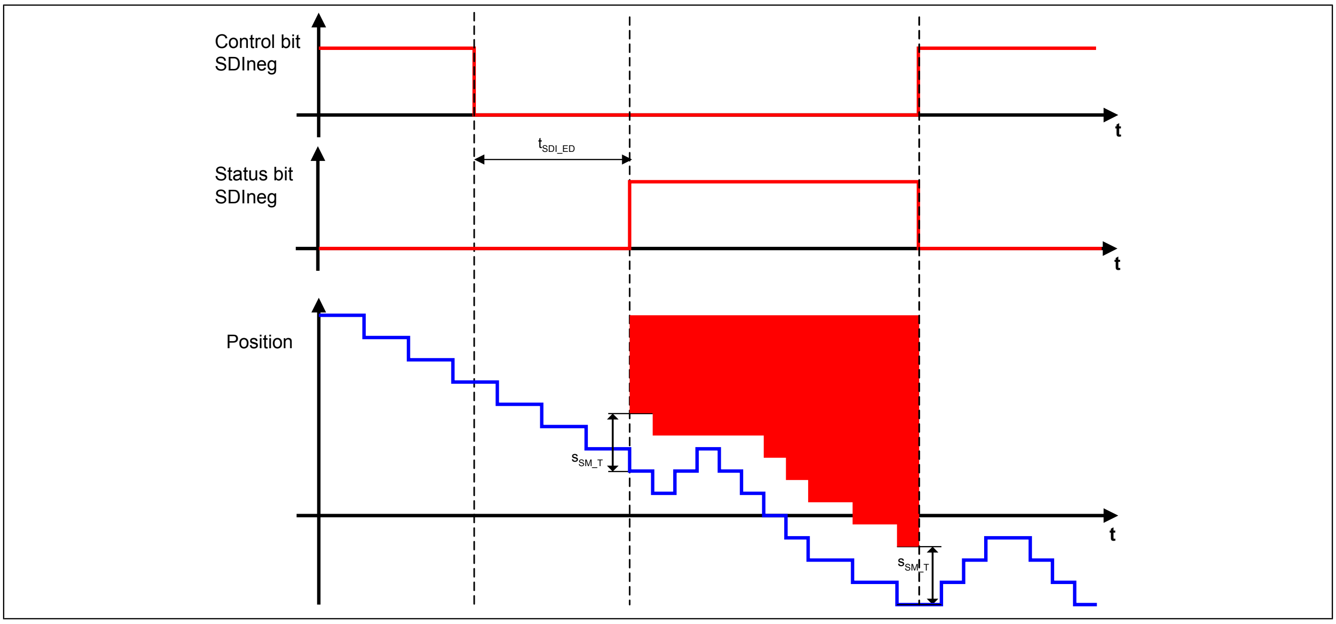


Figure 81: Safe Direction (SDI) - Negative direction of rotation allowed

Information:

The Safe Direction safety function can be activated in parallel with other safety functions. For example, SLS or SLI can be limited to a certain direction.

Information:

The functional safe state of the SDI safety function has been achieved if the drive has not violated a defined direction of movement and this direction of movement is being safety-monitored.
The respective bit is set when the functional safe state has been achieved.

The purpose of the delay time "SDI - Enable delay time" (t_{SDI_ED}) is to compensate for the different runtimes of standard and safety applications.

When monitoring the direction of movement, then standstill tolerance ("Standstill monitoring - Position tolerance" (s_{SM_T}) parameter) is not permitted to be exceeded in the forbidden direction of movement. When moving in the permissible direction of movement, the position window moves along with it.

Danger!

If the safe direction of movement is violated, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state. Torque and power to the drive are switched off, causing the drive to spin out!
An error will cause a synchronous axis to no longer be synchronous!
Output "S_NotErrFUNC" or "S_Status_NotErrFunc" of the function block is reset!

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

Danger!

In the event of an error when monitoring the safe direction of rotation, a dynamic forward movement in the dangerous direction can occur during the error response time.
During this time, the drive can accelerate to its maximum before coasting to a stop. The resulting residual distance must be taken into account when configuring the permissible tolerance limits and is not permitted to present any danger.
The dangerous movement must be determined by a risk analysis.

Danger!

If the SDI safety function is used in the safety application, then each of the directions of movement that are being used must be tested by selecting and deselecting it when commissioning the machine!
The test should contain at least one violation of each safe direction of movement that is being used.
The error response must be tested accordingly!

6.4.17 Safely Limited Acceleration (SLA)

Information:

Safety function Safely Limited Acceleration (SLA) is only available with SafeMOTION Safety Release 1.9 (firmware 300) and later!

6.4.17.1 Parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 236: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Speed functions - SLA (previously *Safely Limited Acceleration*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLA - Acceleration limit in positive direction (previously *Safe acceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for acceleration in the positive direction of movement	0	R 1.9
SLA - Deceleration limit in positive direction (previously *Safe deceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for deceleration in the positive direction of movement	0	R 1.9
SLA - Acceleration limit in negative direction (previously *Safe acceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for acceleration in the negative direction of movement	0	R 1.9
SLA - Deceleration limit in negative direction (previously *Safe deceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for deceleration in the negative direction of movement	0	R 1.9
SLA - Enable delay time (previously *Delay time to start SLA (us)*)	[µs]	Delay time between the SLA request and activation of the safety function	0	R 1.9

Table 237: SafeMOTION parameter group: Speed functions - SLA

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

6.4.17.2 Behavior

The SLA safety function is used to monitor the acceleration or deceleration with respect to defined maximum limits.

Information:

The SLA safety function requires safe encoder evaluation.

If the safety function is programmed in the safety application and if an error is detected in the safe encoder evaluation, then the SafeMOTION module immediately switches to the FUNCTIONAL FAIL SAFE state after the function block is activated!

The parameters "SLA - Acceleration limit in positive direction" ($a_{SLA\_ACC\_P\_L}$) and "SLA - Deceleration limit in positive direction" ($a_{SLA\_DEC\_P\_L}$) can be used to set the limit values for acceleration and deceleration in the positive direction of movement. The parameters "SLA - Acceleration limit in negative direction" ($a_{SLA\_ACC\_N\_L}$) and "SLA - Deceleration limit in negative direction" ($a_{SLA\_DEC\_N\_L}$) can be used to set the limit values in the negative direction of movement.

Setting input "S_RequestSLA" or "S_Control_SLA" to SAFEFALSE requests safety function SLA.

After the "SLA - Enable delay time" (t_{SLA_ED}) has expired, the configured acceleration and deceleration limits are monitored. The purpose of the delay time is to compensate for the different runtimes of the standard and safety applications.

The "SafetyActiveSLA" or "S_Status_SLA" status bit will be set to SAFETRUE if no errors occur while monitoring is active.

Information:

The SLA safety function can be activated in parallel with other safety functions. This makes it possible, for example, to reduce the expected residual distances in the worst-case calculation.

Information:

The SLA safety function has achieved its safe state when the safety function is selected and no violation is detected during monitoring of the acceleration and deceleration limits.

The respective bit is set when the functional safe state has been achieved.

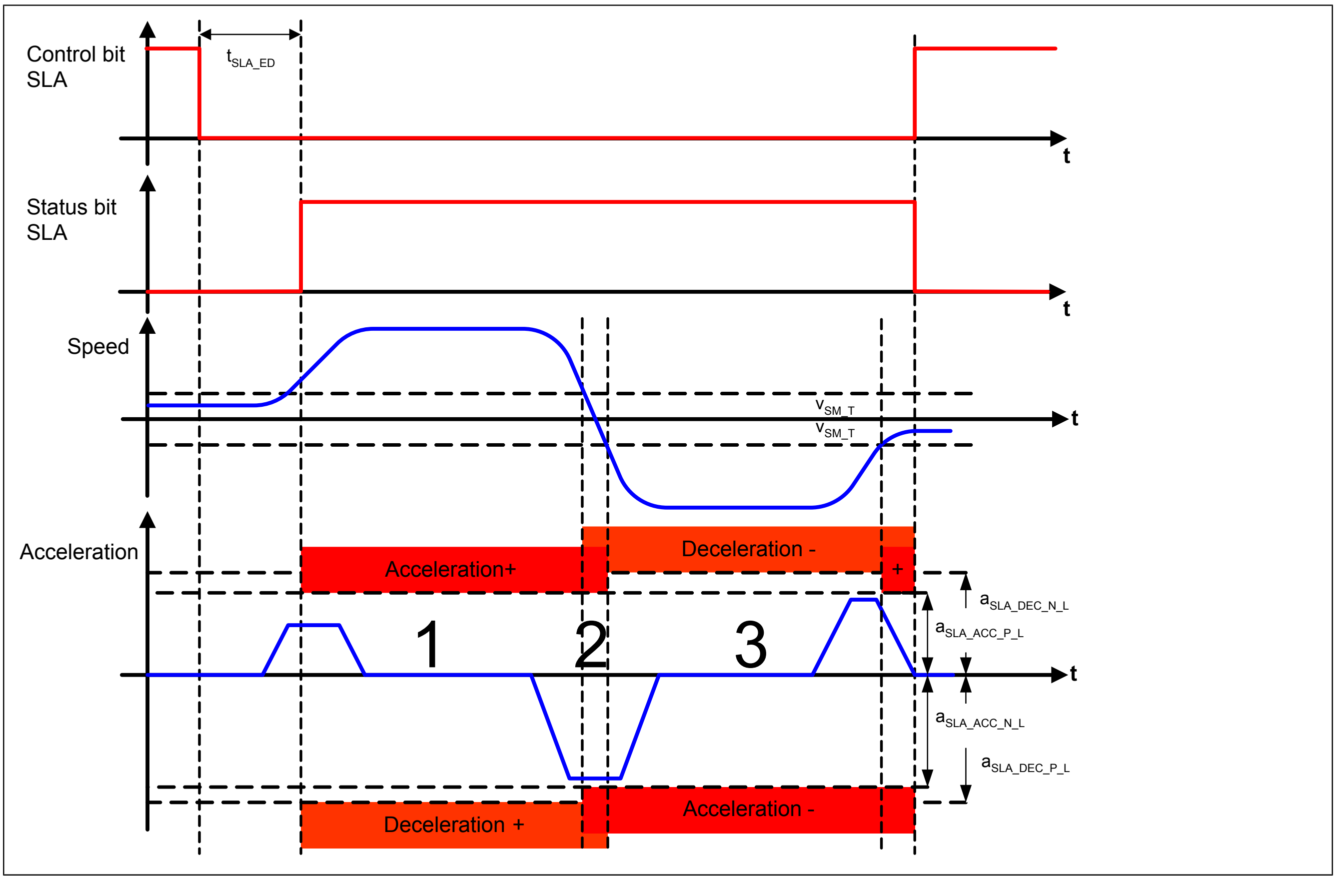


Figure 82: Safely Limited Acceleration (SLA)

Monitoring of acceleration and deceleration limits can be classified into the following 3 types (see Fig. 82 "Safely Limited Acceleration (SLA)"):

1 Positive direction of movement

If a movement in the positive direction is detected (current speed is greater than the value of the "Standstill monitoring - Speed tolerance" (v_{SM_T}) parameter for standstill monitoring), then the limit values set using the "SLA - Acceleration limit in positive direction" ($a_{SLA\_ACC\_P\_L}$) and "SLA - Deceleration limit in positive direction" ($a_{SLA\_DEC\_P\_L}$) parameters are monitored.

2 Standstill

If standstill is detected (current speed is within ± the value set for the "Standstill monitoring - Speed tolerance" (v_{SM_T}) parameter for standstill monitoring), then the lowest limit value is used for monitoring in each case:

- "SLA - Acceleration limit in positive direction" ($a_{SLA\_ACC\_P\_L}$) and "SLA - Deceleration limit in negative direction" ($a_{SLA\_DEC\_N\_L}$)
- "SLA - Deceleration limit in positive direction" ($a_{SLA\_DEC\_P\_L}$) and "SLA - Acceleration limit in negative direction" ($a_{SLA\_ACC\_N\_L}$)

3 Negative direction of movement

If a movement in the negative direction is detected (current speed is less than the value of the "Standstill monitoring - Speed tolerance" (v_{SM_T}) parameter for standstill monitoring in the negative direction), then the limit values set using the "SLA - Acceleration limit in negative direction" ($a_{SLA\_ACC\_N\_L}$) and "SLA - Deceleration limit in negative direction" ($a_{SLA\_DEC\_N\_L}$) parameters are monitored.

Danger!

If an acceleration or deceleration limit is violated, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

The drive loses all torque/power and coasts to a stop!

In the event of an error, a synchronous axis will no longer be synchronous. The S_NotErrFUNC output on the function block is reset.

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

Danger!

When calculating the residual distance when the monitored limit values are violated, the worst case scenario – i.e. the maximum speed possible – must be assumed. The maximum possible speed of the drive in the event of an error is calculated based on the speed at the time of the error, the maximum acceleration and the error response time.

The spin-out movement or residual distance is not permitted to result in a hazard!

Danger!

When acceleration or deceleration is safety-monitored, a dynamic forward movement may occur during the error response time. During this time, the drive can accelerate to its maximum before coasting to a stop. The limit being monitored must be set so that the calculated forward movement will not cause any danger.

The dangerous movement must be determined by a risk analysis.

Danger!

If the safety function is used in the safety application, then it must be tested when commissioning the machine by selecting and deselecting it!

The test should contain at least one violation of each configured limit. The error response must be tested accordingly!

6.4.18 Safe Homing

Information:

The Safe Homing safety function is only available with Safety Release R 1.4 and later!

6.4.18.1 Parameters

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Mode (previously *Mode*)	Direct / Reference switch / *Home Offset /* *Home offset with correction*	Selects the homing mode *Modes "Home offset" and "Home offset with correction" are only available for ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	Direct	R 1.4
Homing - Home position or home offset (previously *Home Position or Home Offset (units)*)	[units]	Home position or home offset	0	R 1.4
Homing - Enable RSP (Remanent safe position) *(previously Remanent safe position)*	*Enabled/* *Disabled*	*Selects whether or not to use the remanent safe position* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*Disabled*	R 1.9
Homing - Edge of reference switch (previously *Edge of reference switch*)	Positive / Negative	Selects the switching edge for the reference switch The switching edge for the reference switch input is positive if the logical state of the reference switch changes from SAFEFALSE to SAFETRUE in the positive direction of movement.	Positive	R 1.4
Homing - Trigger direction (previously *Trigger direction*)	Positive / Negative	Selects the trigger direction If the homing procedure requires a movement, then this parameter specifies the direction for evaluating the reference switch / reference pulse.	Positive	R 1.4
Homing - Enable reference pulse *(previously Reference pulse)*	*Enabled/* *Disabled*	*Selects whether or not to use a reference pulse for homing* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*Disabled*	R 1.4
Homing - Blocking distance *(previously Blocking distance (% encoder reference system))*	*%*	*Distance within which evaluation of the reference pulse will be suppressed.* *This is calculated starting at the configured reference switch edge and indicated as a percentage of the encoder reference system.* *A single revolution is used as the encoder reference system for rotary encoders.* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*0*	R 1.4
Homing - Maximum trigger speed (previously *Max. trigger speed (units/s)*)	[units/s]	Maximum permissible speed for evaluating the reference switch / reference pulse	0	R 1.4
Homing - Monitoring time (previously *Homing Monitoring Time (µs)*)	[µs]	Monitoring time for the homing procedure	0	R 1.4

Table 238: SafeMOTION parameter group: Absolute position functions - Homing

6.4.18.2 Behavior

The Safe Homing function provides a way to establish a reference between the encoder position and the machine position.

Depending on the homing mode, it may be necessary for the drive to perform a homing procedure. A homing procedure requires the control functions between the electronic controller and the drive motor to be active. Other safety functions might have to be selected in order to prevent a hazardous state during the homing procedure.

The following homing modes are supported:

- Direct
- Reference switch
- Home offset / Home offset with correction *(only available for ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!)*

Information:

Safe homing requires safe evaluation of the position.
If the function is programmed in the safety application and if an error is detected in the safe encoder evaluation, then the SafeMOTION module immediately switches to the FAIL SAFE state after the function block is activated! The only way to exit the FAIL SAFE state is to complete a power off/on cycle!

A positive edge on the **RequestHoming** control bit starts "Safe Homing" and simultaneously resets the **SafePositionValid** status bit.
As soon as the homing procedure is finished, the **SafePositionValid** status bit is set and the **RequestHoming** control bit must be reset.
The homing procedure must be complete within the monitoring time "Homing - Monitoring time" (t_{HOME_M}) or else the SafeMOTION module will switch to the FUNCTIONAL FAIL SAFE state.

The homing procedure will be aborted if the **RequestHoming** control bit is reset before the procedure is completed.

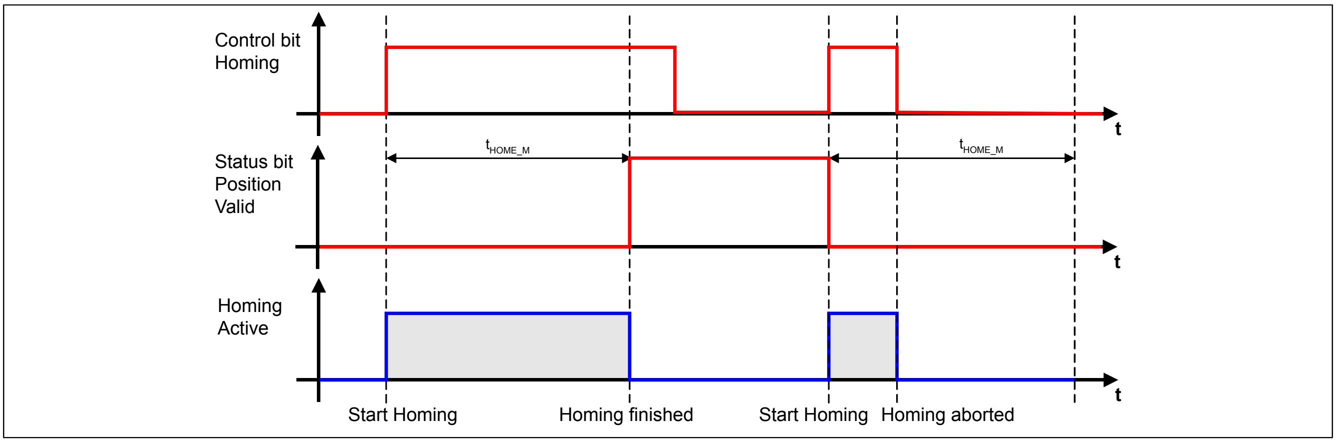


Figure 83: Safe Homing

Information:

The Safe Homing safety function is a prerequisite for implementing the SLP and SMP safety functions and for using the safe position. The SafePositionValid status will remain set to SAFEFALSE until safe homing has been performed!

Danger!

If an error occurs during the homing procedure, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.
The S_NotErrFUNC output on the function block is reset, and the drive loses all torque/power and coasts to a stop!
In the event of an error, a synchronous axis will no longer be synchronous.

Danger!

If the safe position is used in SafeDESIGNER, then the "Position Valid" output of the SF_SafeMC_Position_BR(_V2, _V3) function block must also always be evaluated.
This will be reset immediately only with referenced axes SAFETRUE, and the first time an encoder error occurs (SAFEFALSE).
This enables the safety application to detect any encoder error, even if only brief.
If a machine reference is not required for the application, then the axis can be referenced using "Direct" mode.

6.4.18.2.1 ReqHominOK status

The S_ReqHominOK" or "S_Status_ReqHomingOk" status is only available with Safety Release R1.9 and later. The "S_ReqHominOK" or "S_Status_ReqHomingOk" status provides feedback in SafeDESIGNER regarding whether direct homing is performed when the "S_PositionValid" or "S_Status_Homing" status is already set, even for large cycle times.

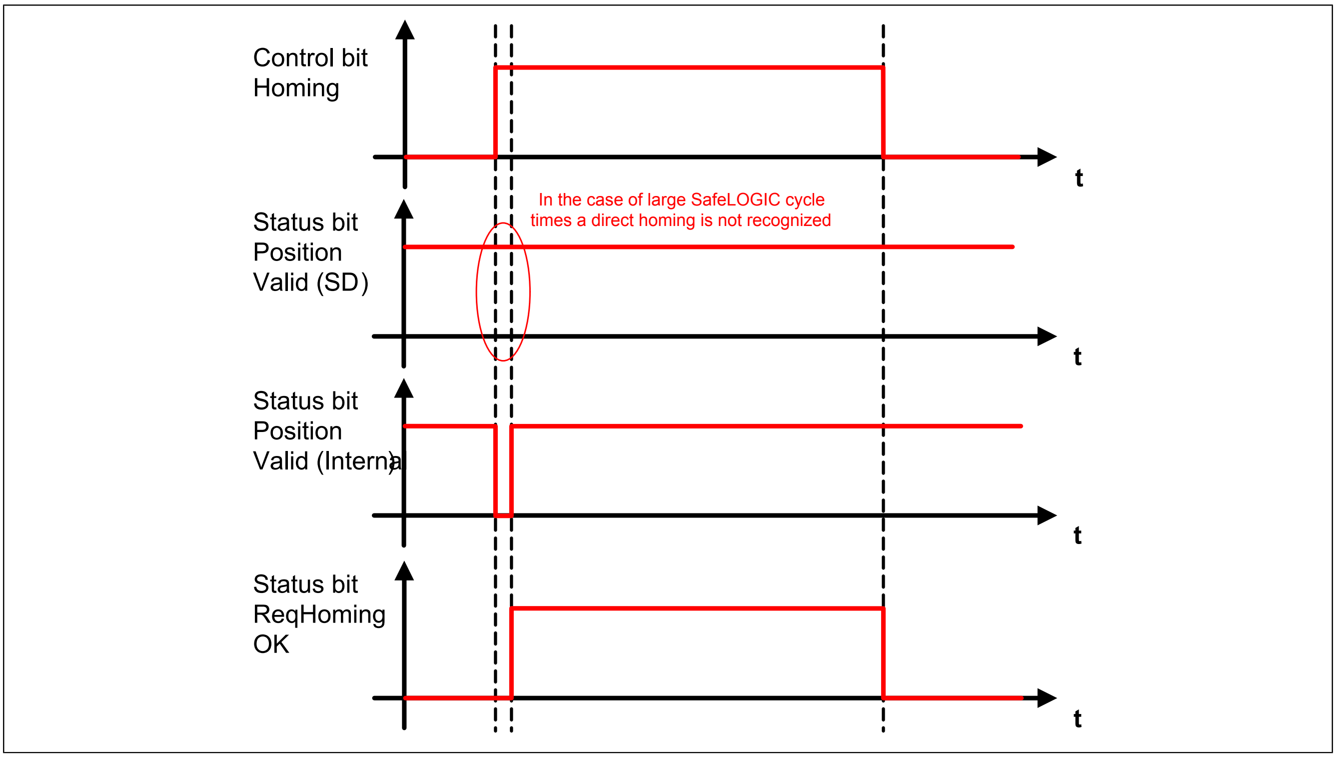


Figure 84: Safe homing - "ReqHomingOK" status bit

6.4.18.3 "Direct" mode

6.4.18.3.1 Parameters

Group: Absolute position functions - Homing (previously *Homing*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Home position or home offset (previously *Home Position or Home Offset (units)*)	[units]	Home position or home offset	0	R 1.4
Homing - Mode (previously *Mode*)	Direct / Reference Switch / *Home Offset /* *Home Offset with Correction*	Selects the homing mode *Modes "Home offset" and "Home offset with correction" are only available for ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	Direct	R 1.4
Homing - Enable reference pulse *(previously Reference pulse)*	*Enabled/* *Disabled*	*Selects whether or not to use a reference pulse for homing* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2!*	*Disabled*	R 1.4

Table 239: SafeMOTION parameter group: Absolute position functions - Homing

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 240: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Absolute position functions - SMP/SLP (previously *Safety Position Limits*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SMP - Enable

(previously Safe Maximum Position)</td><td>Enabled/
Disabled</td><td>Activates the SMP safety function from the configuration<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>SMP is activated</td></tr><tr><td>Disabled</td><td>SMP is deactivated</td></tr></table></td><td>Disabled</td><td>R 1.4</td></tr>
<tr><td>SMP - Lower position limit

(previously Safe Lower Position Limit for SMP (units))</td><td>[units]</td><td>Lower position limit for the machine's full travel range</td><td>0</td><td>R 1.4</td></tr>
<tr><td>SMP - Upper position limit

(previously Safe Upper Position Limit for SMP (units))</td><td>[units]</td><td>Upper position limit for the machine's full travel range</td><td>0</td><td>R 1.4</td></tr>
<tr><td>SLP - Lower position limit

(previously Safe Lower Position Limit for SLP (units))</td><td>[units]</td><td>Lower position limit for the monitoring range</td><td>0</td><td>R 1.4</td></tr>
<tr><td>SLP - Upper position limit

(previously Safe Upper Position Limit for SLP (units))</td><td>[units]</td><td>Upper position limit for the monitoring range</td><td>0</td><td>R 1.4</td></tr>
<tr><td>SLP - Enable delay time

(previously Delay time to start SLP (us))</td><td>[µs]</td><td>Delay time between the SLP request and start of monitoring</td><td>0</td><td>R 1.4</td></tr>
</table>

Table 241: SafeMOTION parameter group: Absolute position functions - SMP/SLP

Danger!

The position limits being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement, a dangerous movement cannot occur in the event of a worst case scenario.

The dangerous movement must be determined by a risk analysis.

Information:

The following application rule must be observed:

$\mathbf{LIM_{SMP,NEG} \leq LIM_{SLP,NEG} \leq LIM_{SLP,POS} \leq LIM_{SMP,POS}}$

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

6.4.18.3.2 Behavior

"Direct" mode is used if the current position of the axis is known and only needs to be applied to the SafeMOTION module.

The following scenario is an example of how this mode can be used:

- A functional homing procedure is first carried out on the SafeMOTION module.
- The axis is then moved to a defined position.
- The operator confirms via a safe button that the position is correct → internally, a safe homing procedure is initiated in "Direct" mode.

When homing in "Direct" mode, the actual position of the axis is set to the value specified in the "Homing - Home position or home offset" (s_{HOME}) parameter immediately after the homing command (positive edge on the "S_RequestHoming" or "S_Control_Homing" input).

The "S_ReferenceSwitch" or "S_Control_RefSwitch" input is not evaluated.

Information:

The axis must be at a standstill when the homing request is made.
The values configured under "General settings - Standstill monitoring" are monitored in this regard.
If the standstill tolerances are violated, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state. The "S_NotErrFUNC" or "S_Status_NotErrFunc" output on the function block is reset, and the drive loses all torque/power and coasts to a stop!

Information:

The reference pulse is not permitted to be used in Direct mode!
If the reference pulse is being used ("Homing - Enable reference pulse" = Enabled), then the system will enter state FAIL SAFE when checking the configuration during startup.
The only way to exit the FAIL SAFE state is to complete a power off/on cycle and modify the safety application!

Information:

If Safe Maximum Position has been activated in the configuration ("SMP - Enable" = Enabled), then the value set for the "Homing - Home position or home offset" (s_{HOME}) parameter must lie within the permissible SMP window ("SMP - Lower position limit" (s_{SMP_LL}) and "SMP - Upper position limit" (s_{SMP_UL} parameters).
If this is not the case, then the system will switch to the FAIL SAFE state when the configuration is checked during startup.
The only way to exit the FAIL SAFE state is to complete a power off/on cycle and modify the safety application!

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

6.4.18.4 "Reference switch" mode

6.4.18.4.1 parameter

Group: Absolute position functions - Homing (previously *Homing*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Mode (previously *Mode*)	Direct / Reference switch / *Home Offset /* *Home offset with correction*	Selects the homing mode *Modes "Home offset" and "Home offset with correction" are only available for ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	Direct	R 1.4
Homing - Home position or home offset (previously *Home Position or Home Offset (units)*)	[units]	Home position or home offset	0	R 1.4
Homing - Enable RSP (Remanent safe position) *(previously Remanent safe position)*	*Enabled/ Disabled*	*Selects whether or not to use the remanent safe position* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*Disabled*	R 1.9
Homing - Edge of reference switch (previously *Edge of reference switch*)	Positive / Negative	Selects the switching edge for the reference switch The switching edge for the reference switch input is positive if the logical state of the reference switch changes from SAFEFALSE to SAFETRUE in the positive direction of movement.	Positive	R 1.4
Homing - Trigger direction (previously *Trigger direction*)	Positive / Negative	Selects the trigger direction If the homing procedure requires a movement, then this parameter specifies the direction for evaluating the reference switch / reference pulse.	Positive	R 1.4
Homing - Enable reference pulse *(previously Reference pulse)*	*Enabled/ Disabled*	*Selects whether or not to use a reference pulse for homing* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*Disabled*	R 1.4
Homing - Blocking distance *(previously Blocking distance (% encoder reference system))*	*%*	*Distance within which evaluation of the reference pulse will be suppressed.* *This is calculated starting at the configured reference switch edge and indicated as a percentage of the encoder reference system.* *A single revolution is used as the encoder reference system for rotary encoders.* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*0*	R 1.4
Homing - Maximum trigger speed (previously *Max. trigger speed (units/s)*)	[units/s]	Maximum permissible speed for evaluating the reference switch / reference pulse	0	R 1.4
Homing - Monitoring time (previously *Homing Monitoring Time (µs)*)	[µs]	Monitoring time for the homing procedure	0	R 1.4

Table 242: SafeMOTION parameter group: Absolute position functions - Homing

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 243: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

6.4.18.4.2 Behavior

"Reference switch" mode correlates with the "Switch Gate", "Abs Switch" and "Limit Switch" homing modes on the SafeMOTION module.

Information:

If the reference switch input ("S_ReferenceSwitch" or "S_Control_RefSwitch") on the function block is not connected, the SafeMOTION module will switch to the FAIL SAFE state.
The only way to exit the FAIL SAFE state is to complete a power off/on cycle and modify the safety application!

Depending on the configuration, the SafeMOTION module will pass over the reference switch / limit switch several times.

Danger!

The reference switch / limit switch is part of the safety function and must therefore be accounted for in the risk analysis.

Use a debounced position switch suitable for safety applications!

The machine manufacturer is responsible for implementing a suitable switch!

After the homing command (i.e. positive edge of the "S_RequestHoming" or "S_Control_Homing" input), the SafeMOTION module uses the reference switch edge that matches the "Homing - Edge of reference switch" and "Homing - Trigger direction" as long as it is passed below the "Homing - Maximum trigger speed" (v_{HOME_MAX}).
If the reference switch is passed with a speed greater than the "Homing - Maximum trigger speed" (v_{HOME_MAX}), then the reference switch edge is ignored.

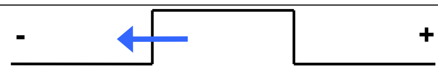
Configuration	Reference switch evaluation
Homing - Edge of reference switch = Negative Homing - Trigger direction = Negative	
Homing - Edge of reference switch = Positive Homing - Trigger direction = Negative	
Homing - Edge of reference switch = Negative Homing - Trigger direction = Positive	
Homing - Edge of reference switch = Positive Homing - Trigger direction = Positive	

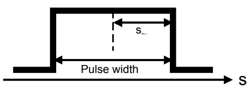
Table 244: Selecting the reference switch edge

Information:

After the homing command is given, the homing procedure must be completed within the configured "Homing - Monitoring time" (t_{HOME_M}). Otherwise, the SafeMOTION module will switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state.
The function block output "S_NotErrFUNC" or "S_Status_NotErrFunc" is reset and the torque and power to the drive are switched off, causing it to spin out!
An error will cause a synchronous axis to no longer be synchronous.

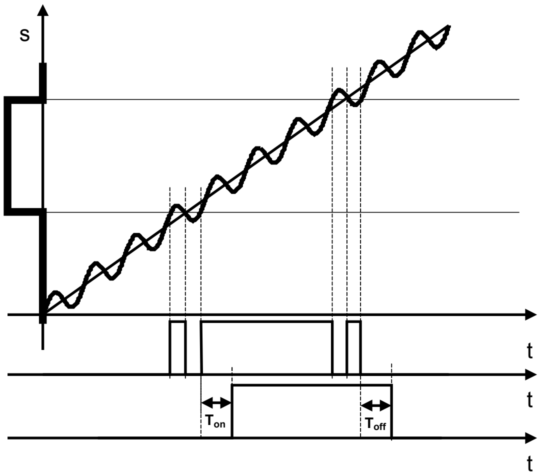
Danger!

The standstill "Standstill monitoring - Position tolerance" (s_{SM_T}) must be less than or equal to half the pulse width of the reference switch being used!



Danger!

The necessary filter (T_{on}, T_{off}) when reading the reference switch edges in SafeDESIGNER must be determined according to the control behavior during standstill.



Errors in the referenced absolute position due to the delay caused by the filter times must be taken into account!

6.4.18.4.2.1 ACOPOSmulti SafeMOTION SinCos

The home position is applied immediately after the reference switch edge is evaluated successfully.

6.4.18.4.2.2 ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION, ACOPOSmotor SafeMOTION

Homing - Enable reference pulse = Disabled

If the reference pulse is disabled, then the home position is applied immediately after the reference switch edge is evaluated successfully.

Homing - Enable reference pulse = Enabled

This mode is recommended when the positions of the ACOPOSmulti system and the SafeMOTION module must match exactly. Evaluation of the reference pulse compensates for the speed-dependent position difference by processing the two values at different times.

Information:

If "Homing - Enable reference pulse" is set to "Enabled", then a rotary EnDat 2.2 functional safety encoder must be used. The reference pulse is generated at each single-turn overflow.

If "Homing - Enable reference pulse" = Enabled, then the home position is not applied until the first valid reference pulse after the reference switch edge is reached.

After a valid reference switch edge is evaluated, the evaluation of the reference pulse is suppressed for the distance set by parameter "Homing - Blocking distance". The next reference pulse is only evaluated after this distance has been exceeded, at which point the home position is applied.

For a homing procedure to be valid, the direction of movement must not change between the time the reference switch edge occurs and the valid reference pulse; the "Homing - Maximum trigger speed" (v_{HOME_MAX}) limit must also not be exceeded.

Information:

If the direction of movement changes while searching for the reference pulse, the reference switch must be passed again.

Information:

If the "Homing - Maximum trigger speed" (v_{HOME_MAX}) speed limit is exceeded while searching for the reference pulse, the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.
The "S_NotErrFUNC" or "S_Status_NotErrFunc" output on the function block is reset, and the drive loses all torque/power and coasts to a stop!
In the event of an error, a synchronous axis will no longer be synchronous.

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

6.4.18.5 Mode Home offset / Home offset with correction (only available for SafeMOTION EnDat 2.2)

Information:

Modes "Home offset" and "Home offset with correction" are only available for ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!

6.4.18.5.1 Parameters

Group: Absolute position functions - Homing (previously *Homing*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Home position or home offset (previously *Home Position or Home Offset (units)*)	[units]	Home position or home offset	0	R 1.4
Homing - Mode (previously *Mode*)	Direct / Reference Switch / *Home Offset /* *Home Offset with Correction*	Selects the homing mode *Modes "Home offset" and "Home offset with correction" are only available for ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	Direct	R 1.4

Table 245: SafeMOTION parameter group: Absolute position functions - Homing

Group: Absolute position functions - SMP/SLP (previously *Safety Position Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SMP - Enable (previously *Safe Maximum Position*)	Enabled/ Disabled	Activates the SMP safety function from the configuration **Value** / **Description** Enabled: SMP is activated Disabled: SMP is deactivated	Disabled	R 1.4
SMP - Lower position limit (previously *Safe Lower Position Limit for SMP (units)*)	[units]	Lower position limit for the machine's full travel range	0	R 1.4
SMP - Upper position limit (previously *Safe Upper Position Limit for SMP (units)*)	[units]	Upper position limit for the machine's full travel range	0	R 1.4
SLP - Lower position limit (previously *Safe Lower Position Limit for SLP (units)*)	[units]	Lower position limit for the monitoring range	0	R 1.4
SLP - Upper position limit (previously *Safe Upper Position Limit for SLP (units)*)	[units]	Upper position limit for the monitoring range	0	R 1.4
SLP - Enable delay time (previously *Delay time to start SLP (us)*)	[µs]	Delay time between the SLP request and start of monitoring	0	R 1.4

Table 246: SafeMOTION parameter group: Absolute position functions - SMP/SLP

Danger!

The position limits being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement, a dangerous movement cannot occur in the event of a worst case scenario.

The dangerous movement must be determined by a risk analysis.

Information:

The following application rule must be observed:

$\mathbf{LIM_{SMP,NEG} \leq LIM_{SLP,NEG} \leq LIM_{SLP,POS} \leq LIM_{SMP,POS}}$

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

6.4.18.5.2 Behavior

If an absolute encoder is being used, then the machine reference can be established via an offset to the encoder position.
A homing procedure is not necessary.
The "Home offset" or "S_Control_RefSwitch" mode uses this offset directly, while "Home offset with correction" takes into account any encoder overflow that might occur in the permissible travel range.
The offset is configured in SafeDESIGNER using the "Homing - Home position or home offset" (s_{HOME}) parameter.

The "S_ReferenceSwitch" input is not evaluated.

Danger!

This homing mode can only be used for absolute encoders (single-turn encoders / multi-turn encoders / linear encoders). Using another encoder for this mode will cause the SafeMOTION module to switch to the FAIL SAFE state.
The Fail Safe state can only be exited by powering off/on and changing the safety application!

Information:

If the SMP and/or SLP safety functions are used, then their position window must be smaller than the safety-related encoder counting range.
If one of the two position windows is configured greater than the encoder counting range, the SafeMOTION module will switch to the FAIL SAFE state.
The only way to exit the FAIL SAFE state is to complete a power off/on cycle and modify the safety application!

For more information, see Safe encoder counting range (only applies to SafeMOTION EnDat 2.2).

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

Home offset

This mode is particularly suited for absolute encoders that provide unique position values over the entire travel range. The home offset allows the encoder position to accurately represent the machine position over the entire travel range.

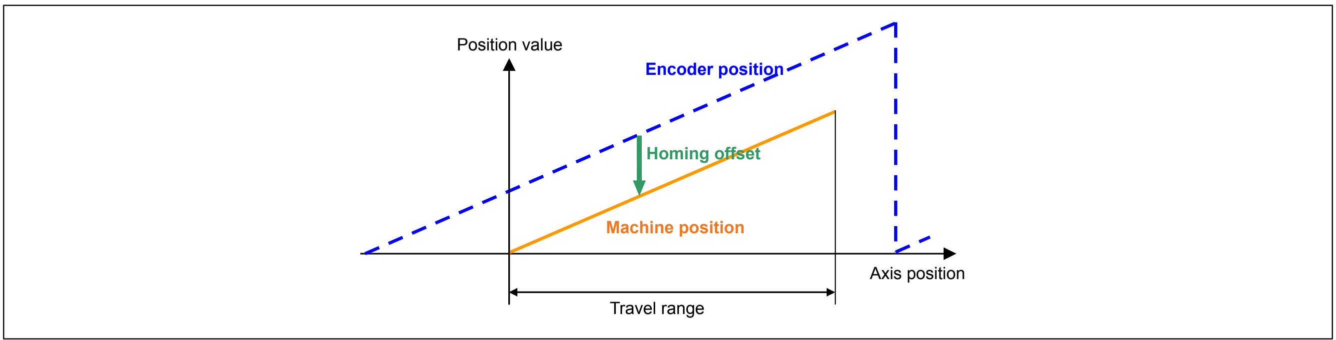


Figure 85: Homing mode - Home offset

The home offset can be determined by performing a calibration movement (e.g. homing with a reference switch).

Home offset with correction

In addition to setting the home offset, this homing mode checks to determine if the machine position is within the travel range defined by the SMP position limits. If this is not the case, the home offset in the safety-relevant encoder counting range is corrected.

Information:

The SMP safety function must be activated when using this mode. If SMP is deactivated, the SafeMOTION module switches to the FAIL SAFE state.
The only way to exit the FAIL SAFE state is to complete a power off/on cycle and modify the safety application!

Counting range correction is needed when using absolute encoders if the encoder returns a unique position value over the entire range of movement but an encoder overflow occurs within the range of movement. In this case, the home offset depends on whether the machine was calibrated at a position to the right or the left of the overflow point.

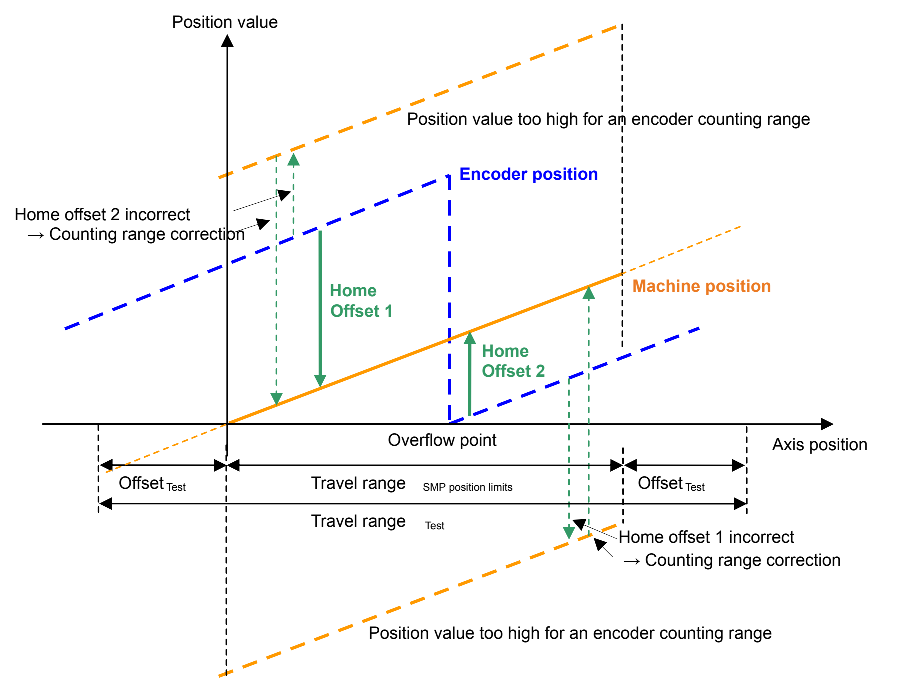


Figure 86: Homing method "Home offset with correction"

To the right of the overflow point, Home Offset 1 – which applies to the left side – would lead to an incorrect position value. To the left of the overflow point, Home Offset 2 – which applies to the right side – would lead to an incorrect position value. This can be compensated for with counting range correction.

Information:

Counting range correction only works if the encoder range is greater than or equal to the travel range!
Keep in mind that only the safety-relevant part of the encoder counting range is used.

6.4.19 Remanent Safe Position (RSP)

Information:

This functionality is only available with Safety Release R 1.9 or later and only for ACOPOSmulti SafeMOTION EnDat 2.2 inverter modules, ACOPOS P3 SafeMOTION servo drives and ACOPOSmotor SafeMOTION!

Information:

In order to be able to use the RSP safety function:

- **The axis must first be homed using the "Safe Homing" safety function. It does not matter which homing mode is used, but the respective safety notices must be observed.**
- **The STO and SOS safety functions must be used in accordance with the respective safety notices.**

Danger!

The RSP safety function is only permitted to be used if suitable technical measures are taken to prevent impermissible movement of the axis when it is switched off (e.g. motor holding brake, self-locking gear, etc.). The axis is not in the OPERATIONAL state and not permitted to be moved further than the lag tolerance (max. half the safe absolute encoder counting range - 2 * "Standstill monitoring - Position tolerance" (s_{SM_T})).

$$\Delta x_{Danger} > \frac{x_{SafeEncoderRange}}{2} - 2 \cdot x_{s_{SM\_T}}$$

It is the user's responsibility to take suitable technical measures to prevent excess movement.

Danger!

In order to perform testing and validation of the RSP safety function in the course of maintenance, the SafeMOTION module must have performed the RSP procedure.

Danger!

If the module is replaced, an initial homing procedure must be performed without the "S_SwitchHomingMode" or "S_Control_SwitchHomingMode" input activated.

Danger!

The RSP safety function is not suitable for continuously rotating axes. If an INT32 overflow of the safe position occurs during homing, homing using RSP will result in the FUNCTIONAL FAIL SAFE state.

6.4.19.1 Parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 247: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Absolute position functions - Homing (previously *Homing*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Enable RSP (Remanent safe position) *(previously Remanent safe position)*	*Enabled/ Disabled*	*Selects whether or not to use the remanent safe position* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*Disabled*	R 1.9

Table 248: SafeMOTION parameter group: Absolute position functions - Homing

6.4.19.2 Behavior

The RSP safety function can be activated or deactivated via the configuration.

With this safety function, after the safe position has been homed once to the machine position, the homed safe position does not have to be homed again after a power off/on cycle. It is only possible to store valid position data after a controlled standstill of the drive. The standstill must therefore be ensured. It must also be ensured that no power is supplied to the drive while the data is being saved so that it is not possible for the drive to move. These requirements are met when using the STO and SOS safety functions.

Information:

If the safety function RSP is used and the inputs "S_RequestHoming" or "S_Control_Homing", "S_SwitchHomingMode" or "S_Control_SwitchHomingMode", "S_RequestSTO" or "S_Control_STO" and "S_RequestSOS" or "S_Control_SOS" on the function block are not connected, the SafeMOTION module changes to state FAIL SAFE.

The only way to exit the FAIL SAFE state is to complete a power off/on cycle and modify the safety application!

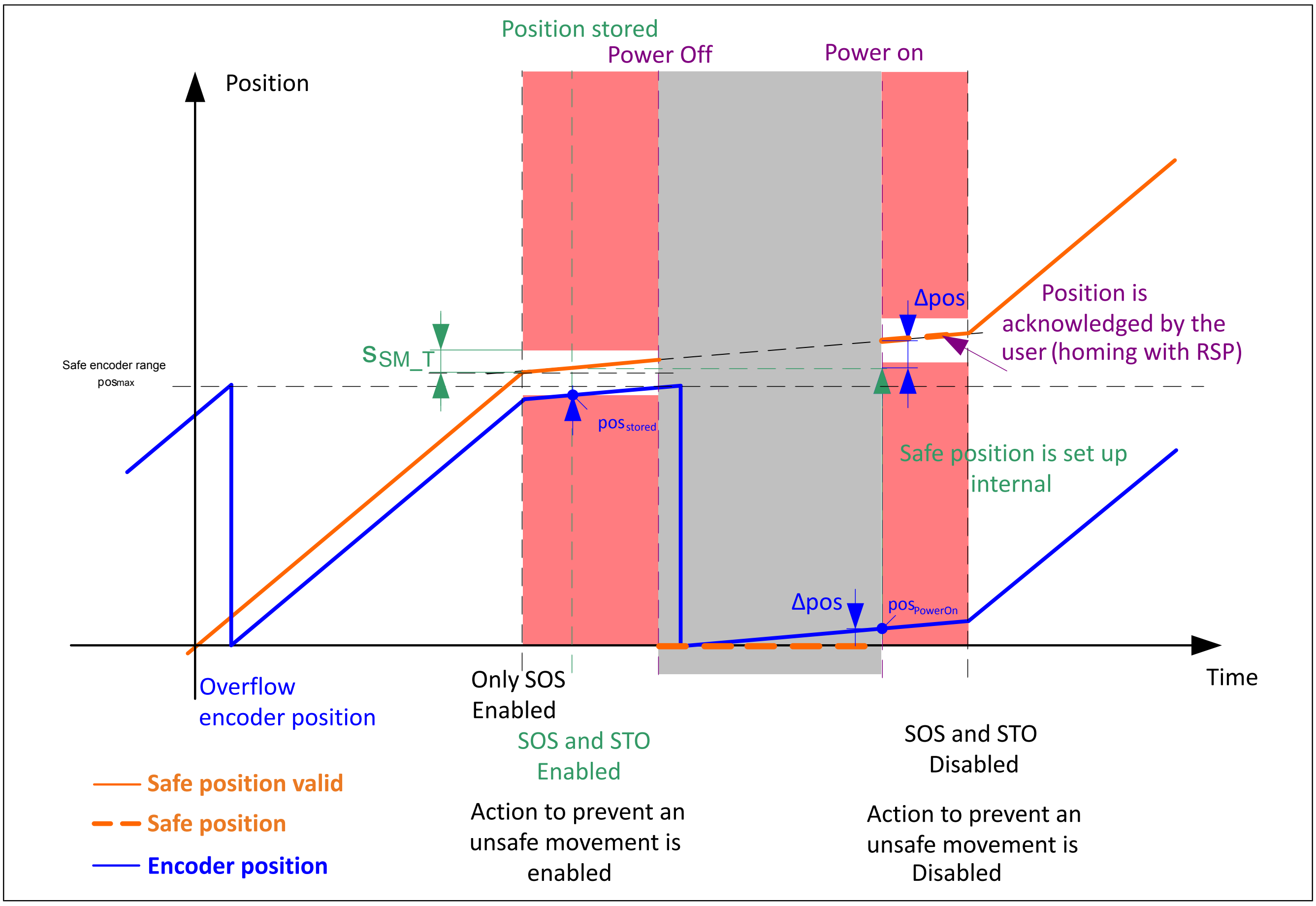


Figure 87: RSP safety function - Timing diagram with encoder overflow during power off

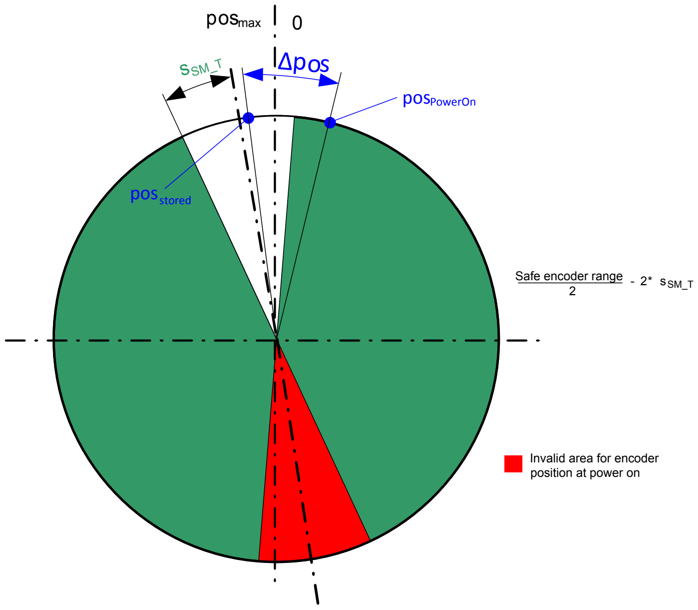


Figure 88: RSP safety function with respect to position for one revolution

6.4.19.2.1 RSP procedure

This safety function is not intended to provide a functional safe position following an uncontrolled machine failure. The following procedure is defined in order to achieve a controlled stop and enable the use of the remanent safe position:

1. Stop the axis in a controlled manner (valid safe position required).
2. Achieve the "S_RSPValid" or "S_Status_RSPValid" status
   This indicates whether the position has been stored and whether homing with RSP will be possible after powering off. The following conditions must be met in order to achieve the "S_RSPValid" or "S_Status_RSP-Valid" status:
   - STO and SOS are selected.
   - STO and SOS are active and in their safe state.
   - The axis has been homed and the safe position is valid ("S_SafePositionValid" or "S_Status_Hom-ing" = TRUE).
   - The store procedure is completed after the other conditions have been fulfilled.
3. Activate the technical measures required to prevent a dangerous movement. Execute a power off. A danger-ous movement is one that corresponds to half the safe encoder counting range minus two times "Standstill monitoring - Position tolerance" (s_{SM_T}).
   $$\Delta x_{Danger} > \frac{x_{SafeEncoderRange}}{2} - 2 \cdot xs_{SM\_T}$$
4. Confirm the restored position by homing with RSP after powering on.
   - To confirm the restored position after powering on, execute a homing command (i.e. positive edge of "S_RequestHoming" or "S_Control_Homing" input) with the "S_SwitchHomingMode" or "S_Con-trol_SwitchHomingMode" input enabled.

Information:

If the switching frequency of the "S_RSPValid" or "S_Status_RSPValid" status is too fast to complete the store procedure, a warning is entered in the Safety Logger. The SOS and STO safety functions are active in this state and are not deselected until the most recent store procedure is completed.

Information:

If the module is powered on after a controlled stop and homing is performed without the "S_Switch-HomingMode" or "S_Control_SwitchHomingMode" input enabled, or if an encoder error is detected, then homing with RSP will cause the module to switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

The drive loses all torque/power!

Information:

If an error or change in the configuration is detected when powering on after a controlled stop, then the position is not applied and homing with RSP will cause the module to switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

The drive loses all torque/power!

Information:

If the FUNCTIONAL FAIL SAFE error state occurs when homing with RSP, the axis must be homed again with the "S_SwitchHomingMode" or "S_Control_SwitchHomingMode" input disabled in order to obtain a new, valid safe position.

6.4.20 Safely Limited Position (SLP)

Information:

The "Safely Limited Position" safety function is only available with Safety Release 1.4 and later!

6.4.20.1 Parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 249: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 250: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Absolute position functions - SMP/SLP (previously *Safety Position Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SMP - Enable (previously *Safe Maximum Position*)	Enabled/ Disabled	Activates the SMP safety function from the configuration <table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>SMP is activated</td></tr><tr><td>Disabled</td><td>SMP is deactivated</td></tr></table>	Disabled	R 1.4
SMP - Lower position limit (previously *Safe Lower Position Limit for SMP (units)*)	[units]	Lower position limit for the machine's full travel range	0	R 1.4
SMP - Upper position limit (previously *Safe Upper Position Limit for SMP (units)*)	[units]	Upper position limit for the machine's full travel range	0	R 1.4
SLP - Lower position limit (previously *Safe Lower Position Limit for SLP (units)*)	[units]	Lower position limit for the monitoring range	0	R 1.4
SLP - Upper position limit (previously *Safe Upper Position Limit for SLP (units)*)	[units]	Upper position limit for the monitoring range	0	R 1.4
SLP - Enable delay time (previously *Delay time to start SLP (us)*)	[µs]	Delay time between the SLP request and start of monitoring	0	R 1.4

Table 251: SafeMOTION parameter group: Absolute position functions - SMP/SLP

Danger!

The position limits being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement, a dangerous movement cannot occur in the event of a worst case scenario.

The dangerous movement must be determined by a risk analysis.

Information:

The following application rule must be observed:

$\mathbf{LIM_{SMP,NEG} \leq LIM_{SLP,NEG} \leq LIM_{SLP,POS} \leq LIM_{SMP,POS}}$

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

6.4.20.2 Behavior

The purpose of the SLP safety function is to monitor a specified position window.

The "SLP - Lower position limit" (s_{SMP_LL}) and "SLP - Upper position limit" (s_{SMP_UL}) parameters can be used to configure the limits of the monitoring range.

Setting input "S_RequestSLP" or "S_Control_SLP" to SAFEFALSE requests safety function SLP.

After the configurable time "SLP - Enable delay time" (t_{SLP_ED}) has expired, the position window is monitored.

The "S_SafetyActiveSLP" or "S_Status_SLP" status bit will be set to SAFETRUE if no errors occur while monitoring is active.

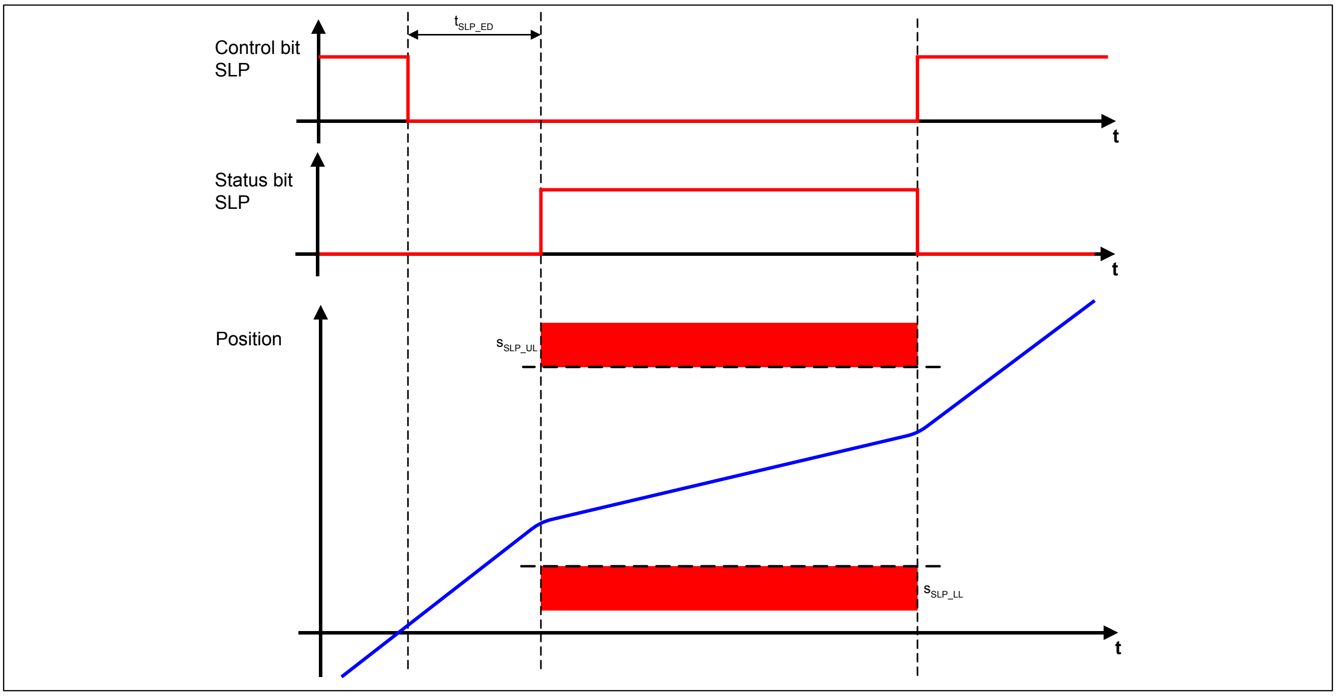


Figure 89: Safely Limited Position (SLP)

Information:

The axis must be homed successfully before using the SLP safety function.
If a homing procedure is not completed successfully or the "S_SafePositionValid" or "S_Status_Homing" status changes, then the request for the SLP safety function causes the module to switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state.
The drive loses all torque/power and coasts to a stop! In the event of an error, a synchronous axis will no longer be synchronous.
Output "S_NotErrFUNC" or "S_Status_NotErrFunc" of the function block is reset!

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

To minimize the residual distance when the position window is exceeded, a position-dependent speed limit is monitored in addition to the position.

Danger!

In the worst case, the monitored position window can be violated while the axis is coasting to a stop. This must be taken into account when defining the limits!

When the position limit is approached, the monitored speed limit is calculated in such a way that the drive will come to a full stop before the positioning limit is reached using the configured "Ramp monitoring - Speed deceleration limit" (a_{RM_L}) parameter.

Permitted speed in the direction of the upper position limit:

$$v_{LIM,POS} = \sqrt{2\left(LIM_{SLP,POS} - s\right) \cdot a}$$

Permitted speed in the direction of the lower position limit:

$$v_{LIM,NEG} = \sqrt{2\left(s - LIM_{SLP,NEG}\right) \cdot a}$$

The position-dependent speed limit is illustrated in the following figure.

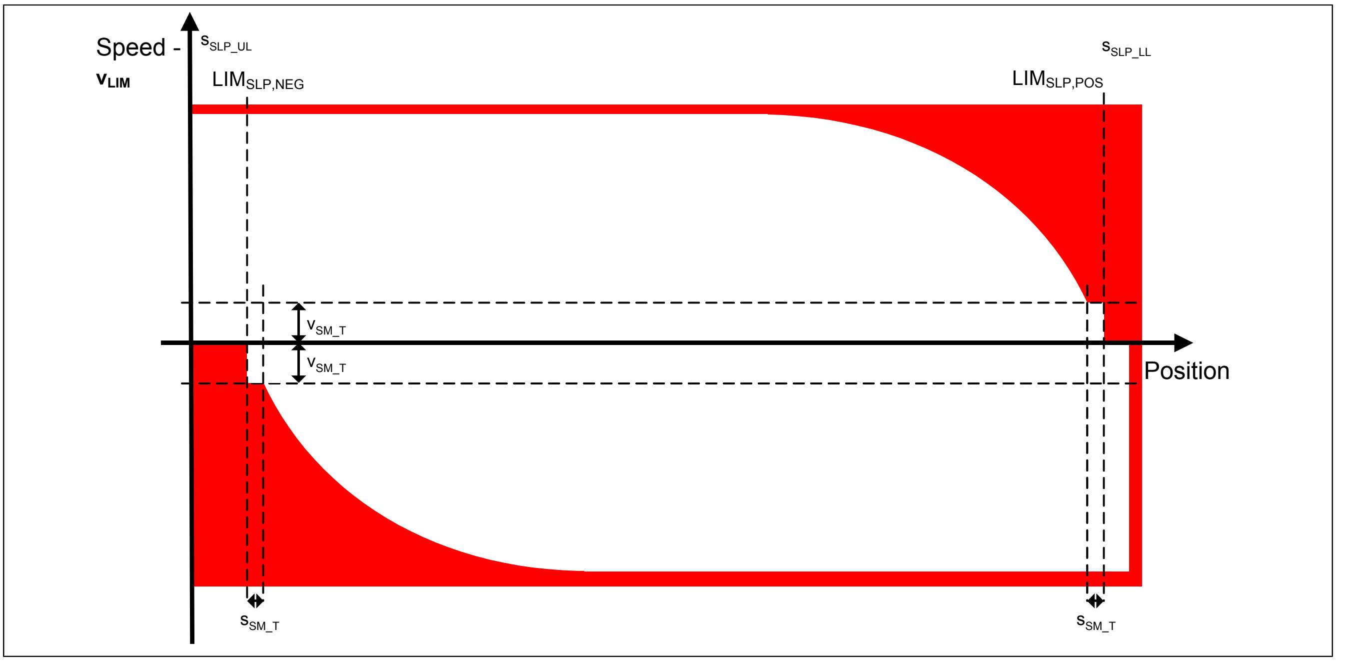


Figure 90: Position-dependent speed window

Danger!

If the position window or the position-dependent speed limit is violated while the SLP safety function is activated or the "S_SafePositionValid" or "S_Status_Homing" status is lost, then the module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.
The "S_NotErrFUNC" or "S_Status_NotErrFunc" output on the function block is reset, and the drive loses all torque/power and coasts to a stop!
In the event of an error, a synchronous axis will no longer be synchronous.

Danger!

If the SLP safety function is used in the safety application, then it must be tested when commissioning the machine by selecting and deselecting it!
The test should contain at least one violation of each position limit. The error response must be tested accordingly!

6.4.21 Safe Maximum Position (SMP)

Information:

The "Safe Maximum Position" safety function is only available with Safety Release 1.4 and later!

6.4.21.1 Parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 252: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 253: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Absolute position functions - SMP/SLP (previously *Safety Position Limits*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SMP - Enable

(previously Safe Maximum Position)</td><td>Enabled/
Disabled</td><td>Activates the SMP safety function from the configuration<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>SMP is activated</td></tr><tr><td>Disabled</td><td>SMP is deactivated</td></tr></table></td><td>Disabled</td><td>R 1.4</td></tr>
<tr><td>SMP - Lower position limit

(previously Safe Lower Position Limit for SMP (units))</td><td>[units]</td><td>Lower position limit for the machine's full travel range</td><td>0</td><td>R 1.4</td></tr>
<tr><td>SMP - Upper position limit

(previously Safe Upper Position Limit for SMP (units))</td><td>[units]</td><td>Upper position limit for the machine's full travel range</td><td>0</td><td>R 1.4</td></tr>
<tr><td>SLP - Lower position limit

(previously Safe Lower Position Limit for SLP (units))</td><td>[units]</td><td>Lower position limit for the monitoring range</td><td>0</td><td>R 1.4</td></tr>
<tr><td>SLP - Upper position limit

(previously Safe Upper Position Limit for SLP (units))</td><td>[units]</td><td>Upper position limit for the monitoring range</td><td>0</td><td>R 1.4</td></tr>
<tr><td>SLP - Enable delay time

(previously Delay time to start SLP (us))</td><td>[µs]</td><td>Delay time between the SLP request and start of monitoring</td><td>0</td><td>R 1.4</td></tr>
</table>

Table 254: SafeMOTION parameter group: Absolute position functions - SMP/SLP

Danger!

The position limits being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement, a dangerous movement cannot occur in the event of a worst case scenario.

The dangerous movement must be determined by a risk analysis.

Information:

The following application rule must be observed:

$$LIM_{SMP,NEG} \le LIM_{SLP,NEG} \le LIM_{SLP,POS} \le LIM_{SMP,POS}$$

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

6.4.21.2 Behavior

The difference between SMP and SLP is that SMP cannot be actively requested. It is either enabled or disabled by the configuration.

When enabled, the current position is constantly monitored against a defined position window.

The "SMP - Lower position limit" (s_{SMP_LL}) and "SMP - Upper position limit" (s_{SMP_UL}) parameters can be used to configure the limits of the monitoring range.

The SMP safety function only works with homed axes since it requires a safe absolute position.
If SMP is configured, a 15-minute timeout period begins when pulse disabling is activated. The homing procedure must take place during this time.
When homing is completed and if there were no errors during monitoring, the "S_SafetyActiveSMP" or "S_Status_SMP" status bit is set to SAFETRUE.

Information:

The axis must be homed successfully before using the "Safe Maximum Position" safety function.
If the homing procedure does not complete successfully within 15 minutes after pulse disabling is activated, the "SafePositionValid" or "S_Status_Homing" status bit is lost for an already homed axis or there is a violation of the position window or position-dependent speed limit, then the SafeMOTION module switches to the FUNCTIONAL FAIL SAFE error state.
The "S_NotErrFUNC" or "S_Status_NotErrFunc" output on the function block is reset, and the drive loses all torque/power and coasts to a stop! In the event of an error, a synchronous axis will no longer be synchronous.

As with the SLP safety function, the SMP safety function also monitors a position-dependent speed limit in addition to the position in order to minimize the remaining distance if the position window is exceeded.
See the description of safety function "Safely Limited Position (SLP)".

Danger!

In the worst case, the monitored position window can be violated while the axis is coasting to a stop. This must be taken into account when defining the limits!
If the position window has been exceeded, then movement is only possible in the direction of the position window after the FUNCTIONAL FAIL SAFE state has been acknowledged.
Attempting to move beyond the standstill tolerance in the unsafe direction (i.e. away from the position window) will cause the SafeMOTION module to switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Danger!

If the SMP safety function is used in the safety application, then it must be tested when commissioning the machine! The test should contain at least one violation of each position limit. The error response must be tested accordingly!

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

6.4.22 Safe Brake Test (SBT)

Information:

This functionality is available with Safety Release R1.7 or later and for ACOPOSmulti SafeMOTION SinCos inverter modules!

Information:

This functionality is available for ACOPOS P3 SafeMOTION servo drives in hardware upgrade 1.10.2.x or later!

The function is approved starting with a defined hardware revision; for older hardware revisions, using the safety function leads directly to state FAIL SAFE. The necessary hardware revision is noted in the servo drive data sheet.

Danger!

The safe torque can only be used for synchronous motors with undefined poles ($L_d = L_q$)!

Danger!

Use of the SBT safety function requires fault exclusion for encoder shaft breakage or that safe encoder connection monitoring is active.

This requires either a safe encoder mounting, or the application must meet the necessary requirements for safe encoder shaft breakage monitoring!

Information:

Determining the added value of using this function depends on the requirements of the brake being used and is your responsibility as user.

Danger!

The SBT safety function is not a typical safety function!

It is only used to test an engaged holding brake by applying a configurable stator current for a certain period of time.

The test is carried out at the specified safety level and with the specified precision.

Danger!

Overheating of the motor can change the torque constant k_T and therefore negatively influence the safe torque.

Ensure that the motor has been sized so as to prevent overheating.

Danger!

The accuracy of the safe current only applies up to the continuous current of the performance class used. It is not permitted to use a safety function that should monitor or detect a current above the continuous current of the performance class used.

6.4.22.1 Parameters

Group: Advanced functions - SBT (previously *Safe Brake Test*) (only available for ACOPOSmulti SafeMOTION SinCos and ACOPOS P3 SafeMOTION (hardware upgrade 1.10.2.x or later)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBT - Threshold (previously *Safe Brake Test threshold (uA)*)	[µA]	Threshold value for the stator current that must be exceeded during the brake test	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - External load (previously *Safe Brake Test external load (uA)*)	[µA]	External load	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Position tolerance (previously *Safe Brake Test position tolerance (units)*)	[units]	Position tolerance	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Maximum torque duration (previously *Safe Brake Test maximum torque duration (us)*)	[µs]	Duration of the test for which the maximum torque must be present	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Test interval (previously *Safe Brake Test interval (s)*)	[s]	Retry interval for the safe brake test	28800	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Enable delay time (previously *Delay Time to start SBT (us)*)	[µs]	Delay time between the SBT request and activation of the safety function	0	R 1.7 SinCos R 1.10 ACOPOS P3

Table 255: SafeMOTION parameter group: Advanced functions - SBT

The parameters are checked when the SafeMOTION module is started up. If a parameter is invalid, the module switches to an error state. In addition, a corresponding error entry is made in the logger.

If an external load is not configured, the following guidelines apply:

- Threshold value "SBT - Threshold" i_{SBT_TRESH} must be greater than the accuracy of the safe current of the module used.

The following additional guidelines apply for an external load:

- External load "SBT - External load" is not permitted to be greater than threshold value "SBT - Threshold".
- External load "SBT - External load" must be greater than accuracy of the safe current $i_{\varepsilon SBT}$ of the module used.
- External load "SBT - External load" i_{SBT_LOAD} is known and approximately constant as permissible external load torque $T_{LOAD} \in [T_{LOAD\_MIN}, T_{LOAD\_MAX}]$.

6.4.22.2 Behavior

The SBT safety function allows an engaged brake to be tested by applying a configurable stator current for a specified period of time.

An external load can be taken into account if it is configured in SafeDESIGNER using parameter "SBT - External load" (i_{SBT_LOAD}). In this case, the safe test torque is reduced by the external load after the test.

The brake test must be performed by the standard application; the SafeMOTION module monitors this process.

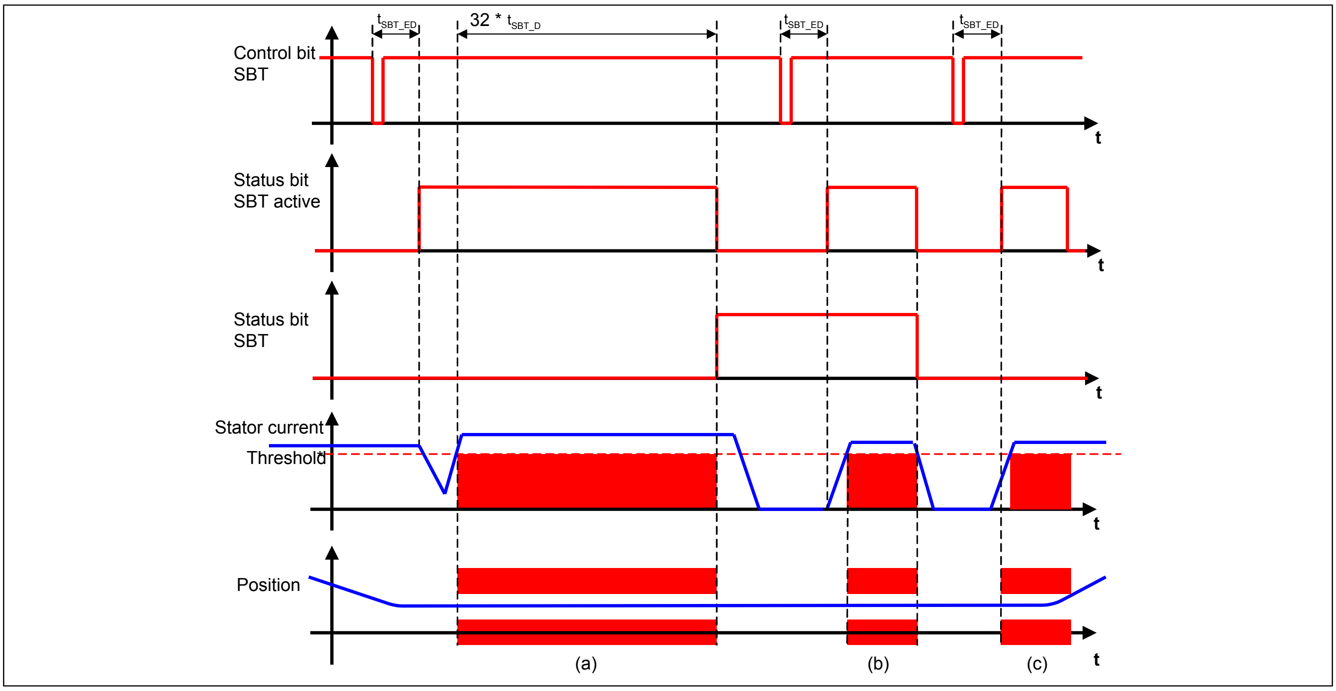


Figure 91: Safe Brake Test (SBT)

A corresponding mode is available in PLCopen function block MC_BR_BrakeControl.

Function block SF_SafeMC_SBT_BR_V1_00 is available in SafeDESIGNER for requesting the safe brake test.

A negative edge on control bit "SBT" starts the SBT safe brake test; status bit "SBT_Active" is set simultaneously.

As soon as the brake test has been completed successfully, status bit "SBT" is set and "SBT_Active" is reset simultaneously.

The request for the safe brake test is edge-controlled. Resetting the "SBT" control bit to SAFETRUE has no effect on the rest of the process.

Immediately after the safe brake test is requested, the actual brake test is delayed by the "SBT - Enable delay time" (t_{SBT_ED}) counter. This time allows the standard application to react to the status of the request bit and bring the axis to a standstill if necessary.

The safe brake test is handled differently depending on whether or not an external load is present at the time of the test.

6.4.22.3 Safe brake test without external load

If no external load is configured in SafeDESIGNER, monitoring of the load on the brake starts immediately after the "SBT - Enable delay time" (t_{SBT_ED}) has expired. The safe brake output is simultaneously switched to 0 V.

6.4.22.4 Safe brake test with configured external load

After the "SBT - Enable delay time" (t_{SBT_ED}) has expired, the value of the stator current required to hold the load is immediately checked against the expected value. This means that at the time of the test the amount of stator current must be within the relatively tolerated measurement error of external load torque ε_{SBT_LOAD} = ±6.25% of expected value "SBT - External load" (i_{SBT_LOAD}). If this is the case, the safe brake output is switched to 0 V and the stator current must undershoot the safe test torque.

Because an external load is already exerting torque on the engaged brake, the amount of torque that the drive must apply to test the brake is reduced. The safe test bench current is reduced by the amount of the external load.

The parameter current of external load "SBT - External Load" i_{SBT_LOAD} can only be used if the measured external load, taking into account accuracy of the safe current for SBT $i_{\varepsilon SBT}$ and accuracy of the motor torque characteristic curve $_{T\_MC}$, is within the relatively tolerated measurement error of external load value ε_{SBT_LOAD}.

$$\varepsilon_{SBT\_LOAD} > \frac{T_M^{-1}(T_{LOAD\_MAX})\frac{1}{(1-\varepsilon_{T\_MC})} + i_{\varepsilon SBT}}{i_{SBT\_LOAD}} - 1 \bigwedge \varepsilon_{SBT\_LOAD} > 1 - \frac{T_{MC}^{-1}(T_{LOAD\_MIN}) - i_{\varepsilon SBT}}{i_{SBT\_LOAD}}$$

If the condition listed is not met, the availability of function SBT with constant load cannot be ensured.

Danger!

This function cannot be used with a variable load.

Danger!

In order for the measurement of the external load to provide valid results, the load must be held by the drive at the time of measurement. This means that the brake is not permitted to be engaged!

6.4.22.5 Brake load monitoring

From this point on, the safe brake test procedure is the same with or without a configured external load.

The MC_BR_BrakeControl function block in the standard application ensures that the desired amount of torque is applied to the brake. The stator current is increased in a ramped form until it reaches the setpoint. From the time the stator current exceeds the threshold value "SBT - Threshold" (i_{SBT_TRESH}), the safe position is stored and a position window is calculated.
The size of the position window can be configured using the "SBT - Position tolerance" (s_{SBT_L}) parameter. The "SBT" status bit is set to "Active" simultaneously and monitoring is started.

The "SBT - Maximum torque duration" (t_{SBT_D}) parameter defines the minimum duration of the test, during which the test torque must be applied. The total duration of monitoring is 32x this time (see Fig. 91 "Safe Brake Test (SBT)" on page 410 (a)).
During this time, the test current is not permitted to fall below the threshold value; the safe position is not permitted to leave the position window.

If the stator current falls below its threshold value during active monitoring (see Fig. 91 "Safe Brake Test (SBT)" on page 410 (b)) or the position tolerance window is violated (see Fig. 91 "Safe Brake Test (SBT)" on page 410 (c)), then the safe brake test becomes invalid and is aborted. If the status bit "SBT" is already set, it is reset. In addition, a corresponding entry is made in the Safety Logger.

After a successful brake test, the "SBT" status bit is set and a configurable timer is started (Parameter "SBT - Test interval" (t_{SBT_TI})). After this timer has expired, the "SBT" status bit is reset to indicate that a new brake test is required.

6.4.22.6 Accuracy of SBT

The following accuracies must be taken into account when configuring SBT.

Accuracy of the safe current

For valid general information about current measurement and its accuracy, see 6.2.5.1 "Accuracy of the safe current" on page 315.

The threshold value must be taken into account by accuracy of the safe current for SBT $i_{\varepsilon SBT}$. This alone guarantees valid execution of the brake test, even with the maximum permissible measurement error of the current transformers.

Accuracy of the test principle

With SBT, the torque-forming current can be distorted due to faulty commutation. The test principle used by SBT guarantees that a measurement error of ε_{SBT_TEST} = 2% is not exceeded.

Accuracy of the motor torque characteristic curve

With SBT, the safe current and not the safe motor torque is monitored. The functional relationship between motor torque T and torque-forming current i_S is given by the motor torque characteristic curve. When converting the SBT parameters from motor torque to torque-forming current, accuracy of the motor torque characteristic ε_{T_MC}, which can result in a reduction in motor torque or an increase in the required safe current, must be taken into account.

$$i_S = T_{MC}^{-1}(T)\frac{1}{(1-\varepsilon_{T\_MC})}$$

6.4.22.7 Calculating the current threshold value to be configured

Safe test torque of the holding brake T_{SBT_RISK} is obtained from the risk analysis. The test torque must be converted to required test current i_{SBT_RISK} using motor torque characteristic curve $T_{MC}^{-1}(T)$ (see 6.4.6 "Safe Torque" on page 348).

$$i_{SBT\_RISK} = T_{MC}^{-1}(T_{SBT\_RISK})$$

If a maximum permissible external load torque of $T_{LOAD} \in [T_{LOAD\_MIN}, T_{LOAD\_MAX}]$ is always present when performing the safe brake test, the required test torque can be reduced by minimum permissible external load torque T_{LOAD_MIN} with "Safe brake test without external load".

$$i_{SBT\_RISK} = T_{MC}^{-1}(T_{SBT\_RISK} - T_{LOAD\_MIN})$$

SBT monitors that safe test current of the holding brake i_{SBT_RISK} always undershoots threshold value of the stator current i_{SBT_TRESH} when the test is performed. When configuring the threshold value of the stator current, test current i_{SBT_RISK} must be increased by accuracy of the motor torque characteristic ε_{T_MC}, measurement error of the SBT test principle ε_{SBT_TEST} and accuracy of the safe current for SBT $i_{\varepsilon SBT}$.

$$i_{SBT\_TRESH} = i_{SBT\_RISK} * \frac{(1+\varepsilon_{SBT\_TEST})}{(1-\varepsilon_{T\_MC})} + i_{\varepsilon SBT}$$

ε_{SBT_TEST}	Measurement error of the SBT test principle 2%
ε_{T_MC}	Accuracy of the motor torque characteristic curve (see motor data sheet)
$i_{\varepsilon SBT}$	Accuracy of the safe current for SBT

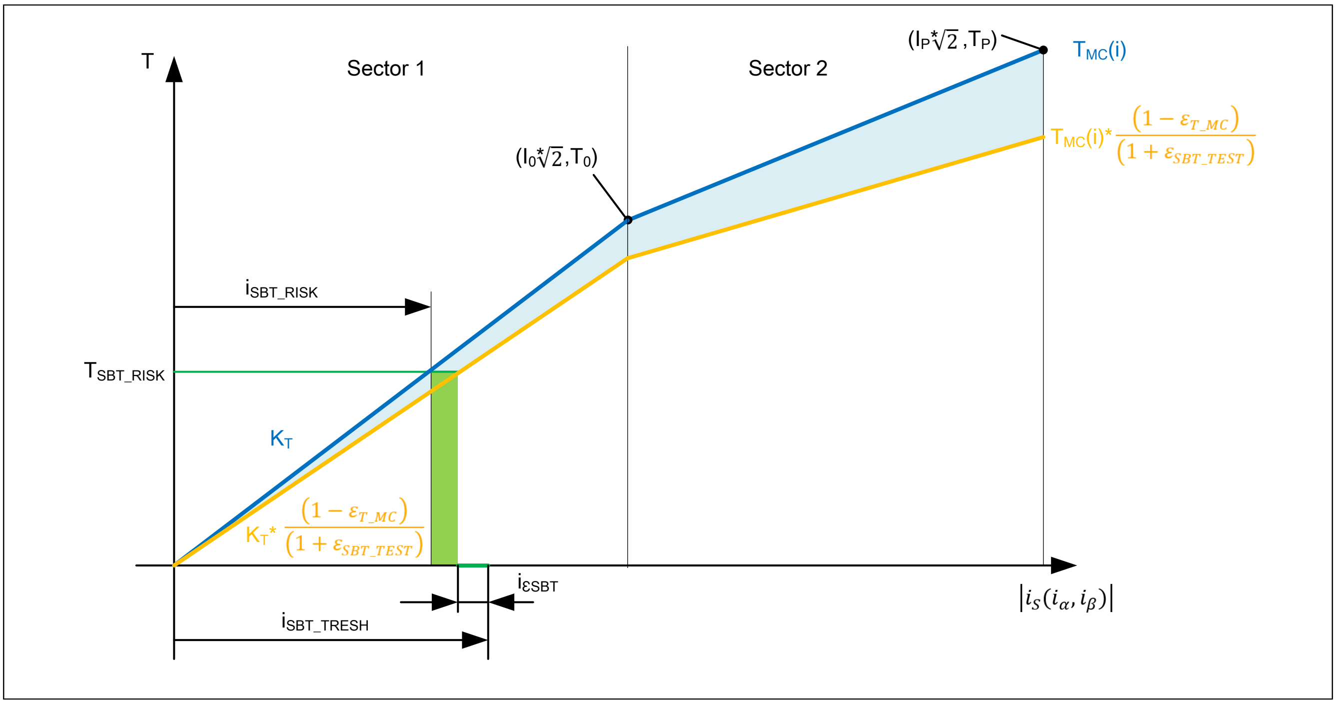


Figure 92: Effect of SBT accuracies on the stator current threshold

Danger!

If the accuracies of function SBT are not taken into account, a current value (or torque) that is too low can be monitored under certain circumstances. In this case, it cannot be guaranteed that the intended safe current is correctly monitored, and the result of the safety function is invalid!

Information:

The values for the test current and duration of the test depend on the application and the brake being used; it is the user's responsibility to set these values appropriately.

6.4.22.8 Calculating the standard test torque of the holding brake

During functional testing of the holding brake torque, the engaged holding brake is loaded by the standard application with standard test torque of the holding brake (parameter ID 1268) T_{BT}. The standard test torque is specified using function block MC_BR_BrakeControl (TestTorque) or a parameter ID (parameter ID 1268). Threshold value i_{SBT_TRESH} must be exceeded at a permissible external load torque of $T_{LOAD} \in [T_{LOAD\_MIN}, T_{LOAD\_MAX}]$.

To ensure the availability of safety function SBT, standard test torque T_{BT} must be sufficiently increased in accordance with accuracy of the motor torque characteristic ε_{T_MC} and accuracy of the safe current for SBT $i_{\varepsilon SBT}$.

$$T_{BT} = T_{MC}(i_{SBT\_TRESH}) + T_{MC}\left(\frac{1}{(1-\varepsilon_{T\_MC})} T_{MC}^{-1}(T_{LOAD\_MAX}) + i_{\varepsilon SBT}\right)$$

6.4.22.9 Permissible safe test torque of the holding brake

Functional testing of the holding brake torque is not permitted to exceed motor holding brake nominal torque (parameter ID 43) T_{BRAKE_RATED}. For this purpose, permissible safe test torque of the holding brake $T_{SBT\_RISK\_PERMIT}$ must be determined.

$$T_{SBT\_RISK\_PERMIT} = \frac{(1-\varepsilon_{T\_MC})}{(1+\varepsilon_{SBT\_TEST})} \cdot T_{MC}\left(T_{MC}^{-1}\left(T_{BRAKE\_RATED} - T_{MC}\left(\frac{1}{(1-\varepsilon_{T\_MC})} T_{MC}^{-1}(T_{LOAD\_MAX}) + i_{\varepsilon SBT}\right)\right) - i_{\varepsilon SBT}\right) + T_{LOAD\_MIN}$$

If safe test torque of the holding brake (from the risk analysis) T_{SBT_RISK} is greater than permissible safe test torque of the holding brake $T_{SBT\_RISK\_PERMIT}$, motor holding brake nominal torque (parameter ID 43) T_{BRAKE_RATED} is too small and a more powerful brake must be used (holding brake with higher nominal torque).

6.4.23 Safely Limited Torque, SLT

Information:

This functionality is only available for ACOPOS P3 SafeMOTION in hardware upgrade 1.10.2.x or later!

The function is approved starting with a defined hardware revision; for older hardware revisions, using the safety function leads directly to state FAIL SAFE. The necessary hardware revision is noted in the servo drive data sheet.

6.4.23.1 Parameter

Parameter	Unit	Description	Default value	Starting in Safety Release
SLT - Torque limit	[mNm]	Torque limitation monitored during activation of SLT	0	R 1.10
SLT - Enable delay time	[µs]	Delay time between the SLT request and activation of the safety function	0	R 1.10

Table 256: SafeMOTION parameter group: Advanced functions - SLT

Parameter	Unit	Description	Default value	Starting in Safety Release
Motor - Number of pole pairs (hardware upgrade 1.10.2.x and later)	-	Number of pole pairs on the rotor circumference	1	1.10
Motor - Direction*) (hardware upgrade 1.10.2.x and later)	Standard / Inverse	Direction of rotation of the motor	Standard	1.10
Motor - Stator resistance (hardware upgrade 1.10.2.x and later)	mOhm	Ohmic stator resistance measured between two connections (phase - phase) of the motor	0	1.10
Motor - Stator inductance (hardware upgrade 1.10.2.x and later)	µH	Stator inductance measured between two connections (phase - phase) of the motor	0	1.10
Motor - Torque constant (hardware upgrade 1.10.2.x and later)	µNm / A	Torque constant of the motor	0	1.10
Motor - Rated speed (hardware upgrade 1.10.2.x and later)	units/s	Nominal speed of the motor	0	1.10
Motor - Stall current (hardware upgrade 1.10.2.x and later)	mA	Stall current of the motor	0	1.10
Motor - Rated current (hardware upgrade 1.10.2.x and later)	mA	Nominal current of the motor	0	1.10
Motor - Peak current (hardware upgrade 1.10.2.x and later)	mA	Peak current of the motor	0	1.10
Motor - Stall torque (hardware upgrade 1.10.2.x and later)	mNm	Stall torque of the motor that is output when the stall current is applied	0	1.10
Motor - Peak torque (hardware upgrade 1.10.2.x and later)	mNm	Peak torque of the motor that is briefly output when the peak current is applied	0	1.10
Motor - Moment of inertia (optional) (hardware upgrade 1.10.2.x and later)	µkgm²	Mass moment of inertia of the motor. Consists of the sum of the inertias of the rotor, encoder and holding brake.	0	1.10
Motor - External moment of inertia (optional) (hardware upgrade 1.10.2.x and later)	µkgm²	External mass moment of inertia, depends on the total external load	0	1.10

Table 257: SafeMOTION parameter group: General settings - Motor

*) The direction of rotation of the motor is not related to the counting direction of the speed ("EUS - Counting direction"), i.e. the direction of rotation of the motor can be changed explicitly in the non-safe application and must therefore also be taken into account in SafeDESIGNER.

6.4.23.2 Behavior

Safety function SLT is used to monitor the electric motor torque for compliance with a specified maximum limit.

Information:

The SLT safety function requires safe motor current evaluation. If the function is programmed in the safety application and if an error is detected in the safe motor current evaluation, then the SafeMC module immediately switches to the FUNCTIONAL FAIL SAFE state after the function block is activated!

Parameter "SLT - Torque Limit" T_{SLT_LIM} can be used to set the limit value for the electrical motor torque for the positive and negative directions of movement.

Setting the "S_Control_SLT" input to SAFEFALSE requests the SLT safety function.

After configurable delay time "SLT - Enable delay time" t_{SLT_ED} has elapsed, the configured motor torque limit is monitored.

The purpose of delay time t_{SLT_ED} is to compensate for the different runtimes of the standard and safety applications. If the delay time is set to 0, then the motor torque limit will be monitored right after the request is made for the safety function.

The standard (non-safety-related) application must implement a closed-loop control appropriate for the level of danger to decelerate the movement and ensure adherence to the respective motor torque limit.

The "S_Status_SLT" status bit will be set to SAFETRUE if no errors occur while monitoring is active.

Information:

The SLT safety function can be activated in parallel with other safety functions. This makes it possible, for example, to reduce the expected residual distances in the worst-case calculation.

Information:

The SLT safety function has achieved its safe state when the safety function is selected and no violation is detected during monitoring of the motor torque limit of the drive.

The respective bit is set when the functional safe state has been achieved.

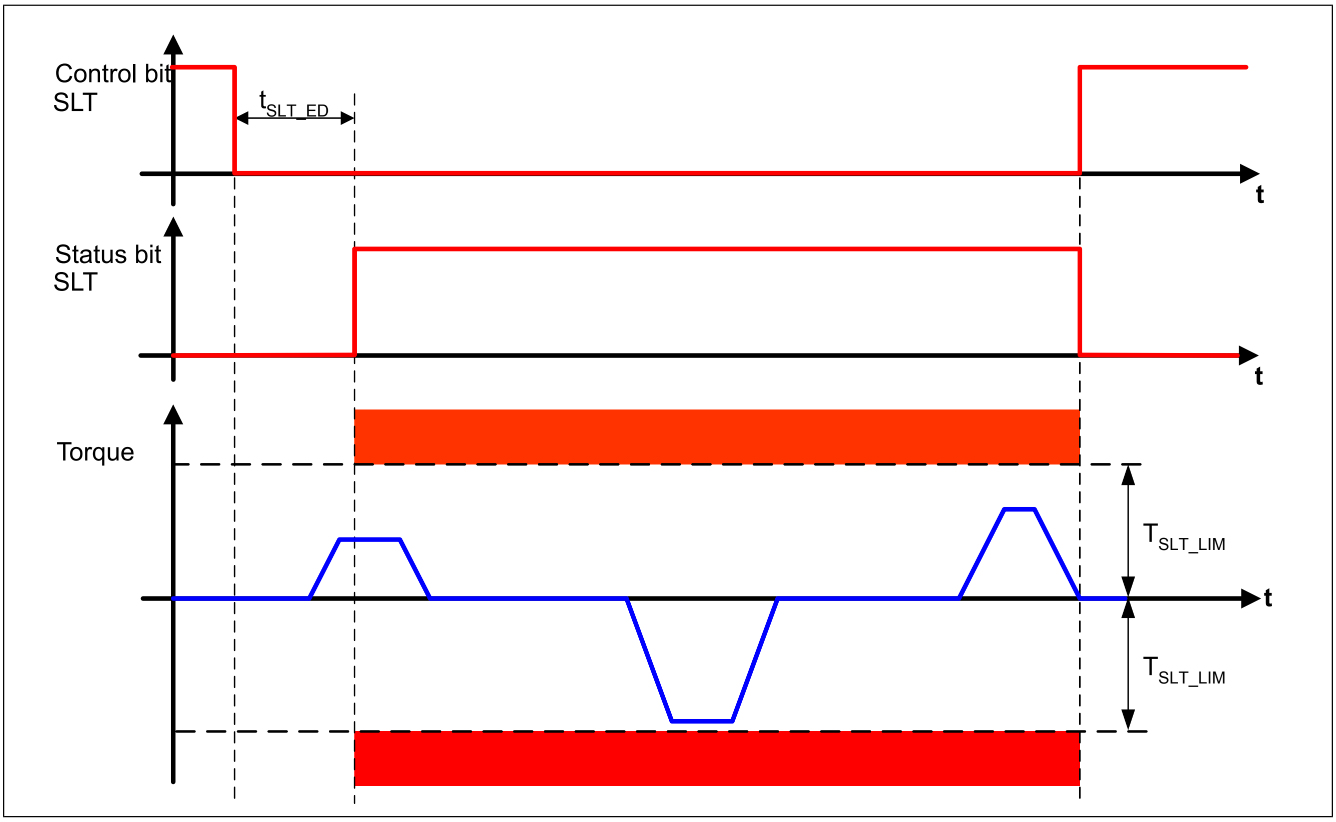


Figure 93: Safely Limited Torque, SLT

Danger!

When monitoring the safely limited motor torque, in the event of error a change in angular momentum that corresponds to the electrical dynamic behavior of the motor can occur during the error response time. The limitation of the torque cannot be ensured within the error response time. The dangerous change in angular momentum must be determined in a risk analysis and is not permitted to result in any hazard!

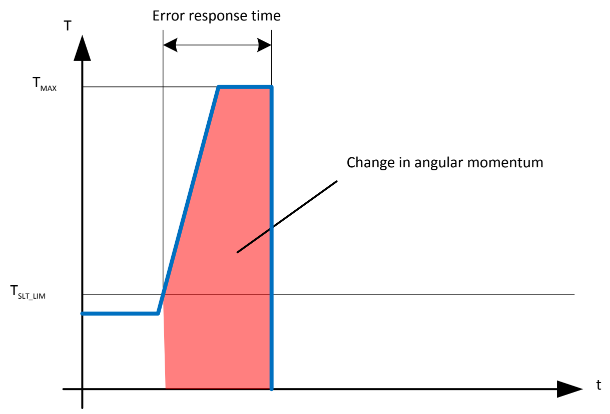


Figure 94: Possible change of the angular momentum in the event of an error

Danger!

If a motor torque limit is violated, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state. The drive loses all torque/power and coasts to a stop! In the event of an error, a synchronous axis will no longer be synchronous. Output "S_NotErrFUNC" or "S_Status_NotErrFunc" of the function block is reset!

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

Danger!

If the safety function is used in the safety application, then it must be tested when commissioning the machine by selecting and deselecting it!

The test should contain at least one violation of each configured limit. The error response must be tested accordingly!

Danger!

The safe torque can only be used for synchronous motors with undefined poles ($L_d = L_q$)!

Danger!

Overheating of the motor can change torque constant K_T and therefore negatively influence the safe torque. Ensure that the motor has been sized so as to prevent overheating.

Danger!

If the accuracy of the safe current is not taken into account, a current value or torque that is too low can be monitored under certain circumstances. In this case, it cannot be guaranteed that the target torque will be reached or that the torque limit will be correctly monitored; the result of the safety function is therefore invalid!

The accuracy of the safe current only applies up to the continuous current of the performance class used. It is not permitted to use a safety function that should monitor or detect a current above the continuous current of the performance class used.

6.4.23.3 Accuracy of SLT

The following accuracies must be taken into account when configuring SLT.

For valid general information about current measurement and its accuracy, see 6.2.5.1 "Accuracy of the safe current" on page 315.

In order to calculate the motor torque, the accuracy of the safe current must be taken into account. This alone guarantees valid execution of safety function SLT, even with the maximum measuring error of the current transformers.

6.4.23.4 Calculating the electrical motor torque limit to be configured

In the configuration of parameter "SLT - Torque limit" T_{SLT_LIM}, safe electrical motor torque limit (from the risk analysis) T_{SLR_RISK} and corresponding current i_{SLT_RISK} must be calculated from the motor torque characteristic curve (see 6.4.6 "Safe Torque" on page 348); the accuracy of the safe current must also be taken into account. i_{SLT_RISK} must then be calculated back to a torque.

i_{SLT_RISK} is calculated according to 6.4.6 "Safe Torque" on page 348 as follows:

$$i_{SLT\_RISK} = T_{MC}^{-1}\left(T_{SLT\_RISK}\right)$$

Accuracy of the safe current SLT $i_{\varepsilon SLT}$ of the power classes of the servo drive must then be subtracted.

$$i_{SLT\_LIM} = i_{SLT\_RISK} - i_{\varepsilon SLT}$$

Transforming it back into a torque value results in "SLT - Torque Limit" to be configured for the safety function.

$$T_{SLT\_LIM} = T_{MC}\left(i_{SLT\_LIM}\right)$$

6.4.24 Safe machine options

6.4.24.1 Parameters

Group: Safe machine options (previously *Additional Parameter*)

Parameter	Unit	Description	Default value	Used starting in Safety Release
Safe machine options - Enable (previously *Activate Safe Machine Options*)	Enabled/ Disabled	Activates/Deactivates the "Safe machine options" safety function	Disabled	R 1.9

Table 258: SafeMOTION parameter group: Safe machine options

6.4.24.2 Behavior

The primary method for configuring a SafeMOTION module is to set the parameters in SafeDESIGNER and transfer them to the SafeLOGIC controller along with the safety application. From there, they are transferred to the SafeMOTION module. These parameters are labeled as "Default parameters" and require the use of SafeDESIGNER.

To allow them to be configured without using SafeDESIGNER, Safety Release 1.9 introduces the "Safe machine options" safety function.

"Safe machine options" is used to modify the parameters of the SafeMOTION module from the standard application.

The safe machine options are transferred from the standard application to the SafeLOGIC controller as a data block, and stored there permanently. The SafeMOTION module needs to restart in order to transfer the safe machine options, and in some cases this occurs automatically. This means that the parameters cannot be changed at runtime.

Information:

It is only possible to use the "Safe machine options" safety function:

- **On SG4 target systems**
- **With SafeLOGIC X20SL8100**
- **With Automation Runtime AR 4.06 or later**

Danger!

Changing the module's parameters using the "Safe machine options" is equivalent to modifying the safety application.

Acknowledgment and unlock requests must be handled by authorized personnel only. Automated acknowledgment and unlocking logic is not permitted. This requirement must be listed in a code review document.

The danger warnings in the "Maintenance scenarios" chapter of the technical data sheets for X20SL8xxx and X20SLXxxx series devices must also be observed. Functions are only permitted to be executed by personnel with proper authorization. Access to the respective visualization components must be limited to the authorized group of personnel using suitable means.

Personnel authorized to acknowledge data are responsible for verifying the data that is to be acknowledged (project CRC, project save date, content of machine options, etc.).

Local personnel must be informed whenever access takes place. The user must implement suitable measures to ensure that remote access is not possible without notifying local personnel.

Proper functionality must be verified by comprehensive functional testing. All test procedures and results must be documented. Testing must be able to identify any data mismatches between the HMI application and safety application. Comprehensive functional testing must be carried out to ensure proper functionality after the standard application is created or modified as well as after any changes are made to Automation Runtime.

The following description assumes that the "Safe machine options - Enable" module parameter has been set to "Enabled".

6.4.24.3 Transferring to the SafeLOGIC controller

The safeDownloadData() function block from the AsSafety library is used to transfer the safe machine options. For information regarding the use of this function block, see library AsSafety in Automation Help.

As mentioned above, the safe machine options are transferred as a data block. This data block contains a 64-byte array, variables for version identification and the safety parameters themselves. The format of the safe machine options depends on the Safety Release of the module type (see "6.4.24.6 "Data structure of safe machine options (Safety Release 1.9 and later)" on page 420").

In Safety Release 1.9 and later, a structure type is provided in library "SafeMC" for SafeMOTION modules. Please note the minimum required ACP10 version (see 5.3 "System requirements" on page 267).

Since the entire safe machine option data block is always transferred, the "enable bits" can be used to enable each parameter. Each bit corresponds to a parameter. For parameters whose "enable bit" is set, the default value (as configured in SafeDESIGNER) is overwritten by the value in the structure. For parameters whose "enable bit" is not set, the default value (as configured in SafeDESIGNER) is retained.

Information:

When the safe machine options are transferred to the SafeLOGIC controller, their ranges are not checked. It is therefore possible to set values that are outside the valid ranges. To prevent malfunctions, the range check is performed on the SafeMOTION module. If faulty parameter settings are detected, the SafeMOTION module enters the FAIL SAFE state during startup.

Information:

The application that handles the transfer must be developed in accordance with currently applicable regulations. Manipulation of parameters by unauthorized personnel is not permitted and must be prevented.

After parameters have been changed, a complete functional test must be performed in order to ensure that the behavior of the safety application meets specifications.

Information:

The format of the safe machine options is backward compatible.

6.4.24.4 Transferring to the SafeMOTION module

Transfer always takes place in state PREOPERATIONAL. If the safe machine options on the SafeLOGIC controller are by a download, they are transferred automatically to the respective SafeMOTION module. On the SafeMOTION module, each of the "enable bits" is evaluated; for any that are set, the default value of the corresponding parameter is overwritten by the value of the safe machine option. Each parameter has a valid range of values which may depend on the values of other parameters (SMS/SLS speed limits, etc.). This range of values is checked on the SafeMOTION module.

If faulty parameter settings are detected, the SafeMOTION module enters the FAIL SAFE state and a corresponding error is entered in the Safety Logger.

6.4.24.5 Missing safe machine options

If the "Safe machine options" safety function is activated, then the safe machine options must be found on the SafeLOGIC controller. If there is no data block for the respective SafeMOTION module, then the SafeMOTION module does not switch to the OPERATIONAL state and can therefore not be used.

Downloading safe machine options to the SafeLOGIC controller triggers an automatic restart of the SafeMOTION module, and the safe machine options are transferred from the SafeLOGIC controller to the SafeMOTION module.

6.4.24.6 Data structure of safe machine options (Safety Release 1.9 and later)

Data structure of safe machine options:

- ACOPOSmulti SafeMOTION EnDat 2.2 (Safety Release 1.9 and later)
- ACOPOSmotor SafeMOTION (Safety Release 1.10 and later)
- ACOPOSmulti SafeMOTION SinCos (Safety Release 1.9 and later)

Parameters that are set using a drop-down menu in SafeDESIGNER have a specific range of values, which is listed in the following table for each parameter.

Data type	EnDat 2.2		SinCos		Name	Constant / Name in SafeDESIGNER
	Index	Byte offset	Index	Byte offset		
USINT[64]		0 .. 63		0 .. 63	EnableBits	**SafeMOTION EnDat 2.2**: SMC_EnDat22_R19_OptsIndex_enum **SafeMOTION SinCos**: SMC_SinCos_R19_OptsIndex_enum
UINT		64 .. 65		64 .. 65	StructInfoAxisTypeID	Axis type ID of the SafeMOTION module
UINT		66 .. 67		66 .. 67	StructInfoSize	Size of the parameter structure
UDINT		68 .. 71		68 .. 71	StructInfoVersion	StructInfoVersion
USINT	**0**	72	**0**	72	EncoderType	EUS - Encoder type **SafeMOTION EnDat 2.2**: Encoder used = 1 Encoder not used = 0 **SafeMOTION SinCos**: Rotary encoder = 0 Linear encoder = 1 Encoder not used = 2
USINT	**1**	73	**1**	73	FuncFailSafeEncErrMode	FFS - Caused by encoder error Always = 0 Only if safety functions requiring an encoder are enabled = 1
USINT	**2**	74	**2**	74	*AlignmentByte1*	*Alignment placeholder. Do not use!*
USINT	**3**	75	**3**	75	*AlignmentByte2*	*Alignment placeholder. Do not use!*
UDINT	Not used		**4**	76 .. 79	NrOfSignalperiods	EUS - Number of signal periods
DINT	**4**	76 .. 79	**5**	80 .. 83	ScaleRevo	EUS - Count of physical reference system
DINT	**5**	80 .. 83	**6**	84 .. 87	ScaleUnits	EUS - Units per count of physical reference system
DINT	**6**	84 .. 87	**7**	88 .. 91	ScaleDirection	EUS - Counting direction Default = 0 Inverse = 1
DINT	**7**	88 .. 91	**8**	92 .. 95	ScaleLength	EUS - Length of physical reference system for linear encoder
DINT	**8**	92 .. 95	**9**	96 .. 99	ScaleNormSpeedMax	EUS - Maximum speed to normalize speed range
DINT	**9**	96 .. 99	**10**	100 .. 103	AccelerationMax	EUS - Encoder acceleration limit
DINT	**10**	100 .. 103	**11**	104 .. 107	HomingPos	Homing - Home position or home offset
DINT	**11**	104 .. 107	**12**	108 .. 111	HomingMaxSpeed	Homing - Maximum trigger speed
DINT	**12**	108 .. 111	**13**	112 .. 115	HomingTMon	Homing - Monitoring time
USINT	**13**	112	**14**	116	HomingMode	Homing - Mode Direct = 0 Reference switch = 1 Home offset = 2 (only SafeMOTION EnDat 2.2) Home offset with correction = 3 (only SafeMOTION EnDat 2.2)
USINT	**14**	113	**15**	117	HomingRefSwEdge	Homing - Edge of reference switch Negative = 0 Positive = 1
USINT	**15**	114	**16**	118	HomingTriggerDir	Homing - Trigger direction Negative = 0 Positive = 1
USINT	**16**	115	Not used		HomingRefPulse	Homing - Enable reference pulse Disabled = 0 Enabled = 1
USINT	**17**	116	Not used		HomingRemanentSafePos	Homing - Enable RSP (Remanent safe position) Disabled = 0 Enabled = 1
USINT	**18**	117	Not used		HomingRefPBlock	Homing - Blocking distance
USINT	**19**	118	**17**	119	*AlignmentByte3*	*Alignment placeholder. Do not use!*
USINT	**20**	119	Not used		*AlignmentByte4*	*Alignment placeholder. Do not use!*
DINT	**21**	120 .. 123	**18**	120 .. 123	DecelerationRamp	Ramp monitoring - Speed deceleration limit
USINT	**22**	124	**19**	124	UseSMS	SMS - Enable Enabled = 0 Disabled = 1
USINT	**23**	125	**20**	125	UseAutoResetAtStartup	Automatic reset on start - Enable Enabled = 0 Disabled = 1
USINT	**24**	126	**21**	126	SelectSTO1channel	STO1 - Channel Highside = 0 Lowside = 1
USINT	**25**	127	**22**	127	UseRampMonitoringSS1	SS1 - Ramp monitoring - Enable Disabled = 0 Enabled = 1

Table 259: Data structure of safe machine options, Safety Release 1.9 and later (SMC_EnDat22_R19_Opts_typ, SMC_SinCos_R19_Opts_typ)

Data type	EnDat 2.2		SinCos		Name	Constant / Name in SafeDESIGNER
	Index	Byte offset	Index	Byte offset		
USINT	**26**	128	**23**	128	UseRampMonitoringSS2	SS2 - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**27**	129	**24**	129	UseRampMonitoringSLS	SLS - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**28**	130	**25**	130	UseEarlyLimitMon	Early limit monitoring - Enable Disabled = 0 Enabled = 1
USINT	**29**	131	**26**	131	UseSMP	SMP - Enable Enabled = 0 Disabled = 1
USINT	**30**	132	**27**	132	UseEncPosMon	Encoder monitoring - Position error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**31**	133	**28**	133	UseEncSpeedMon	Encoder monitoring - Speed error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**32**	134	**29**	134	UseSetPosAliveTest	Encoder monitoring - Position setpoint alive testing (SPA) - Enable Disabled = 0 Enabled = 1
USINT	**33**	135	**30**	135	FuncFailSafeMode	FFS - Mode STO = 0 STO1 and STO with time delay = 1
DINT	**34**	136 .. 139	**31**	136 .. 139	FuncFailSafeDelaySTO	FFS - STO Enable delay time
DINT	**35**	140 .. 143	**32**	140 .. 143	FuncFailSafeDelayBrk	FFS - Delay time until the brake engages
DINT	**36**	144 .. 147	**33**	144 .. 147	AccelerationLimPos	SLA - Acceleration limit in positive direction
DINT	**37**	148 .. 151	**34**	148 .. 151	DecelerationLimPos	SLA - Deceleration limit in positive direction
DINT	**38**	152 .. 155	**35**	152 .. 155	AccelerationLimNeg	SLA - Acceleration limit in negative direction
DINT	**39**	156 .. 159	**36**	156 .. 159	DecelerationLimNeg	SLA - Deceleration limit in negative direction
DINT	**40**	160 .. 163	**37**	160 .. 163	SpeedLimitSMS	SMS - Speed limit
DINT	**41**	164 .. 167	**38**	164 .. 167	SpeedLimitSLS1	SLS1 - Speed limit
DINT	**42**	168 .. 171	**39**	168 .. 171	SpeedLimitSLS2	SLS2 - Speed limit
DINT	**43**	172 .. 175	**40**	172 .. 175	SpeedLimitSLS3	SLS3 - Speed limit
DINT	**44**	176 .. 179	**41**	176 .. 179	SpeedLimitSLS4	SLS4 - Speed limit
DINT	**45**	180 .. 183	**42**	180 .. 183	PosLimitMinSMP	SMP - Lower position limit
DINT	**46**	184 .. 187	**43**	184 .. 187	PosLimitMaxSMP	SMP - Upper position limit
DINT	**47**	188 .. 191	**44**	188 .. 191	PosLimitMinSLP	SLP - Lower position limit
DINT	**48**	192 .. 195	**45**	192 .. 195	PosLimitMaxSLP	SLP - Upper position limit
DINT	**49**	196 .. 199	**46**	196 .. 199	SpeedTolerance	Standstill monitoring - Speed tolerance
DINT	**50**	200 .. 203	**47**	200 .. 203	PositionTolerance	Standstill monitoring - Position tolerance
DINT	**51**	204 .. 207	**48**	204 .. 207	SliPositionWindow	SLI - Position limit
DINT	**52**	208 .. 211	**49**	208 .. 211	SliToffDelay	SLI - Disable delay time
DINT	**53**	212 .. 215	**50**	212 .. 215	RampMonTimeSS1	SS1 - Ramp monitoring - Enable
DINT	**54**	216 .. 219	**51**	216 .. 219	RampMonTimeSS2	SS2 - Ramp monitoring - Enable
DINT	**55**	220 .. 223	**52**	220 .. 223	RampMonTimeSLS1	SLS1 - Ramp monitoring - Time
DINT	**56**	224 .. 227	**53**	224 .. 227	RampMonTimeSLS2	SLS2 - Ramp monitoring - Time
DINT	**57**	228 .. 231	**54**	228 .. 231	RampMonTimeSLS3	SLS3 - Ramp monitoring - Time
DINT	**58**	232 .. 235	**55**	232 .. 235	RampMonTimeSLS4	SLS4 - Ramp monitoring - Time
DINT	**59**	236 .. 239	**56**	236 .. 239	DelayRampMonitoring	Ramp monitoring - Enable delay time
DINT	**60**	240 .. 243	**57**	240 .. 243	DelaySDI	SDI - Enable delay time
DINT	**61**	244 .. 247	**58**	244 .. 247	DelaySBC	SBC - Enable delay time
DINT	**62**	248 .. 251	**59**	248 .. 251	DelaySLP	SLP - Enable delay time
DINT	Not used		**60**	252 .. 255	DelaySBT	SBT - Enable delay time
DINT	**63**	252 .. 255	**61**	256 .. 259	DelaySLA	SLA - Enable delay time
DINT	**64**	256 .. 259	**62**	260 .. 263	EarlyLimitMonTime	Early limit monitoring - Time
DINT	**65**	260 .. 263	**63**	264 .. 267	EncMonitoringPosTol	Encoder monitoring - Position error tolerance
DINT	**66**	264 .. 267	**64**	268 .. 271	EncMonitoringSpeedTol	Encoder monitoring - Speed error tolerance
DINT	Not used		**65**	272 .. 275	SbtInterval	SBT - Test interval
DINT	Not used		**66**	276 .. 279	SbtTreshold	SBT - Threshold
DINT	Not used		**67**	280 .. 283	SbtExternalLoad	SBT - External load
DINT	Not used		**68**	284 .. 287	SbtDuration	SBT - Maximum torque duration
DINT	Not used		**69**	288 .. 291	SbtPositionTolerance	SBT - Position tolerance

Table 259: Data structure of safe machine options, Safety Release 1.9 and later (SMC_EnDat22_R19_Opts_typ, SMC_SinCos_R19_Opts_typ)

- ACOPOSmulti SafeMOTION EnDat 2.2 (Safety Release 1.10 and later, hardware upgrade 1.10.2x and later)
- ACOPOSmotor SafeMOTION (Safety Release 1.10 and later, hardware upgrade 1.10.2.x and later)
- ACOPOSmulti SafeMOTION SinCos (Safety Release 1.10 and later, hardware upgrade 1.10.2.x and later)

Parameters that are set using a drop-down menu in SafeDESIGNER have a specific range of values, which is listed in the following table for each parameter.

Data type	EnDat 2.2		SinCos		Name	Constant / Name in SafeDESIGNER
	Index	Byte offset	Index	Byte offset		
USINT[64]		0 .. 63		0 .. 63	EnableBits	**SafeMOTION EnDat 2.2**: SMC_EnDat22_R19_OptsIndex_enum **SafeMOTION SinCos**: SMC_SinCos_R19_OptsIndex_enum
UINT		64 .. 65		64 .. 65	StructInfoAxisTypeID	Axis type ID of the SafeMOTION module
UINT		66 .. 67		66 .. 67	StructInfoSize	Size of the parameter structure
UDINT		68 .. 71		68 .. 71	StructInfoVersion	StructInfoVersion
USINT	**0**	72	**0**	72	EncoderType	EUS - Encoder type **SafeMOTION EnDat 2.2**: Encoder used = 1 Encoder not used = 0 **SafeMOTION SinCos**: Rotary encoder = 0 Linear encoder = 1 Encoder not used = 2
USINT	**1**	73	**1**	73	FuncFailSafeEncErrMode	FFS - Caused by encoder error Always = 0 Only if safety functions requiring an encoder are enabled = 1
USINT	**2**	74	**2**	74	ModeBM	BM - Mode Off = 0 Prev. enabled SF = 1 Prev. enabled and configured SF = 2 Configured SF = 3
USINT	**3**	75	**3**	75	UseSEM	Encoder monitoring - Safe Encoder Mounting Approved by user = 0 From motor data record = 1
UDINT	Not used		**4**	76 .. 79	NrOfSignalperiods	EUS - Number of signal periods
DINT	**4**	76 .. 79	**5**	80 .. 83	ScaleRevo	EUS - Count of physical reference system
DINT	**5**	80 .. 83	**6**	84 .. 87	ScaleUnits	EUS - Units per count of physical reference system
DINT	**6**	84 .. 87	**7**	88 .. 91	ScaleDirection	EUS - Counting direction Default = 0 Inverse = 1
DINT	**7**	88 .. 91	**8**	92 .. 95	ScaleLength	EUS - Length of physical reference system for linear encoder
DINT	**8**	92 .. 95	**9**	96 .. 99	ScaleNormSpeedMax	EUS - Maximum speed to normalize speed range
DINT	**9**	96 .. 99	**10**	100 .. 103	AccelerationMax	EUS - Encoder acceleration limit
DINT	**10**	100 .. 103	**11**	104 .. 107	HomingPos	Homing - Home position or home offset
DINT	**11**	104 .. 107	**12**	108 .. 111	HomingMaxSpeed	Homing - Maximum trigger speed
DINT	**12**	108 .. 111	**13**	112 .. 115	HomingTMon	Homing - Monitoring time
USINT	**13**	112	**14**	116	HomingMode	Homing - Mode Direct = 0 Reference switch = 1 Home offset = 2 (only SafeMOTION EnDat 2.2) Home offset with correction = 3 (only SafeMOTION EnDat 2.2)
USINT	**14**	113	**15**	117	HomingRefSwEdge	Homing - Edge of reference switch Negative = 0 Positive = 1
USINT	**15**	114	**16**	118	HomingTriggerDir	Homing - Trigger direction Negative = 0 Positive = 1
USINT	**16**	115	Not used		HomingRefPulse	Homing - Enable reference pulse Disabled = 0 Enabled = 1
USINT	**17**	116	Not used		HomingRemanentSafePos	Homing - Enable RSP (Remanent safe position) Disabled = 0 Enabled = 1
USINT	**18**	117	Not used		HomingRefPBlock	Homing - Blocking distance
USINT	**19**	118	**17**	119	*AlignmentByte3*	*Alignment placeholder. Do not use!*
USINT	**20**	119	Not used		*AlignmentByte4*	*Alignment placeholder. Do not use!*
DINT	**21**	120 .. 123	**18**	120 .. 123	DecelerationRamp	Ramp monitoring - Speed deceleration limit
USINT	**22**	124	**19**	124	UseSMS	SMS - Enable Enabled = 0 Disabled = 1
USINT	**23**	125	**20**	125	UseAutoResetAtStartup	Automatic reset on start - Enable Enabled = 0 Disabled = 1
USINT	**24**	126	**21**	126	SelectSTO1channel	STO1 - Channel Highside = 0 Lowside = 1
USINT	**25**	127	**22**	127	UseRampMonitoringSS1	SS1 - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**26**	128	**23**	128	UseRampMonitoringSS2	SS2 - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**27**	129	**24**	129	UseRampMonitoringSLS	SLS - Ramp monitoring - Enable Disabled = 0 Enabled = 1

Table 260: Data structure of safe machine options, Safety Release 1.10 and later (SMC_EnDat22_V02_Opts_typ, SMC_SinCos_V02_Opts_typ)

Data type	EnDat 2.2		SinCos		Name	Constant / Name in SafeDESIGNER
	Index	Byte offset	Index	Byte offset		
USINT	**28**	130	**25**	130	UseEarlyLimitMon	Early limit monitoring - Enable Disabled = 0 Enabled = 1
USINT	**29**	131	**26**	131	UseSMP	SMP - Enable Enabled = 0 Disabled = 1
USINT	**30**	132	**27**	132	UseEncPosMon	Encoder monitoring - Position error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**31**	133	**28**	133	UseEncSpeedMon	Encoder monitoring - Speed error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**32**	134	**29**	134	UseSetPosAliveTest	Encoder monitoring - Position setpoint alive testing (SPA) - Enable Disabled = 0 Enabled = 1
USINT	**33**	135	**30**	135	FuncFailSafeMode	FFS - Mode STO = 0 STO1 and STO with time delay = 1
DINT	**34**	136 .. 139	**31**	136 .. 139	FuncFailSafeDelaySTO	FFS - STO Enable delay time
DINT	**35**	140 .. 143	**32**	140 .. 143	FuncFailSafeDelayBrk	FFS - Delay time until the brake engages
DINT	**36**	144 .. 147	**33**	144 .. 147	AccelerationLimPos	SLA - Acceleration limit in positive direction
DINT	**37**	148 .. 151	**34**	148 .. 151	DecelerationLimPos	SLA - Deceleration limit in positive direction
DINT	**38**	152 .. 155	**35**	152 .. 155	AccelerationLimNeg	SLA - Acceleration limit in negative direction
DINT	**39**	156 .. 159	**36**	156 .. 159	DecelerationLimNeg	SLA - Deceleration limit in negative direction
DINT	**40**	160 .. 163	**37**	160 .. 163	SpeedLimitSMS	SMS - Speed limit
DINT	**41**	164 .. 167	**38**	164 .. 167	SpeedLimitSLS1	SLS1 - Speed limit
DINT	**42**	168 .. 171	**39**	168 .. 171	SpeedLimitSLS2	SLS2 - Speed limit
DINT	**43**	172 .. 175	**40**	172 .. 175	SpeedLimitSLS3	SLS3 - Speed limit
DINT	**44**	176 .. 179	**41**	176 .. 179	SpeedLimitSLS4	SLS4 - Speed limit
DINT	**45**	180 .. 183	**42**	180 .. 183	PosLimitMinSMP	SMP - Lower position limit
DINT	**46**	184 .. 187	**43**	184 .. 187	PosLimitMaxSMP	SMP - Upper position limit
DINT	**47**	188 .. 191	**44**	188 .. 191	PosLimitMinSLP	SLP - Lower position limit
DINT	**48**	192 .. 195	**45**	192 .. 195	PosLimitMaxSLP	SLP - Upper position limit
DINT	**49**	196 .. 199	**46**	196 .. 199	SpeedTolerance	Standstill monitoring - Speed tolerance
DINT	**50**	200 .. 203	**47**	200 .. 203	PositionTolerance	Standstill monitoring - Position tolerance
DINT	**51**	204 .. 207	**48**	204 .. 207	SliPositionWindow	SLI - Position limit
DINT	**52**	208 .. 211	**49**	208 .. 211	SliToffDelay	SLI - Disable delay time
DINT	**53**	212 .. 215	**50**	212 .. 215	RampMonTimeSS1	SS1 - Ramp monitoring - Enable
DINT	**54**	216 .. 219	**51**	216 .. 219	RampMonTimeSS2	SS2 - Ramp monitoring - Enable
DINT	**55**	220 .. 223	**52**	220 .. 223	RampMonTimeSLS1	SLS1 - Ramp monitoring - Time
DINT	**56**	224 .. 227	**53**	224 .. 227	RampMonTimeSLS2	SLS2 - Ramp monitoring - Time
DINT	**57**	228 .. 231	**54**	228 .. 231	RampMonTimeSLS3	SLS3 - Ramp monitoring - Time
DINT	**58**	232 .. 235	**55**	232 .. 235	RampMonTimeSLS4	SLS4 - Ramp monitoring - Time
DINT	**59**	236 .. 239	**56**	236 .. 239	DelayRampMonitoring	Ramp monitoring - Enable delay time
DINT	**60**	240 .. 243	**57**	240 .. 243	DelaySDI	SDI - Enable delay time
DINT	**61**	244 .. 247	**58**	244 .. 247	DelaySBC	SBC - Enable delay time
DINT	**62**	248 .. 251	**59**	248 .. 251	DelaySLP	SLP - Enable delay time
DINT	Not used		**60**	252 .. 255	DelaySBT	SBT - Enable delay time
DINT	**63**	252 .. 255	**61**	256 .. 259	DelaySLA	SLA - Enable delay time
DINT	**64**	256 .. 259	**62**	260 .. 263	EarlyLimitMonTime	Early limit monitoring - Time
DINT	**65**	260 .. 263	**63**	264 .. 267	EncMonitoringPosTol	Encoder monitoring - Position error tolerance
DINT	**66**	264 .. 267	**64**	268 .. 271	EncMonitoringSpeedTol	Encoder monitoring - Speed error tolerance
DINT	Not used		**65**	272 .. 275	SbtInterval	SBT - Test interval
DINT	Not used		**66**	276 .. 279	SbtTreshold	SBT - Threshold
DINT	Not used		**67**	280 .. 283	SbtExternalLoad	SBT - External load
DINT	Not used		**68**	284 .. 287	SbtDuration	SBT - Maximum torque duration
DINT	Not used		**69**	288 .. 291	SbtPositionTolerance	SBT - Position tolerance
DINT	67	268 .. 271	**70**	292 .. 295	DelayFFSBM	Blackout Mode delay time to FFS (µs)
DINT	68	272 .. 275	**71**	296 .. 299	ConfiguredSFBM	Blackout Mode configured control word

Table 260: Data structure of safe machine options, Safety Release 1.10 and later (SMC_EnDat22_V02_Opts_typ, SMC_SinCos_V02_Opts_typ)

- ACOPOS P3 SafeMOTION (Safety Release 1.10 and later)

Parameters that are set using a drop-down menu in SafeDESIGNER have a specific range of values, which is listed in the following table for each parameter.

Data type	ACOPOS P3 SafeMOTION EnDat 2.2		Name	Constant / Name in SafeDESIGNER
	Index	Byte offset		
USINT[64]		0 .. 63	EnableBits	SMC_Acp_P3_R110_OptsIndex_enum
UINT		64 .. 65	StructInfoAxisTypeID	Axis type ID of the SafeMOTION module
UINT		66 .. 67	StructInfoSize	Size of the parameter structure
UDINT		68 .. 71	StructInfoVersion	StructInfoVersion
Axis 1 - For 1-axis, 2-axis and 3-axis modules				
USINT	**0**	72 .. 72	UseAutoResetAtStartup	Automatic reset on start - Enable Enabled = 0 Disabled = 1
USINT	**1**	73 .. 73	FuncFailSafeMode	FFS - Mode STO = 0 STO1 and STO with time delay = 1
USINT	**2**	74 .. 74	ucFuncFailSafeEncErrMode	FFS - Caused by encoder error Always = 0 Only if safety functions requiring an encoder are enabled = 1
USINT	**3**	75 .. 75	BMMode	BM - Mode Off = 0 Prev. enabled SF = 1 Prev. enabled and configured SF = 2 Configured SF = 3
DINT	**4**	76 .. 79	FuncFailSafeDelaySTO	FFS - STO Enable delay time
DINT	**5**	80 .. 83	FuncFailSafeDelayBrk	FFS - Delay time until the brake engages
USINT	**6**	84 .. 84	EncoderType	EUS - Encoder type Encoder used = 1 Encoder not used = 0
USINT	**7**	85 .. 85	*AlignmentByte2*	*Alignment placeholder. Do not use!*
USINT	**8**	86 .. 86	*AlignmentByte3*	*Alignment placeholder. Do not use!*
USINT	**9**	87 .. 87	*AlignmentByte4*	*Alignment placeholder. Do not use!*
DINT	**10**	88 .. 91	ScaleRevo	EUS - Count of physical reference system
DINT	**11**	92 .. 95	ScaleUnits	EUS - Units per count of physical reference system
DINT	**12**	96 .. 99	ScaleDirection	EUS - Counting direction Default = 0 Inverse = 1
DINT	**13**	100 .. 103	ScaleLength	EUS - Length of physical reference system for linear encoder
DINT	**14**	104 .. 107	ScaleNormSpeedMax	EUS - Maximum speed to normalize speed range
DINT	**15**	108 .. 111	AccelerationMax	EUS - Encoder acceleration limit
USINT	**16**	112 .. 112	UseEncPosMon	Encoder monitoring - Position error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**17**	113 .. 113	UseEncSpeedMon	Encoder monitoring - Speed error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**18**	114 .. 114	UseSetPosAliveTest	Encoder monitoring - Position setpoint alive testing (SPA) - Enable Disabled = 0 Enabled = 1
USINT	**19**	115 .. 115	UseSEM	Encoder monitoring - Safe Encoder Mounting Approved by user = 0 From motor data record = 1
DINT	**20**	116 .. 119	EncMonitoringPosTol	Encoder monitoring - Position error tolerance
DINT	**21**	120 .. 123	EncMonitoringSpeedTol	Encoder monitoring - Speed error tolerance
DINT	**22**	124 .. 127	PositionTolerance	Standstill monitoring - Position tolerance
DINT	**23**	128 .. 131	SpeedTolerance	Standstill monitoring - Speed tolerance
USINT	**24**	132 .. 132	UseEarlyLimitMon	Early limit monitoring - Enable Disabled = 0 Enabled = 1
USINT	**25**	133 .. 133	*AlignmentByte6*	*Alignment placeholder. Do not use!*
USINT	**26**	134 .. 134	*AlignmentByte7*	*Alignment placeholder. Do not use!*
USINT	**27**	135 .. 135	*AlignmentByte8*	*Alignment placeholder. Do not use!*
DINT	**28**	136 .. 139	EarlyLimitMonTime	Early limit monitoring - Time
DINT	**29**	140 .. 143	DecelerationRamp	Ramp monitoring - Speed deceleration limit
DINT	**30**	144 .. 147	DelayRampMonitoring	Ramp monitoring - Enable delay time
USINT	**31**	148 .. 148	SelectSTO1channel	STO1 - Channel Highside = 0 Lowside = 1
USINT	**32**	149 .. 149	*AlignmentByte9*	*Alignment placeholder. Do not use!*
USINT	**33**	150 .. 150	*AlignmentByte10*	*Alignment placeholder. Do not use!*
USINT	**34**	151 .. 151	*AlignmentByte11*	*Alignment placeholder. Do not use!*
USINT	**35**	152 .. 152	UseRampMonitoringSS1	SS1 - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**36**	153 .. 153	*AlignmentByte12*	*Alignment placeholder. Do not use!*
USINT	**37**	154 .. 154	*AlignmentByte13*	*Alignment placeholder. Do not use!*
USINT	**38**	155 .. 155	*AlignmentByte14*	*Alignment placeholder. Do not use!*
DINT	**39**	156 .. 159	RampMonTimeSS1	SS1 - Ramp monitoring time
DINT	**40**	160 .. 163	DelaySBC	SBC - Enable delay time

Table 261: Data structure of safe machine options in Safety Release 1.10 and later (SMC_Acp_P3_1Ax_R110_Opts_typ, SMC_Acp_P3_2Ax_R110_Opts_typ, SMC_Acp_P3_3Ax_R110_Opts_typ)

Data type	ACOPOS P3 SafeMOTION EnDat 2.2		Name	Constant / Name in SafeDESIGNER
	Index	**Byte offset**		
USINT	**41**	164 .. 164	UseRampMonitoringSS2	SS2 - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**42**	165 .. 165	*AlignmentByte15*	*Alignment placeholder. Do not use!*
USINT	**43**	166 .. 166	*AlignmentByte16*	*Alignment placeholder. Do not use!*
USINT	**44**	167 .. 167	*AlignmentByte17*	*Alignment placeholder. Do not use!*
DINT	**45**	168 .. 171	RampMonTimeSS2	SS2 - Ramp monitoring time
DINT	**46**	172 .. 175	AccelerationLimPos	SLA - Acceleration limit in positive direction
DINT	**47**	176 .. 179	DecelerationLimPos	SLA - Deceleration limit in positive direction
DINT	**48**	180 .. 183	AccelerationLimNeg	SLA - Acceleration limit in negative direction
DINT	**49**	184 .. 187	DecelerationLimNeg	SLA - Deceleration limit in negative direction
DINT	**50**	188 .. 191	DelaySLA	SLA - Enable delay time
USINT	**51**	192 .. 192	UseSMS	SMS - Enable Enabled = 0 Disabled = 1
USINT	**52**	193 .. 193	*AlignmentByte18*	*Alignment placeholder. Do not use!*
USINT	**53**	194 .. 194	*AlignmentByte19*	*Alignment placeholder. Do not use!*
USINT	**54**	195 .. 195	*AlignmentByte20*	*Alignment placeholder. Do not use!*
DINT	**55**	196 .. 199	SpeedLimitSMS	SMS - Speed limit
DINT	**56**	200 .. 203	SpeedLimitSLS1	SLS1 - Speed limit
DINT	**57**	204 .. 207	SpeedLimitSLS2	SLS2 - Speed limit
DINT	**58**	208 .. 211	SpeedLimitSLS3	SLS3 - Speed limit
DINT	**59**	212 .. 215	SpeedLimitSLS4	SLS4 - Speed limit
USINT	**60**	216 .. 216	UseRampMonitoringSLS	SLS - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**61**	217 .. 217	*AlignmentByte21*	*Alignment placeholder. Do not use!*
USINT	**62**	218 .. 218	*AlignmentByte22*	*Alignment placeholder. Do not use!*
USINT	**63**	219 .. 219	*AlignmentByte23*	*Alignment placeholder. Do not use!*
DINT	**64**	220 .. 223	RampMonTimeSLS1	SLS1 - Ramp monitoring - Time
DINT	**65**	224 .. 227	RampMonTimeSLS2	SLS2 - Ramp monitoring - Time
DINT	**66**	228 .. 231	RampMonTimeSLS3	SLS3 - Ramp monitoring - Time
DINT	**67**	232 .. 235	RampMonTimeSLS4	SLS4 - Ramp monitoring - Time
DINT	**68**	236 .. 239	DelaySDI	SDI - Enable delay time
DINT	**69**	240 .. 243	SliPositionWindow	SLI - Position limit
DINT	**70**	244 .. 247	SliToffDelay	SLI - Disable delay time
USINT	**71**	248 .. 248	HomingMode	Homing - Mode Direct = 0 Reference switch = 1 Home offset = 2 Home offset with correction = 3
USINT	**72**	249 .. 249	*AlignmentByte24*	*Alignment placeholder. Do not use!*
USINT	**73**	250 .. 250	*AlignmentByte25*	*Alignment placeholder. Do not use!*
USINT	**74**	251 .. 251	*AlignmentByte26*	*Alignment placeholder. Do not use!*
DINT	**75**	252 .. 255	HomingPos	Homing - Home position or home offset
USINT	**76**	256 .. 256	HomingRemanentSafePos	Homing - Enable RSP (Remanent safe position) Disabled = 0 Enabled = 1
USINT	**77**	257 .. 257	HomingRefSwEdge	Homing - Edge of reference switch Negative = 0 Positive = 1
USINT	**78**	258 .. 258	HomingTriggerDir	Homing - Trigger direction Negative = 0 Positive = 1
USINT	**79**	259 .. 259	HomingRefPulse	Homing - Enable reference pulse Disabled = 0 Enabled = 1
USINT	**80**	260 .. 260	HomingRefPBlock	Homing - Blocking distance
USINT	**81**	261 .. 261	*AlignmentByte27*	*Alignment placeholder. Do not use!*
USINT	**82**	262 .. 262	*AlignmentByte28*	*Alignment placeholder. Do not use!*
USINT	**83**	263 .. 263	*AlignmentByte29*	*Alignment placeholder. Do not use!*
DINT	**84**	264 .. 267	HomingMaxSpeed	Homing - Maximum trigger speed
DINT	**85**	268 .. 271	HomingTMon	Homing - Monitoring time
USINT	**86**	272 .. 272	UseSMP	SMP - Enable Enabled = 0 Disabled = 1
USINT	**87**	273 .. 273	*AlignmentByte30*	*Alignment placeholder. Do not use!*
USINT	**88**	274 .. 274	*AlignmentByte31*	*Alignment placeholder. Do not use!*
USINT	**89**	275 .. 275	*AlignmentByte32*	*Alignment placeholder. Do not use!*
DINT	**90**	276 .. 279	PosLimitMinSMP	SMP - Lower position limit
DINT	**91**	280 .. 283	PosLimitMaxSMP	SMP - Upper position limit
DINT	**92**	284 .. 287	PosLimitMinSLP	SLP - Lower position limit

Table 261: Data structure of safe machine options in Safety Release 1.10 and later (SM-C_Acp_P3_1Ax_R110_Opts_typ, SMC_Acp_P3_2Ax_R110_Opts_typ, SMC_Acp_P3_3Ax_R110_Opts_typ)

Data type	ACOPOS P3 SafeMOTION EnDat 2.2		Name	Constant / Name in SafeDESIGNER
	Index	**Byte offset**		
DINT	**93**	288 .. 291	PosLimitMaxSLP	SLP - Upper position limit
DINT	**94**	292 .. 295	DelaySLP	SLP - Enable delay time
Axis2 - Only for ACOPOS P3 SafeMOTION 2-axis and 3-axis modules				
USINT	**95**	296 .. 296	UseAutoResetAtStartup	Automatic reset on start - Enable Enabled = 0 Disabled = 1
USINT	**96**	297 .. 297	FuncFailSafeMode	FFS - Mode STO = 0 STO1 and STO with time delay = 1
USINT	**97**	298 .. 298	ucFuncFailSafeEncErrMode	FFS - Caused by encoder error Always = 0 Only if safety functions requiring an encoder are enabled = 1
USINT	**98**	299 .. 299	BMMode	BM - Mode Off = 0 Prev. enabled SF = 1 Prev. enabled and configured SF = 2 Configured SF = 3
DINT	**99**	300 .. 303	FuncFailSafeDelaySTO	FFS - STO Enable delay time
DINT	**100**	304 .. 307	FuncFailSafeDelayBrk	FFS - Delay time until the brake engages
USINT	**101**	308 .. 308	EncoderType	EUS - Encoder type Encoder used = 1 Encoder not used = 0
USINT	**102**	309 .. 309	*AlignmentByte2*	*Alignment placeholder. Do not use!*
USINT	**103**	310 .. 310	*AlignmentByte3*	*Alignment placeholder. Do not use!*
USINT	**104**	311 .. 311	*AlignmentByte4*	*Alignment placeholder. Do not use!*
DINT	**105**	312 .. 315	ScaleRevo	EUS - Count of physical reference system
DINT	**106**	316 .. 319	ScaleUnits	EUS - Units per count of physical reference system
DINT	**107**	320 .. 323	ScaleDirection	EUS - Counting direction Default = 0 Inverse = 1
DINT	**108**	324 .. 327	ScaleLength	EUS - Length of physical reference system for linear encoder
DINT	**109**	328 .. 331	ScaleNormSpeedMax	EUS - Maximum speed to normalize speed range
DINT	**110**	332 .. 335	AccelerationMax	EUS - Encoder acceleration limit
USINT	**111**	336 .. 336	UseEncPosMon	Encoder monitoring - Position error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**112**	337 .. 337	UseEncSpeedMon	Encoder monitoring - Speed error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**113**	338 .. 338	UseSetPosAliveTest	Encoder monitoring - Position setpoint alive testing (SPA) - Enable Disabled = 0 Enabled = 1
USINT	**114**	339 .. 339	UseSEM	Encoder monitoring - Safe Encoder Mounting Approved by user = 0 From motor data record = 1
DINT	**115**	340 .. 343	EncMonitoringPosTol	Encoder monitoring - Position error tolerance
DINT	**116**	344 .. 347	EncMonitoringSpeedTol	Encoder monitoring - Speed error tolerance
DINT	**117**	348 .. 351	PositionTolerance	Standstill monitoring - Position tolerance
DINT	**118**	352 .. 355	SpeedTolerance	Standstill monitoring - Speed tolerance
USINT	**119**	356 .. 356	UseEarlyLimitMon	Early limit monitoring - Enable Disabled = 0 Enabled = 1
USINT	**120**	357 .. 357	*AlignmentByte6*	*Alignment placeholder. Do not use!*
USINT	**121**	358 .. 358	*AlignmentByte7*	*Alignment placeholder. Do not use!*
USINT	**122**	359 .. 359	*AlignmentByte8*	*Alignment placeholder. Do not use!*
DINT	**123**	360 .. 363	EarlyLimitMonTime	Early limit monitoring - Time
DINT	**124**	364 .. 367	DecelerationRamp	Ramp monitoring - Speed deceleration limit
DINT	**125**	368 .. 371	DelayRampMonitoring	Ramp monitoring - Enable delay time
USINT	**126**	372 .. 372	SelectSTO1channel	STO1 - Channel Highside = 0 Lowside = 1
USINT	**127**	373 .. 373	*AlignmentByte9*	*Alignment placeholder. Do not use!*
USINT	**128**	374 .. 374	*AlignmentByte10*	*Alignment placeholder. Do not use!*
USINT	**129**	375 .. 375	*AlignmentByte11*	*Alignment placeholder. Do not use!*
USINT	**130**	376 .. 376	UseRampMonitoringSS1	SS1 - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**131**	377 .. 377	*AlignmentByte12*	*Alignment placeholder. Do not use!*
USINT	**132**	378 .. 378	*AlignmentByte13*	*Alignment placeholder. Do not use!*
USINT	**133**	379 .. 379	*AlignmentByte14*	*Alignment placeholder. Do not use!*
DINT	**134**	380 .. 383	RampMonTimeSS1	SS1 - Ramp monitoring time
DINT	**135**	384 .. 387	DelaySBC	SBC - Enable delay time

Table 261: Data structure of safe machine options in Safety Release 1.10 and later (SMC_Acp_P3_1Ax_R110_Opts_typ, SMC_Acp_P3_2Ax_R110_Opts_typ, SMC_Acp_P3_3Ax_R110_Opts_typ)

Data type	ACOPOS P3 SafeMOTION EnDat 2.2		Name	Constant / Name in SafeDESIGNER
	Index	**Byte offset**		
USINT	**136**	388 .. 388	UseRampMonitoringSS2	SS2 - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**137**	389 .. 389	*AlignmentByte15*	*Alignment placeholder. Do not use!*
USINT	**138**	390 .. 390	*AlignmentByte16*	*Alignment placeholder. Do not use!*
USINT	**139**	391 .. 391	*AlignmentByte17*	*Alignment placeholder. Do not use!*
DINT	**140**	392 .. 395	RampMonTimeSS2	SS2 - Ramp monitoring time
DINT	**141**	396 .. 399	AccelerationLimPos	SLA - Acceleration limit in positive direction
DINT	**142**	400 .. 403	DecelerationLimPos	SLA - Deceleration limit in positive direction
DINT	**143**	404 .. 407	AccelerationLimNeg	SLA - Acceleration limit in negative direction
DINT	**144**	408 .. 411	DecelerationLimNeg	SLA - Deceleration limit in negative direction
DINT	**145**	412 .. 415	DelaySLA	SLA - Enable delay time
USINT	**146**	416 .. 416	UseSMS	SMS - Enable Enabled = 0 Disabled = 1
USINT	**147**	417 .. 417	*AlignmentByte18*	*Alignment placeholder. Do not use!*
USINT	**148**	418 .. 418	*AlignmentByte19*	*Alignment placeholder. Do not use!*
USINT	**149**	419 .. 419	*AlignmentByte20*	*Alignment placeholder. Do not use!*
DINT	**150**	420 .. 423	SpeedLimitSMS	SMS - Speed limit
DINT	**151**	424 .. 427	SpeedLimitSLS1	SLS1 - Speed limit
DINT	**152**	428 .. 431	SpeedLimitSLS2	SLS2 - Speed limit
DINT	**153**	432 .. 435	SpeedLimitSLS3	SLS3 - Speed limit
DINT	**154**	436 .. 439	SpeedLimitSLS4	SLS4 - Speed limit
USINT	**155**	440 .. 440	UseRampMonitoringSLS	SLS - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**156**	441 .. 441	*AlignmentByte21*	*Alignment placeholder. Do not use!*
USINT	**157**	442 .. 442	*AlignmentByte22*	*Alignment placeholder. Do not use!*
USINT	**158**	443 .. 443	*AlignmentByte23*	*Alignment placeholder. Do not use!*
DINT	**159**	444 .. 447	RampMonTimeSLS1	SLS1 - Ramp monitoring - Time
DINT	**160**	448 .. 451	RampMonTimeSLS2	SLS2 - Ramp monitoring - Time
DINT	**161**	452 .. 455	RampMonTimeSLS3	SLS3 - Ramp monitoring - Time
DINT	**162**	456 .. 459	RampMonTimeSLS4	SLS4 - Ramp monitoring - Time
DINT	**163**	460 .. 463	DelaySDI	SDI - Enable delay time
DINT	**164**	464 .. 467	SliPositionWindow	SLI - Position limit
DINT	**165**	468 .. 471	SliToffDelay	SLI - Disable delay time
USINT	**166**	472 .. 472	HomingMode	Homing - Mode Direct = 0 Reference switch = 1 Home offset = 2 Home offset with correction = 3
USINT	**167**	473 .. 473	*AlignmentByte24*	*Alignment placeholder. Do not use!*
USINT	**168**	474 .. 474	*AlignmentByte25*	*Alignment placeholder. Do not use!*
USINT	**169**	475 .. 475	*AlignmentByte26*	*Alignment placeholder. Do not use!*
DINT	**170**	476 .. 479	HomingPos	Homing - Home position or home offset
USINT	**171**	480 .. 480	HomingRemanentSafePos	Homing - Enable RSP (Remanent safe position) Disabled = 0 Enabled = 1
USINT	**172**	481 .. 481	HomingRefSwEdge	Homing - Edge of reference switch Negative = 0 Positive = 1
USINT	**173**	482 .. 482	HomingTriggerDir	Homing - Trigger direction Negative = 0 Positive = 1
USINT	**174**	483 .. 483	HomingRefPulse	Homing - Enable reference pulse Disabled = 0 Enabled = 1
USINT	**175**	484 .. 484	HomingRefPBlock	Homing - Blocking distance
USINT	**176**	485 .. 485	*AlignmentByte27*	*Alignment placeholder. Do not use!*
USINT	**177**	486 .. 486	*AlignmentByte28*	*Alignment placeholder. Do not use!*
USINT	**178**	487 .. 487	*AlignmentByte29*	*Alignment placeholder. Do not use!*
DINT	**179**	488 .. 491	HomingMaxSpeed	Homing - Maximum trigger speed
DINT	**180**	492 .. 495	HomingTMon	Homing - Monitoring time
USINT	**181**	496 .. 496	UseSMP	SMP - Enable Enabled = 0 Disabled = 1
USINT	**182**	497 .. 497	*AlignmentByte30*	*Alignment placeholder. Do not use!*
USINT	**183**	498 .. 498	*AlignmentByte31*	*Alignment placeholder. Do not use!*
USINT	**184**	499 .. 499	*AlignmentByte32*	*Alignment placeholder. Do not use!*
DINT	**185**	500 .. 503	PosLimitMinSMP	SMP - Lower position limit
DINT	**186**	504 .. 507	PosLimitMaxSMP	SMP - Upper position limit
DINT	**187**	508 .. 511	PosLimitMinSLP	SLP - Lower position limit

Table 261: Data structure of safe machine options in Safety Release 1.10 and later (SMC_Acp_P3_1Ax_R110_Opts_typ, SMC_Acp_P3_2Ax_R110_Opts_typ, SMC_Acp_P3_3Ax_R110_Opts_typ)

Data type	ACOPOS P3 SafeMOTION EnDat 2.2		Name	Constant / Name in SafeDESIGNER
	Index	**Byte offset**		
DINT	**188**	512 .. 515	PosLimitMaxSLP	SLP - Upper position limit
DINT	**189**	516 .. 519	DelaySLP	SLP - Enable delay time
Axis3 - Only for ACOPOS P3 SafeMOTION 3-axis modules				
USINT	**190**	520 .. 520	UseAutoResetAtStartup	Automatic reset on start - Enable Enabled = 0 Disabled = 1
USINT	**191**	521 .. 521	FuncFailSafeMode	FFS - Mode STO = 0 STO1 and STO with time delay = 1
USINT	**192**	522 .. 522	ucFuncFailSafeEncErrMode	FFS - Caused by encoder error Always = 0 Only if safety functions requiring an encoder are enabled = 1
USINT	**193**	523 .. 523	BMMode	BM - Mode Off = 0 Prev. enabled SF = 1 Prev. enabled and configured SF = 2 Configured SF = 3
DINT	**194**	524 .. 527	FuncFailSafeDelaySTO	FFS - STO Enable delay time
DINT	**195**	528 .. 531	FuncFailSafeDelayBrk	FFS - Delay time until the brake engages
USINT	**196**	532 .. 532	EncoderType	EUS - Encoder type Encoder used = 1 Encoder not used = 0
USINT	**197**	533 .. 533	*AlignmentByte2*	*Alignment placeholder. Do not use!*
USINT	**198**	534 .. 534	*AlignmentByte3*	*Alignment placeholder. Do not use!*
USINT	**199**	535 .. 535	*AlignmentByte4*	*Alignment placeholder. Do not use!*
DINT	**200**	536 .. 539	ScaleRevo	EUS - Count of physical reference system
DINT	**201**	540 .. 543	ScaleUnits	EUS - Units per count of physical reference system
DINT	**202**	544 .. 547	ScaleDirection	EUS - Counting direction Default = 0 Inverse = 1
DINT	**203**	548 .. 551	ScaleLength	EUS - Length of physical reference system for linear encoder
DINT	**204**	552 .. 555	ScaleNormSpeedMax	EUS - Maximum speed to normalize speed range
DINT	**205**	556 .. 559	AccelerationMax	EUS - Encoder acceleration limit
USINT	**206**	560 .. 560	UseEncPosMon	Encoder monitoring - Position error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**207**	561 .. 561	UseEncSpeedMon	Encoder monitoring - Speed error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**208**	562 .. 562	UseSetPosAliveTest	Encoder monitoring - Position setpoint alive testing (SPA) - Enable Disabled = 0 Enabled = 1
USINT	**209**	563 .. 563	UseSEM	Encoder monitoring - Safe Encoder Mounting Approved by user = 0 From motor data record = 1
DINT	**210**	564 .. 567	EncMonitoringPosTol	Encoder monitoring - Position error tolerance
DINT	**211**	568 .. 571	EncMonitoringSpeedTol	Encoder monitoring - Speed error tolerance
DINT	**212**	572 .. 575	PositionTolerance	Standstill monitoring - Position tolerance
DINT	**213**	576 .. 579	SpeedTolerance	Standstill monitoring - Speed tolerance
USINT	**214**	580 .. 580	UseEarlyLimitMon	Early limit monitoring - Enable Disabled = 0 Enabled = 1
USINT	**215**	581 .. 581	*AlignmentByte6*	*Alignment placeholder. Do not use!*
USINT	**216**	582 .. 582	*AlignmentByte7*	*Alignment placeholder. Do not use!*
USINT	**217**	583 .. 583	*AlignmentByte8*	*Alignment placeholder. Do not use!*
DINT	**218**	584 .. 587	EarlyLimitMonTime	Early limit monitoring - Time
DINT	**219**	588 .. 591	DecelerationRamp	Ramp monitoring - Speed deceleration limit
DINT	**220**	592 .. 595	DelayRampMonitoring	Ramp monitoring - Enable delay time
USINT	**221**	596 .. 596	SelectSTO1channel	STO1 - Channel Highside = 0 Lowside = 1
USINT	**222**	597 .. 597	*AlignmentByte9*	*Alignment placeholder. Do not use!*
USINT	**223**	598 .. 598	*AlignmentByte10*	*Alignment placeholder. Do not use!*
USINT	**224**	599 .. 599	*AlignmentByte11*	*Alignment placeholder. Do not use!*
USINT	**225**	600 .. 600	UseRampMonitoringSS1	SS1 - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**226**	601 .. 601	*AlignmentByte12*	*Alignment placeholder. Do not use!*
USINT	**227**	602 .. 602	*AlignmentByte13*	*Alignment placeholder. Do not use!*
USINT	**228**	603 .. 603	*AlignmentByte14*	*Alignment placeholder. Do not use!*
DINT	**229**	604 .. 607	RampMonTimeSS1	SS1 - Ramp monitoring time
DINT	**230**	608 .. 611	DelaySBC	SBC - Enable delay time

Table 261: Data structure of safe machine options in Safety Release 1.10 and later (SM-C_Acp_P3_1Ax_R110_Opts_typ, SMC_Acp_P3_2Ax_R110_Opts_typ, SMC_Acp_P3_3Ax_R110_Opts_typ)

Data type	ACOPOS P3 SafeMOTION EnDat 2.2		Name	Constant / Name in SafeDESIGNER
	Index	**Byte offset**		
USINT	**231**	612 .. 612	UseRampMonitoringSS2	SS2 - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**232**	613 .. 613	*AlignmentByte15*	*Alignment placeholder. Do not use!*
USINT	**233**	614 .. 614	*AlignmentByte16*	*Alignment placeholder. Do not use!*
USINT	**234**	615 .. 615	*AlignmentByte17*	*Alignment placeholder. Do not use!*
DINT	**235**	616 .. 619	RampMonTimeSS2	SS2 - Ramp monitoring time
DINT	**236**	620 .. 623	AccelerationLimPos	SLA - Acceleration limit in positive direction
DINT	**237**	624 .. 627	DecelerationLimPos	SLA - Deceleration limit in positive direction
DINT	**238**	628 .. 631	AccelerationLimNeg	SLA - Acceleration limit in negative direction
DINT	**239**	632 .. 635	DecelerationLimNeg	SLA - Deceleration limit in negative direction
DINT	**240**	636 .. 639	DelaySLA	SLA - Enable delay time
USINT	**241**	640 .. 640	UseSMS	SMS - Enable Enabled = 0 Disabled = 1
USINT	**242**	641 .. 641	*AlignmentByte18*	*Alignment placeholder. Do not use!*
USINT	**243**	642 .. 642	*AlignmentByte19*	*Alignment placeholder. Do not use!*
USINT	**244**	643 .. 643	*AlignmentByte20*	*Alignment placeholder. Do not use!*
DINT	**245**	644 .. 647	SpeedLimitSMS	SMS - Speed limit
DINT	**246**	648 .. 651	SpeedLimitSLS1	SLS1 - Speed limit
DINT	**247**	652 .. 655	SpeedLimitSLS2	SLS2 - Speed limit
DINT	**248**	656 .. 659	SpeedLimitSLS3	SLS3 - Speed limit
DINT	**249**	660 .. 663	SpeedLimitSLS4	SLS4 - Speed limit
USINT	**250**	664 .. 664	UseRampMonitoringSLS	SLS - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**251**	665 .. 665	*AlignmentByte21*	*Alignment placeholder. Do not use!*
USINT	**252**	666 .. 666	*AlignmentByte22*	*Alignment placeholder. Do not use!*
USINT	**253**	667 .. 667	*AlignmentByte23*	*Alignment placeholder. Do not use!*
DINT	**254**	668 .. 671	RampMonTimeSLS1	SLS1 - Ramp monitoring - Time
DINT	**255**	672 .. 675	RampMonTimeSLS2	SLS2 - Ramp monitoring - Time
DINT	**256**	676 .. 679	RampMonTimeSLS3	SLS3 - Ramp monitoring - Time
DINT	**257**	680 .. 683	RampMonTimeSLS4	SLS4 - Ramp monitoring - Time
DINT	**258**	684 .. 687	DelaySDI	SDI - Enable delay time
DINT	**259**	688 .. 691	SliPositionWindow	SLI - Position limit
DINT	**260**	692 .. 695	SliToffDelay	SLI - Disable delay time
USINT	**261**	696 .. 696	HomingMode	Homing - Mode Direct = 0 Reference switch = 1 Home offset = 2 Home offset with correction = 3
USINT	**262**	697 .. 697	*AlignmentByte24*	*Alignment placeholder. Do not use!*
USINT	**263**	698 .. 698	*AlignmentByte25*	*Alignment placeholder. Do not use!*
USINT	**264**	699 .. 699	*AlignmentByte26*	*Alignment placeholder. Do not use!*
DINT	**265**	700 .. 703	HomingPos	Homing - Home position or home offset
USINT	**266**	704 .. 704	HomingRemanentSafePos	Homing - Enable RSP (Remanent safe position) Disabled = 0 Enabled = 1
USINT	**267**	705 .. 705	HomingRefSwEdge	Homing - Edge of reference switch Negative = 0 Positive = 1
USINT	**268**	706 .. 706	HomingTriggerDir	Homing - Trigger direction Negative = 0 Positive = 1
USINT	**269**	707 .. 707	HomingRefPulse	Homing - Enable reference pulse Disabled = 0 Enabled = 1
USINT	**270**	708 .. 708	HomingRefPBlock	Homing - Blocking distance
USINT	**271**	709 .. 709	*AlignmentByte27*	*Alignment placeholder. Do not use!*
USINT	**272**	710 .. 710	*AlignmentByte28*	*Alignment placeholder. Do not use!*
USINT	**273**	711 .. 711	*AlignmentByte29*	*Alignment placeholder. Do not use!*
DINT	**274**	712 .. 715	HomingMaxSpeed	Homing - Maximum trigger speed
DINT	**275**	716 .. 719	HomingTMon	Homing - Monitoring time
USINT	**276**	720 .. 720	UseSMP	SMP - Enable Enabled = 0 Disabled = 1
USINT	**277**	721 .. 721	*AlignmentByte30*	*Alignment placeholder. Do not use!*
USINT	**278**	722 .. 722	*AlignmentByte31*	*Alignment placeholder. Do not use!*
USINT	**279**	723 .. 723	*AlignmentByte32*	*Alignment placeholder. Do not use!*
DINT	**280**	724 .. 727	PosLimitMinSMP	SMP - Lower position limit

Table 261: Data structure of safe machine options in Safety Release 1.10 and later (SMC_Acp_P3_1Ax_R110_Opts_typ, SMC_Acp_P3_2Ax_R110_Opts_typ, SMC_Acp_P3_3Ax_R110_Opts_typ)

Data type	ACOPOS P3 SafeMOTION EnDat 2.2		Name	Constant / Name in SafeDESIGNER
	Index	Byte offset		
DINT	**281**	728 .. 731	PosLimitMaxSMP	SMP - Upper position limit
DINT	**282**	732 .. 735	PosLimitMinSLP	SLP - Lower position limit
DINT	**283**	736 .. 739	PosLimitMaxSLP	SLP - Upper position limit
DINT	**284**	740 .. 743	DelaySLP	SLP - Enable delay time

Table 261: Data structure of safe machine options in Safety Release 1.10 and later (SM-C_Acp_P3_1Ax_R110_Opts_typ, SMC_Acp_P3_2Ax_R110_Opts_typ, SMC_Acp_P3_3Ax_R110_Opts_typ)

- ACOPOS P3 SafeMOTION (Safety Release 1.10 and later, hardware upgrade 1.10.2x and later)

Parameters that are set using a drop-down menu in SafeDESIGNER have a specific range of values, which is listed in the following table for each parameter.

Data type	ACOPOS P3 SafeMOTION EnDat 2.2				Name	Constant / Name in SafeDESIGNER
	Index	Byte offset 1-axis module	Byte offset 2-axis module	Byte offset 3-axis module		
USINT[64]		0 .. 63	0 .. 63	0 .. 63	EnableBits	SMC_Acp_P3_R110_OptsIndex_enum
UINT		64 .. 65	64 .. 65	64 .. 65	StructInfoAxisTypeID	Axis type ID of the SafeMOTION module
UINT		66 .. 67	66 .. 67	66 .. 67	StructInfoSize	Size of the parameter structure
UDINT		68 .. 71	68 .. 71	68 .. 71	StructInfoVersion	StructInfoVersion
Axis 1 - For 1-axis, 2-axis and 3-axis modules						
USINT	**0**	72 .. 72	72 .. 72	72 .. 72	UseAutoResetAtStartup	Automatic reset on start - Enable Enabled = 0 Disabled = 1
USINT	**1**	73 .. 73	73 .. 73	73 .. 73	FuncFailSafeMode	FFS - Mode STO = 0 STO1 and STO with time delay = 1
USINT	**2**	74 .. 74	74 .. 74	74 .. 74	ucFuncFailSafeEncErrMode	FFS - Caused by encoder error Always = 0 Only if safety functions requiring an encoder are enabled = 1
USINT	**3**	75 .. 75	75 .. 75	75 .. 75	BMMode	BM - Mode Off = 0 Prev. enabled SF = 1 Prev. enabled and configured SF = 2 Configured SF = 3
DINT	**4**	76 .. 79	76 .. 79	76 .. 79	FuncFailSafeDelaySTO	FFS - STO Enable delay time
DINT	**5**	80 .. 83	80 .. 83	80 .. 83	FuncFailSafeDelayBrk	FFS - Delay time until the brake engages
USINT	**6**	84 .. 84	84 .. 84	84 .. 84	EncoderType	EUS - Encoder type Encoder used = 1 Encoder not used = 0
USINT	**7**	85 .. 85	85 .. 85	85 .. 85	*AlignmentByte2*	*Alignment placeholder. Do not use!*
USINT	**8**	86 .. 86	86 .. 86	86 .. 86	*AlignmentByte3*	*Alignment placeholder. Do not use!*
USINT	**9**	87 .. 87	87 .. 87	87 .. 87	*AlignmentByte4*	*Alignment placeholder. Do not use!*
DINT	**10**	88 .. 91	88 .. 91	88 .. 91	ScaleRevo	EUS - Count of physical reference system
DINT	**11**	92 .. 95	92 .. 95	92 .. 95	ScaleUnits	EUS - Units per count of physical reference system
DINT	**12**	96 .. 99	96 .. 99	96 .. 99	ScaleDirection	EUS - Counting direction Default = 0 Inverse = 1
DINT	**13**	100 .. 103	100 .. 103	100 .. 103	ScaleLength	EUS - Length of physical reference system for linear encoder
DINT	**14**	104 .. 107	104 .. 107	104 .. 107	ScaleNormSpeedMax	EUS - Maximum speed to normalize speed range
DINT	**15**	108 .. 111	108 .. 111	108 .. 111	AccelerationMax	EUS - Encoder acceleration limit
USINT	**16**	112 .. 112	112 .. 112	112 .. 112	UseEncPosMon	Encoder monitoring - Position error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**17**	113 .. 113	113 .. 113	113 .. 113	UseEncSpeedMon	Encoder monitoring - Speed error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**18**	114 .. 114	114 .. 114	114 .. 114	UseSetPosAliveTest	Encoder monitoring - Position setpoint alive testing (SPA) - Enable Disabled = 0 Enabled = 1
USINT	**19**	115 .. 115	115 .. 115	115 .. 115	UseSEM	Encoder monitoring - Safe Encoder Mounting Approved by user = 0 From motor data record = 1
DINT	**20**	116 .. 119	116 .. 119	116 .. 119	EncMonitoringPosTol	Encoder monitoring - Position error tolerance
DINT	**21**	120 .. 123	120 .. 123	120 .. 123	EncMonitoringSpeedTol	Encoder monitoring - Speed error tolerance
DINT	**22**	124 .. 127	124 .. 127	124 .. 127	PositionTolerance	Standstill monitoring - Position tolerance
DINT	**23**	128 .. 131	128 .. 131	128 .. 131	SpeedTolerance	Standstill monitoring - Speed tolerance

Table 262: Data structure of safe machine options in Safety Release 1.10 and later, hardware upgrade 1.10.2.x and later (SMC_Acp_P3_1A- x_R110_OptsV2_typ, SMC_Acp_P3_2Ax_R110_OptsV2_typ, SMC_Acp_P3_3Ax_R110_OptsV2_typ)

Data type	ACOPOS P3 SafeMOTION EnDat 2.2				Name	Constant / Name in SafeDESIGNER
	Index	Byte offset 1-axis module	Byte offset 2-axis module	Byte offset 3-axis module		
USINT	**24**	132 .. 132	132 .. 132	132 .. 132	UseEarlyLimitMon	Early limit monitoring - Enable Disabled = 0 Enabled = 1
USINT	**25**	133 .. 133	133 .. 133	133 .. 133	*AlignmentByte6*	*Alignment placeholder. Do not use!*
USINT	**26**	134 .. 134	134 .. 134	134 .. 134	*AlignmentByte7*	*Alignment placeholder. Do not use!*
USINT	**27**	135 .. 135	135 .. 135	135 .. 135	*AlignmentByte8*	*Alignment placeholder. Do not use!*
DINT	**28**	136 .. 139	136 .. 139	136 .. 139	EarlyLimitMonTime	Early limit monitoring - Time
DINT	**29**	140 .. 143	140 .. 143	140 .. 143	DecelerationRamp	Ramp monitoring - Speed deceleration limit
DINT	**30**	144 .. 147	144 .. 147	144 .. 147	DelayRampMonitoring	Ramp monitoring - Enable delay time
USINT	**31**	148 .. 148	148 .. 148	148 .. 148	SelectSTO1channel	STO1 - Channel Highside = 0 Lowside = 1
USINT	**32**	149 .. 149	149 .. 149	149 .. 149	*AlignmentByte9*	*Alignment placeholder. Do not use!*
USINT	**33**	150 .. 150	150 .. 150	150 .. 150	*AlignmentByte10*	*Alignment placeholder. Do not use!*
USINT	**34**	151 .. 151	151 .. 151	151 .. 151	*AlignmentByte11*	*Alignment placeholder. Do not use!*
USINT	**35**	152 .. 152	152 .. 152	152 .. 152	UseRampMonitoringSS1	SS1 - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**36**	153 .. 153	153 .. 153	153 .. 153	*AlignmentByte12*	*Alignment placeholder. Do not use!*
USINT	**37**	154 .. 154	154 .. 154	154 .. 154	*AlignmentByte13*	*Alignment placeholder. Do not use!*
USINT	**38**	155 .. 155	155 .. 155	155 .. 155	*AlignmentByte14*	*Alignment placeholder. Do not use!*
DINT	**39**	156 .. 159	156 .. 159	156 .. 159	RampMonTimeSS1	SS1 - Ramp monitoring time
DINT	**40**	160 .. 163	160 .. 163	160 .. 163	DelaySBC	SBC - Enable delay time
USINT	**41**	164 .. 164	164 .. 164	164 .. 164	UseRampMonitoringSS2	SS2 - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**42**	165 .. 165	165 .. 165	165 .. 165	*AlignmentByte15*	*Alignment placeholder. Do not use!*
USINT	**43**	166 .. 166	166 .. 166	166 .. 166	*AlignmentByte16*	*Alignment placeholder. Do not use!*
USINT	**44**	167 .. 167	167 .. 167	167 .. 167	*AlignmentByte17*	*Alignment placeholder. Do not use!*
DINT	**45**	168 .. 171	168 .. 171	168 .. 171	RampMonTimeSS2	SS2 - Ramp monitoring time
DINT	**46**	172 .. 175	172 .. 175	172 .. 175	AccelerationLimPos	SLA - Acceleration limit in positive direction
DINT	**47**	176 .. 179	176 .. 179	176 .. 179	DecelerationLimPos	SLA - Deceleration limit in positive direction
DINT	**48**	180 .. 183	180 .. 183	180 .. 183	AccelerationLimNeg	SLA - Acceleration limit in negative direction
DINT	**49**	184 .. 187	184 .. 187	184 .. 187	DecelerationLimNeg	SLA - Deceleration limit in negative direction
DINT	**50**	188 .. 191	188 .. 191	188 .. 191	DelaySLA	SLA - Enable delay time
USINT	**51**	192 .. 192	192 .. 192	192 .. 192	UseSMS	SMS - Enable Enabled = 0 Disabled = 1
USINT	**52**	193 .. 193	193 .. 193	193 .. 193	*AlignmentByte18*	*Alignment placeholder. Do not use!*
USINT	**53**	194 .. 194	194 .. 194	194 .. 194	*AlignmentByte19*	*Alignment placeholder. Do not use!*
USINT	**54**	195 .. 195	195 .. 195	195 .. 195	*AlignmentByte20*	*Alignment placeholder. Do not use!*
DINT	**55**	196 .. 199	196 .. 199	196 .. 199	SpeedLimitSMS	SMS - Speed limit
DINT	**56**	200 .. 203	200 .. 203	200 .. 203	SpeedLimitSLS1	SLS1 - Speed limit
DINT	**57**	204 .. 207	204 .. 207	204 .. 207	SpeedLimitSLS2	SLS2 - Speed limit
DINT	**58**	208 .. 211	208 .. 211	208 .. 211	SpeedLimitSLS3	SLS3 - Speed limit
DINT	**59**	212 .. 215	212 .. 215	212 .. 215	SpeedLimitSLS4	SLS4 - Speed limit
USINT	**60**	216 .. 216	216 .. 216	216 .. 216	UseRampMonitoringSLS	SLS - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**61**	217 .. 217	217 .. 217	217 .. 217	*AlignmentByte21*	*Alignment placeholder. Do not use!*
USINT	**62**	218 .. 218	218 .. 218	218 .. 218	*AlignmentByte22*	*Alignment placeholder. Do not use!*
USINT	**63**	219 .. 219	219 .. 219	219 .. 219	*AlignmentByte23*	*Alignment placeholder. Do not use!*
DINT	**64**	220 .. 223	220 .. 223	220 .. 223	RampMonTimeSLS1	SLS1 - Ramp monitoring - Time
DINT	**65**	224 .. 227	224 .. 227	224 .. 227	RampMonTimeSLS2	SLS2 - Ramp monitoring - Time
DINT	**66**	228 .. 231	228 .. 231	228 .. 231	RampMonTimeSLS3	SLS3 - Ramp monitoring - Time
DINT	**67**	232 .. 235	232 .. 235	232 .. 235	RampMonTimeSLS4	SLS4 - Ramp monitoring - Time
DINT	**68**	236 .. 239	236 .. 239	236 .. 239	DelaySDI	SDI - Enable delay time
DINT	**69**	240 .. 243	240 .. 243	240 .. 243	SliPositionWindow	SLI - Position limit
DINT	**70**	244 .. 247	244 .. 247	244 .. 247	SliToffDelay	SLI - Disable delay time
USINT	**71**	248 .. 248	248 .. 248	248 .. 248	HomingMode	Homing - Mode Direct = 0 Reference switch = 1 Home offset = 2 Home offset with correction = 3
USINT	**72**	249 .. 249	249 .. 249	249 .. 249	*AlignmentByte24*	*Alignment placeholder. Do not use!*
USINT	**73**	250 .. 250	250 .. 250	250 .. 250	*AlignmentByte25*	*Alignment placeholder. Do not use!*
USINT	**74**	251 .. 251	251 .. 251	251 .. 251	*AlignmentByte26*	*Alignment placeholder. Do not use!*
DINT	**75**	252 .. 255	252 .. 255	252 .. 255	HomingPos	Homing - Home position or home offset

Table 262: Data structure of safe machine options in Safety Release 1.10 and later, hardware upgrade 1.10.2.x and later (SMC_Acp_P3_1A- x_R110_OptsV2_typ, SMC_Acp_P3_2Ax_R110_OptsV2_typ, SMC_Acp_P3_3Ax_R110_OptsV2_typ)

Data type	ACOPOS P3 SafeMOTION EnDat 2.2				Name	Constant / Name in SafeDESIGNER
	Index	**Byte offset 1-axis module**	**Byte offset 2-axis module**	**Byte offset 3-axis module**		
USINT	**76**	256 .. 256	256 .. 256	256 .. 256	HomingRemanentSafePos	Homing - Enable RSP (Remanent safe position) Disabled = 0 Enabled = 1
USINT	**77**	257 .. 257	257 .. 257	257 .. 257	HomingRefSwEdge	Homing - Edge of reference switch Negative = 0 Positive = 1
USINT	**78**	258 .. 258	258 .. 258	258 .. 258	HomingTriggerDir	Homing - Trigger direction Negative = 0 Positive = 1
USINT	**79**	259 .. 259	259 .. 259	259 .. 259	HomingRefPulse	Homing - Enable reference pulse Disabled = 0 Enabled = 1
USINT	**80**	260 .. 260	260 .. 260	260 .. 260	HomingRefPBlock	Homing - Blocking distance
USINT	**81**	261 .. 261	261 .. 261	261 .. 261	*AlignmentByte27*	*Alignment placeholder. Do not use!*
USINT	**82**	262 .. 262	262 .. 262	262 .. 262	*AlignmentByte28*	*Alignment placeholder. Do not use!*
USINT	**83**	263 .. 263	263 .. 263	263 .. 263	*AlignmentByte29*	*Alignment placeholder. Do not use!*
DINT	**84**	264 .. 267	264 .. 267	264 .. 267	HomingMaxSpeed	Homing - Maximum trigger speed
DINT	**85**	268 .. 271	268 .. 271	268 .. 271	HomingTMon	Homing - Monitoring time
USINT	**86**	272 .. 272	272 .. 272	272 .. 272	UseSMP	SMP - Enable Enabled = 0 Disabled = 1
USINT	**87**	273 .. 273	273 .. 273	273 .. 273	*AlignmentByte30*	*Alignment placeholder. Do not use!*
USINT	**88**	274 .. 274	274 .. 274	274 .. 274	*AlignmentByte31*	*Alignment placeholder. Do not use!*
USINT	**89**	275 .. 275	275 .. 275	275 .. 275	*AlignmentByte32*	*Alignment placeholder. Do not use!*
DINT	**90**	276 .. 279	276 .. 279	276 .. 279	PosLimitMinSMP	SMP - Lower position limit
DINT	**91**	280 .. 283	280 .. 283	280 .. 283	PosLimitMaxSMP	SMP - Upper position limit
DINT	**92**	284 .. 287	284 .. 287	284 .. 287	PosLimitMinSLP	SLP - Lower position limit
DINT	**93**	288 .. 291	288 .. 291	288 .. 291	PosLimitMaxSLP	SLP - Upper position limit
DINT	**94**	292 .. 295	292 .. 295	292 .. 295	DelaySLP	SLP - Enable delay time
Axis2 - Only for ACOPOS P3 SafeMOTION 2-axis and 3-axis modules						
USINT	**95**	Not used	296 .. 296	296 .. 296	UseAutoResetAtStartup	Automatic reset on start - Enable Enabled = 0 Disabled = 1
USINT	**96**	Not used	297 .. 297	297 .. 297	FuncFailSafeMode	FFS - Mode STO = 0 STO1 and STO with time delay = 1
USINT	**97**	Not used	298 .. 298	298 .. 298	ucFuncFailSafeEncErrMode	FFS - Caused by encoder error Always = 0 Only if safety functions requiring an encoder are enabled = 1
USINT	**98**	Not used	299 .. 299	299 .. 299	BMMode	BM - Mode Off = 0 Prev. enabled SF = 1 Prev. enabled and configured SF = 2 Configured SF = 3
DINT	**99**	Not used	300 .. 303	300 .. 303	FuncFailSafeDelaySTO	FFS - STO Enable delay time
DINT	**100**	Not used	304 .. 307	304 .. 307	FuncFailSafeDelayBrk	FFS - Delay time until the brake engages
USINT	**101**	Not used	308 .. 308	308 .. 308	EncoderType	EUS - Encoder type Encoder used = 1 Encoder not used = 0
USINT	**102**	Not used	309 .. 309	309 .. 309	*AlignmentByte2*	*Alignment placeholder. Do not use!*
USINT	**103**	Not used	310 .. 310	310 .. 310	*AlignmentByte3*	*Alignment placeholder. Do not use!*
USINT	**104**	Not used	311 .. 311	311 .. 311	*AlignmentByte4*	*Alignment placeholder. Do not use!*
DINT	**105**	Not used	312 .. 315	312 .. 315	ScaleRevo	EUS - Count of physical reference system
DINT	**106**	Not used	316 .. 319	316 .. 319	ScaleUnits	EUS - Units per count of physical reference system
DINT	**107**	Not used	320 .. 323	320 .. 323	ScaleDirection	EUS - Counting direction Default = 0 Inverse = 1
DINT	**108**	Not used	324 .. 327	324 .. 327	ScaleLength	EUS - Length of physical reference system for linear encoder
DINT	**109**	Not used	328 .. 331	328 .. 331	ScaleNormSpeedMax	EUS - Maximum speed to normalize speed range
DINT	**110**	Not used	332 .. 335	332 .. 335	AccelerationMax	EUS - Encoder acceleration limit
USINT	**111**	Not used	336 .. 336	336 .. 336	UseEncPosMon	Encoder monitoring - Position error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**112**	Not used	337 .. 337	337 .. 337	UseEncSpeedMon	Encoder monitoring - Speed error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**113**	Not used	338 .. 338	338 .. 338	UseSetPosAliveTest	Encoder monitoring - Position setpoint alive testing (SPA) - Enable Disabled = 0 Enabled = 1

Table 262: Data structure of safe machine options in Safety Release 1.10 and later, hardware upgrade 1.10.2.x and later (SMC_Acp_P3_1A- x_R110_OptsV2_typ, SMC_Acp_P3_2Ax_R110_OptsV2_typ, SMC_Acp_P3_3Ax_R110_OptsV2_typ)

Data type	ACOPOS P3 SafeMOTION EnDat 2.2				Name	Constant / Name in SafeDESIGNER
	Index	**Byte offset 1-axis module**	**Byte offset 2-axis module**	**Byte offset 3-axis module**		
USINT	**114**	Not used	339 .. 339	339 .. 339	UseSEM	Encoder monitoring - Safe Encoder Mounting Approved by user = 0 From motor data record = 1
DINT	**115**	Not used	340 .. 343	340 .. 343	EncMonitoringPosTol	Encoder monitoring - Position error tolerance
DINT	**116**	Not used	344 .. 347	344 .. 347	EncMonitoringSpeedTol	Encoder monitoring - Speed error tolerance
DINT	**117**	Not used	348 .. 351	348 .. 351	PositionTolerance	Standstill monitoring - Position tolerance
DINT	**118**	Not used	352 .. 355	352 .. 355	SpeedTolerance	Standstill monitoring - Speed tolerance
USINT	**119**	Not used	356 .. 356	356 .. 356	UseEarlyLimitMon	Early limit monitoring - Enable Disabled = 0 Enabled = 1
USINT	**120**	Not used	357 .. 357	357 .. 357	*AlignmentByte6*	*Alignment placeholder. Do not use!*
USINT	**121**	Not used	358 .. 358	358 .. 358	*AlignmentByte7*	*Alignment placeholder. Do not use!*
USINT	**122**	Not used	359 .. 359	359 .. 359	*AlignmentByte8*	*Alignment placeholder. Do not use!*
DINT	**123**	Not used	360 .. 363	360 .. 363	EarlyLimitMonTime	Early limit monitoring - Time
DINT	**124**	Not used	364 .. 367	364 .. 367	DecelerationRamp	Ramp monitoring - Speed deceleration limit
DINT	**125**	Not used	368 .. 371	368 .. 371	DelayRampMonitoring	Ramp monitoring - Enable delay time
USINT	**126**	Not used	372 .. 372	372 .. 372	SelectSTO1channel	STO1 - Channel Highside = 0 Lowside = 1
USINT	**127**	Not used	373 .. 373	373 .. 373	*AlignmentByte9*	*Alignment placeholder. Do not use!*
USINT	**128**	Not used	374 .. 374	374 .. 374	*AlignmentByte10*	*Alignment placeholder. Do not use!*
USINT	**129**	Not used	375 .. 375	375 .. 375	*AlignmentByte11*	*Alignment placeholder. Do not use!*
USINT	**130**	Not used	376 .. 376	376 .. 376	UseRampMonitoringSS1	SS1 - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**131**	Not used	377 .. 377	377 .. 377	*AlignmentByte12*	*Alignment placeholder. Do not use!*
USINT	**132**	Not used	378 .. 378	378 .. 378	*AlignmentByte13*	*Alignment placeholder. Do not use!*
USINT	**133**	Not used	379 .. 379	379 .. 379	*AlignmentByte14*	*Alignment placeholder. Do not use!*
DINT	**134**	Not used	380 .. 383	380 .. 383	RampMonTimeSS1	SS1 - Ramp monitoring time
DINT	**135**	Not used	384 .. 387	384 .. 387	DelaySBC	SBC - Enable delay time
USINT	**136**	Not used	388 .. 388	388 .. 388	UseRampMonitoringSS2	SS2 - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**137**	Not used	389 .. 389	389 .. 389	*AlignmentByte15*	*Alignment placeholder. Do not use!*
USINT	**138**	Not used	390 .. 390	390 .. 390	*AlignmentByte16*	*Alignment placeholder. Do not use!*
USINT	**139**	Not used	391 .. 391	391 .. 391	*AlignmentByte17*	*Alignment placeholder. Do not use!*
DINT	**140**	Not used	392 .. 395	392 .. 395	RampMonTimeSS2	SS2 - Ramp monitoring time
DINT	**141**	Not used	396 .. 399	396 .. 399	AccelerationLimPos	SLA - Acceleration limit in positive direction
DINT	**142**	Not used	400 .. 403	400 .. 403	DecelerationLimPos	SLA - Deceleration limit in positive direction
DINT	**143**	Not used	404 .. 407	404 .. 407	AccelerationLimNeg	SLA - Acceleration limit in negative direction
DINT	**144**	Not used	408 .. 411	408 .. 411	DecelerationLimNeg	SLA - Deceleration limit in negative direction
DINT	**145**	Not used	412 .. 415	412 .. 415	DelaySLA	SLA - Enable delay time
USINT	**146**	Not used	416 .. 416	416 .. 416	UseSMS	SMS - Enable Enabled = 0 Disabled = 1
USINT	**147**	Not used	417 .. 417	417 .. 417	*AlignmentByte18*	*Alignment placeholder. Do not use!*
USINT	**148**	Not used	418 .. 418	418 .. 418	*AlignmentByte19*	*Alignment placeholder. Do not use!*
USINT	**149**	Not used	419 .. 419	419 .. 419	*AlignmentByte20*	*Alignment placeholder. Do not use!*
DINT	**150**	Not used	420 .. 423	420 .. 423	SpeedLimitSMS	SMS - Speed limit
DINT	**151**	Not used	424 .. 427	424 .. 427	SpeedLimitSLS1	SLS1 - Speed limit
DINT	**152**	Not used	428 .. 431	428 .. 431	SpeedLimitSLS2	SLS2 - Speed limit
DINT	**153**	Not used	432 .. 435	432 .. 435	SpeedLimitSLS3	SLS3 - Speed limit
DINT	**154**	Not used	436 .. 439	436 .. 439	SpeedLimitSLS4	SLS4 - Speed limit
USINT	**155**	Not used	440 .. 440	440 .. 440	UseRampMonitoringSLS	SLS - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**156**	Not used	441 .. 441	441 .. 441	*AlignmentByte21*	*Alignment placeholder. Do not use!*
USINT	**157**	Not used	442 .. 442	442 .. 442	*AlignmentByte22*	*Alignment placeholder. Do not use!*
USINT	**158**	Not used	443 .. 443	443 .. 443	*AlignmentByte23*	*Alignment placeholder. Do not use!*
DINT	**159**	Not used	444 .. 447	444 .. 447	RampMonTimeSLS1	SLS1 - Ramp monitoring - Time
DINT	**160**	Not used	448 .. 451	448 .. 451	RampMonTimeSLS2	SLS2 - Ramp monitoring - Time
DINT	**161**	Not used	452 .. 455	452 .. 455	RampMonTimeSLS3	SLS3 - Ramp monitoring - Time
DINT	**162**	Not used	456 .. 459	456 .. 459	RampMonTimeSLS4	SLS4 - Ramp monitoring - Time
DINT	**163**	Not used	460 .. 463	460 .. 463	DelaySDI	SDI - Enable delay time
DINT	**164**	Not used	464 .. 467	464 .. 467	SliPositionWindow	SLI - Position limit
DINT	**165**	Not used	468 .. 471	468 .. 471	SliToffDelay	SLI - Disable delay time

Table 262: Data structure of safe machine options in Safety Release 1.10 and later, hardware upgrade 1.10.2.x and later (SMC_Acp_P3_1A- x_R110_OptsV2_typ, SMC_Acp_P3_2Ax_R110_OptsV2_typ, SMC_Acp_P3_3Ax_R110_OptsV2_typ)

Data type	ACOPOS P3 SafeMOTION EnDat 2.2				Name	Constant / Name in SafeDESIGNER
	Index	Byte offset 1-axis module	Byte offset 2-axis module	Byte offset 3-axis module		
USINT	**166**	Not used	472 .. 472	472 .. 472	HomingMode	Homing - Mode Direct = 0 Reference switch = 1 Home offset = 2 Home offset with correction = 3
USINT	**167**	Not used	473 .. 473	473 .. 473	*AlignmentByte24*	*Alignment placeholder. Do not use!*
USINT	**168**	Not used	474 .. 474	474 .. 474	*AlignmentByte25*	*Alignment placeholder. Do not use!*
USINT	**169**	Not used	475 .. 475	475 .. 475	*AlignmentByte26*	*Alignment placeholder. Do not use!*
DINT	**170**	Not used	476 .. 479	476 .. 479	HomingPos	Homing - Home position or home offset
USINT	**171**	Not used	480 .. 480	480 .. 480	HomingRemanentSafePos	Homing - Enable RSP (Remanent safe position) Disabled = 0 Enabled = 1
USINT	**172**	Not used	481 .. 481	481 .. 481	HomingRefSwEdge	Homing - Edge of reference switch Negative = 0 Positive = 1
USINT	**173**	Not used	482 .. 482	482 .. 482	HomingTriggerDir	Homing - Trigger direction Negative = 0 Positive = 1
USINT	**174**	Not used	483 .. 483	483 .. 483	HomingRefPulse	Homing - Enable reference pulse Disabled = 0 Enabled = 1
USINT	**175**	Not used	484 .. 484	484 .. 484	HomingRefPBlock	Homing - Blocking distance
USINT	**176**	Not used	485 .. 485	485 .. 485	*AlignmentByte27*	*Alignment placeholder. Do not use!*
USINT	**177**	Not used	486 .. 486	486 .. 486	*AlignmentByte28*	*Alignment placeholder. Do not use!*
USINT	**178**	Not used	487 .. 487	487 .. 487	*AlignmentByte29*	*Alignment placeholder. Do not use!*
DINT	**179**	Not used	488 .. 491	488 .. 491	HomingMaxSpeed	Homing - Maximum trigger speed
DINT	**180**	Not used	492 .. 495	492 .. 495	HomingTMon	Homing - Monitoring time
USINT	**181**	Not used	496 .. 496	496 .. 496	UseSMP	SMP - Enable Enabled = 0 Disabled = 1
USINT	**182**	Not used	497 .. 497	497 .. 497	*AlignmentByte30*	*Alignment placeholder. Do not use!*
USINT	**183**	Not used	498 .. 498	498 .. 498	*AlignmentByte31*	*Alignment placeholder. Do not use!*
USINT	**184**	Not used	499 .. 499	499 .. 499	*AlignmentByte32*	*Alignment placeholder. Do not use!*
DINT	**185**	Not used	500 .. 503	500 .. 503	PosLimitMinSMP	SMP - Lower position limit
DINT	**186**	Not used	504 .. 507	504 .. 507	PosLimitMaxSMP	SMP - Upper position limit
DINT	**187**	Not used	508 .. 511	508 .. 511	PosLimitMinSLP	SLP - Lower position limit
DINT	**188**	Not used	512 .. 515	512 .. 515	PosLimitMaxSLP	SLP - Upper position limit
DINT	**189**	Not used	516 .. 519	516 .. 519	DelaySLP	SLP - Enable delay time
Axis3 - Only for ACOPOS P3 SafeMOTION 3-axis modules						
USINT	**190**	Not used	Not used	520 .. 520	UseAutoResetAtStartup	Automatic reset on start - Enable Enabled = 0 Disabled = 1
USINT	**191**	Not used	Not used	521 .. 521	FuncFailSafeMode	FFS - Mode STO = 0 STO1 and STO with time delay = 1
USINT	**192**	Not used	Not used	522 .. 522	ucFuncFailSafeEncErrMode	FFS - Caused by encoder error Always = 0 Only if safety functions requiring an encoder are enabled = 1
USINT	**193**	Not used	Not used	523 .. 523	BMMode	BM - Mode Off = 0 Prev. enabled SF = 1 Prev. enabled and configured SF = 2 Configured SF = 3
DINT	**194**	Not used	Not used	524 .. 527	FuncFailSafeDelaySTO	FFS - STO Enable delay time
DINT	**195**	Not used	Not used	528 .. 531	FuncFailSafeDelayBrk	FFS - Delay time until the brake engages
USINT	**196**	Not used	Not used	532 .. 532	EncoderType	EUS - Encoder type Encoder used = 1 Encoder not used = 0
USINT	**197**	Not used	Not used	533 .. 533	*AlignmentByte2*	*Alignment placeholder. Do not use!*
USINT	**198**	Not used	Not used	534 .. 534	*AlignmentByte3*	*Alignment placeholder. Do not use!*
USINT	**199**	Not used	Not used	535 .. 535	*AlignmentByte4*	*Alignment placeholder. Do not use!*
DINT	**200**	Not used	Not used	536 .. 539	ScaleRevo	EUS - Count of physical reference system
DINT	**201**	Not used	Not used	540 .. 543	ScaleUnits	EUS - Units per count of physical reference system
DINT	**202**	Not used	Not used	544 .. 547	ScaleDirection	EUS - Counting direction Default = 0 Inverse = 1
DINT	**203**	Not used	Not used	548 .. 551	ScaleLength	EUS - Length of physical reference system for linear encoder
DINT	**204**	Not used	Not used	552 .. 555	ScaleNormSpeedMax	EUS - Maximum speed to normalize speed range
DINT	**205**	Not used	Not used	556 .. 559	AccelerationMax	EUS - Encoder acceleration limit

Table 262: Data structure of safe machine options in Safety Release 1.10 and later, hardware upgrade 1.10.2.x and later (SMC_Acp_P3_1A- x_R110_OptsV2_typ, SMC_Acp_P3_2Ax_R110_OptsV2_typ, SMC_Acp_P3_3Ax_R110_OptsV2_typ)

Data type	ACOPOS P3 SafeMOTION EnDat 2.2				Name	Constant / Name in SafeDESIGNER
	Index	**Byte off-set 1-axis module**	**Byte off-set 2-axis module**	**Byte offset 3-axis module**		
USINT	**206**	Not used	Not used	560 .. 560	UseEncPosMon	Encoder monitoring - Position error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**207**	Not used	Not used	561 .. 561	UseEncSpeedMon	Encoder monitoring - Speed error monitoring - Enable Disabled = 0 Enabled = 1
USINT	**208**	Not used	Not used	562 .. 562	UseSetPosAliveTest	Encoder monitoring - Position setpoint alive testing (SPA) - Enable Disabled = 0 Enabled = 1
USINT	**209**	Not used	Not used	563 .. 563	UseSEM	Encoder monitoring - Safe Encoder Mounting Approved by user = 0 From motor data record = 1
DINT	**210**	Not used	Not used	564 .. 567	EncMonitoringPosTol	Encoder monitoring - Position error tolerance
DINT	**211**	Not used	Not used	568 .. 571	EncMonitoringSpeedTol	Encoder monitoring - Speed error tolerance
DINT	**212**	Not used	Not used	572 .. 575	PositionTolerance	Standstill monitoring - Position tolerance
DINT	**213**	Not used	Not used	576 .. 579	SpeedTolerance	Standstill monitoring - Speed tolerance
USINT	**214**	Not used	Not used	580 .. 580	UseEarlyLimitMon	Early limit monitoring - Enable Disabled = 0 Enabled = 1
USINT	**215**	Not used	Not used	581 .. 581	*AlignmentByte6*	*Alignment placeholder. Do not use!*
USINT	**216**	Not used	Not used	582 .. 582	*AlignmentByte7*	*Alignment placeholder. Do not use!*
USINT	**217**	Not used	Not used	583 .. 583	*AlignmentByte8*	*Alignment placeholder. Do not use!*
DINT	**218**	Not used	Not used	584 .. 587	EarlyLimitMonTime	Early limit monitoring - Time
DINT	**219**	Not used	Not used	588 .. 591	DecelerationRamp	Ramp monitoring - Speed deceleration limit
DINT	**220**	Not used	Not used	592 .. 595	DelayRampMonitoring	Ramp monitoring - Enable delay time
USINT	**221**	Not used	Not used	596 .. 596	SelectSTO1channel	STO1 - Channel Highside = 0 Lowside = 1
USINT	**222**	Not used	Not used	597 .. 597	*AlignmentByte9*	*Alignment placeholder. Do not use!*
USINT	**223**	Not used	Not used	598 .. 598	*AlignmentByte10*	*Alignment placeholder. Do not use!*
USINT	**224**	Not used	Not used	599 .. 599	*AlignmentByte11*	*Alignment placeholder. Do not use!*
USINT	**225**	Not used	Not used	600 .. 600	UseRampMonitoringSS1	SS1 - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**226**	Not used	Not used	601 .. 601	*AlignmentByte12*	*Alignment placeholder. Do not use!*
USINT	**227**	Not used	Not used	602 .. 602	*AlignmentByte13*	*Alignment placeholder. Do not use!*
USINT	**228**	Not used	Not used	603 .. 603	*AlignmentByte14*	*Alignment placeholder. Do not use!*
DINT	**229**	Not used	Not used	604 .. 607	RampMonTimeSS1	SS1 - Ramp monitoring time
DINT	**230**	Not used	Not used	608 .. 611	DelaySBC	SBC - Enable delay time
USINT	**231**	Not used	Not used	612 .. 612	UseRampMonitoringSS2	SS2 - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**232**	Not used	Not used	613 .. 613	*AlignmentByte15*	*Alignment placeholder. Do not use!*
USINT	**233**	Not used	Not used	614 .. 614	*AlignmentByte16*	*Alignment placeholder. Do not use!*
USINT	**234**	Not used	Not used	615 .. 615	*AlignmentByte17*	*Alignment placeholder. Do not use!*
DINT	**235**	Not used	Not used	616 .. 619	RampMonTimeSS2	SS2 - Ramp monitoring time
DINT	**236**	Not used	Not used	620 .. 623	AccelerationLimPos	SLA - Acceleration limit in positive direction
DINT	**237**	Not used	Not used	624 .. 627	DecelerationLimPos	SLA - Deceleration limit in positive direction
DINT	**238**	Not used	Not used	628 .. 631	AccelerationLimNeg	SLA - Acceleration limit in negative direction
DINT	**239**	Not used	Not used	632 .. 635	DecelerationLimNeg	SLA - Deceleration limit in negative direction
DINT	**240**	Not used	Not used	636 .. 639	DelaySLA	SLA - Enable delay time
USINT	**241**	Not used	Not used	640 .. 640	UseSMS	SMS - Enable Enabled = 0 Disabled = 1
USINT	**242**	Not used	Not used	641 .. 641	*AlignmentByte18*	*Alignment placeholder. Do not use!*
USINT	**243**	Not used	Not used	642 .. 642	*AlignmentByte19*	*Alignment placeholder. Do not use!*
USINT	**244**	Not used	Not used	643 .. 643	*AlignmentByte20*	*Alignment placeholder. Do not use!*
DINT	**245**	Not used	Not used	644 .. 647	SpeedLimitSMS	SMS - Speed limit
DINT	**246**	Not used	Not used	648 .. 651	SpeedLimitSLS1	SLS1 - Speed limit
DINT	**247**	Not used	Not used	652 .. 655	SpeedLimitSLS2	SLS2 - Speed limit
DINT	**248**	Not used	Not used	656 .. 659	SpeedLimitSLS3	SLS3 - Speed limit
DINT	**249**	Not used	Not used	660 .. 663	SpeedLimitSLS4	SLS4 - Speed limit
USINT	**250**	Not used	Not used	664 .. 664	UseRampMonitoringSLS	SLS - Ramp monitoring - Enable Disabled = 0 Enabled = 1
USINT	**251**	Not used	Not used	665 .. 665	*AlignmentByte21*	*Alignment placeholder. Do not use!*
USINT	**252**	Not used	Not used	666 .. 666	*AlignmentByte22*	*Alignment placeholder. Do not use!*
USINT	**253**	Not used	Not used	667 .. 667	*AlignmentByte23*	*Alignment placeholder. Do not use!*
DINT	**254**	Not used	Not used	668 .. 671	RampMonTimeSLS1	SLS1 - Ramp monitoring - Time

Table 262: Data structure of safe machine options in Safety Release 1.10 and later, hardware upgrade 1.10.2.x and later (SMC_Acp_P3_1A- x_R110_OptsV2_typ, SMC_Acp_P3_2Ax_R110_OptsV2_typ, SMC_Acp_P3_3Ax_R110_OptsV2_typ)

Data type	ACOPOS P3 SafeMOTION EnDat 2.2				Name	Constant / Name in SafeDESIGNER
	Index	**Byte off-set 1-axis module**	**Byte off-set 2-axis module**	**Byte offset 3-axis module**		
DINT	**255**	Not used	Not used	672 .. 675	RampMonTimeSLS2	SLS2 - Ramp monitoring - Time
DINT	**256**	Not used	Not used	676 .. 679	RampMonTimeSLS3	SLS3 - Ramp monitoring - Time
DINT	**257**	Not used	Not used	680 .. 683	RampMonTimeSLS4	SLS4 - Ramp monitoring - Time
DINT	**258**	Not used	Not used	684 .. 687	DelaySDI	SDI - Enable delay time
DINT	**259**	Not used	Not used	688 .. 691	SliPositionWindow	SLI - Position limit
DINT	**260**	Not used	Not used	692 .. 695	SliToffDelay	SLI - Disable delay time
USINT	**261**	Not used	Not used	696 .. 696	HomingMode	Homing - Mode Direct = 0 Reference switch = 1 Home offset = 2 Home offset with correction = 3
USINT	**262**	Not used	Not used	697 .. 697	*AlignmentByte24*	*Alignment placeholder. Do not use!*
USINT	**263**	Not used	Not used	698 .. 698	*AlignmentByte25*	*Alignment placeholder. Do not use!*
USINT	**264**	Not used	Not used	699 .. 699	*AlignmentByte26*	*Alignment placeholder. Do not use!*
DINT	**265**	Not used	Not used	700 .. 703	HomingPos	Homing - Home position or home offset
USINT	**266**	Not used	Not used	704 .. 704	HomingRemanentSafePos	Homing - Enable RSP (Remanent safe position) Disabled = 0 Enabled = 1
USINT	**267**	Not used	Not used	705 .. 705	HomingRefSwEdge	Homing - Edge of reference switch Negative = 0 Positive = 1
USINT	**268**	Not used	Not used	706 .. 706	HomingTriggerDir	Homing - Trigger direction Negative = 0 Positive = 1
USINT	**269**	Not used	Not used	707 .. 707	HomingRefPulse	Homing - Enable reference pulse Disabled = 0 Enabled = 1
USINT	**270**	Not used	Not used	708 .. 708	HomingRefPBlock	Homing - Blocking distance
USINT	**271**	Not used	Not used	709 .. 709	*AlignmentByte27*	*Alignment placeholder. Do not use!*
USINT	**272**	Not used	Not used	710 .. 710	*AlignmentByte28*	*Alignment placeholder. Do not use!*
USINT	**273**	Not used	Not used	711 .. 711	*AlignmentByte29*	*Alignment placeholder. Do not use!*
DINT	**274**	Not used	Not used	712 .. 715	HomingMaxSpeed	Homing - Maximum trigger speed
DINT	**275**	Not used	Not used	716 .. 719	HomingTMon	Homing - Monitoring time
USINT	**276**	Not used	Not used	720 .. 720	UseSMP	SMP - Enable Enabled = 0 Disabled = 1
USINT	**277**	Not used	Not used	721 .. 721	*AlignmentByte30*	*Alignment placeholder. Do not use!*
USINT	**278**	Not used	Not used	722 .. 722	*AlignmentByte31*	*Alignment placeholder. Do not use!*
USINT	**279**	Not used	Not used	723 .. 723	*AlignmentByte32*	*Alignment placeholder. Do not use!*
DINT	**280**	Not used	Not used	724 .. 727	PosLimitMinSMP	SMP - Lower position limit
DINT	**281**	Not used	Not used	728 .. 731	PosLimitMaxSMP	SMP - Upper position limit
DINT	**282**	Not used	Not used	732 .. 735	PosLimitMinSLP	SLP - Lower position limit
DINT	**283**	Not used	Not used	736 .. 739	PosLimitMaxSLP	SLP - Upper position limit
DINT	**284**	Not used	Not used	740 .. 743	DelaySLP	SLP - Enable delay time
DINT	**285**	296 .. 299	520 .. 523	744 .. 747	SbtThreshold	SBT - Threshold (uA)
DINT	**286**	300 .. 303	524 .. 527	748 .. 751	SbtExternalLoad	SBT - External load (uA)
DINT	**287**	304 .. 307	528 .. 531	752 .. 755	SbtPositionTolerance	SBT - Position tolerance (units)
DINT	**288**	308 .. 311	532 .. 535	756 .. 759	SbtDuration	SBT - Maximum torque duration (us)
DINT	**289**	312 .. 315	536 .. 539	760 .. 763	SbtInterval	SBT - Interval (s)
DINT	**290**	316 .. 319	540 .. 543	764 .. 767	DelaySBT	SBT - Enable delay time (us)
DINT	**291**	320 .. 323	544 .. 547	768 .. 771	PolePairsMotor	Motor - Number of pole pairs
DINT	**292**	324 .. 327	548 .. 551	772 .. 775	DirectionMotor	Motor - Direction [-]
DINT	**293**	328 .. 331	552 .. 555	776 .. 779	StatorResistanceMotor	Motor - Stator resistance [mOhm]
DINT	**294**	332 .. 335	556 .. 559	780 .. 783	StatorInductanceMotor	Motor - Stator inductance [µH]
DINT	**295**	336 .. 339	560 .. 563	784 .. 787	TorqueConstantMotor	Motor - Torque constant [µNm/A]
DINT	**296**	340 .. 343	564 .. 567	788 .. 791	RatedSpeedMotor	Motor - Rated speed [units/s]
DINT	**297**	344 .. 347	568 .. 571	792 .. 795	CurrentStallMotor	Motor - Stall current [mA]
DINT	**298**	348 .. 351	572 .. 575	796 .. 799	CurrentRatedMotor	Motor - Rated current [mA]
DINT	**299**	352 .. 355	576 .. 579	800 .. 803	CurrentPeakMotor	Motor - Peak current [mA]
DINT	**300**	356 .. 359	580 .. 583	804 .. 807	TorqueStallMotor	Motor - Stall torque [mNm]
DINT	**301**	360 .. 363	584 .. 587	808 .. 811	TorquePeakMotor	Motor - Peak torque [mNm]
DINT	**302**	364 .. 367	588 .. 591	812 .. 815	MomentOfInertiaMotor	Motor - Moment of inertia (optional) [µkgm²]
DINT	**303**	368 .. 371	592 .. 595	816 .. 819	ExternalMomentofInertiaMotor	Motor - External moment of inertia (optional) [µkgm²]
DINT	**304**	372 .. 375	596 .. 599	820 .. 823	Reserved	Reserved
DINT	**305**	376 .. 379	600 .. 603	824 .. 827	SpeedTolSafeSpeedSSO	SSO - Speed tolerance safe speed [% motor rated speed]
DINT	**306**	380 .. 383	604 .. 607	828 .. 831	InverterSwitchingFreqSSO	SSO - Inverter switching frequency [Hz]
DINT	**307**	384 .. 387	608 .. 611	832 .. 835	InverterAdjAmplFactorSSO	SSO - Inverter adjustment amplification factor [*10^3]
DINT	**308**	388 .. 391	612 .. 625	836 .. 839	InverterAdjExponentSSO	SSO - Inverter adjustment exponent [*10^3/A]
DINT	**309**	392 .. 395	616 .. 619	840 .. 843	ExternalLoadEnabledSSO	SSO - External load enabled

Table 262: Data structure of safe machine options in Safety Release 1.10 and later, hardware upgrade 1.10.2.x and later (SMC_Acp_P3_1A- x_R110_OptsV2_typ, SMC_Acp_P3_2Ax_R110_OptsV2_typ, SMC_Acp_P3_3Ax_R110_OptsV2_typ)

Data type	ACOPOS P3 SafeMOTION EnDat 2.2				Name	Constant / Name in SafeDESIGNER
	Index	Byte offset 1-axis module	Byte offset 2-axis module	Byte offset 3-axis module		
DINT	**310**	396 .. 399	620 .. 623	844 .. 847	TorqueLimitSLT	SLT - Torque limit (mNm)
DINT	**311**	400 .. 403	624 .. 627	848 .. 851	DelaySLT	SLT - Enable delay time (us)
DINT	**312**	404 .. 407	628 .. 631	852 .. 855	DelayFFSBM	BM - Delay time to FFS (µs)
DINT	**313**	408 .. 411	632 .. 635	856 .. 859	ConfiguredSFBM	BM - Configured control word
Axis2 - Only for ACOPOS P3 SafeMOTION 2-axis and 3-axis modules						
DINT	**314**	Not used	636 .. 639	860 .. 863	SbtThreshold	SBT - Threshold (uA)
DINT	**315**	Not used	640 .. 643	864 .. 867	SbtExternalLoad	SBT - External load (uA)
DINT	**316**	Not used	644 .. 647	868 .. 871	SbtPositionTolerance	SBT - Position tolerance (units)
DINT	**317**	Not used	648 .. 651	872 .. 875	SbtDuration	SBT - Maximum torque duration (us)
DINT	**318**	Not used	652 .. 655	876 .. 879	SbtInterval	SBT - Interval (s)
DINT	**319**	Not used	656 .. 659	880 .. 883	DelaySBT	SBT - Enable delay time (us)
DINT	**320**	Not used	660 .. 663	884 .. 887	PolePairsMotor	Motor - Number of pole pairs
DINT	**321**	Not used	664 .. 667	888 .. 891	DirectionMotor	Motor - Direction [-]
DINT	**322**	Not used	668 .. 671	892 .. 895	StatorResistanceMotor	Motor - Stator resistance [mOhm]
DINT	**323**	Not used	672 .. 675	896 .. 899	StatorInductanceMotor	Motor - Stator inductance [µH]
DINT	**324**	Not used	676 .. 679	900 .. 903	TorqueConstantMotor	Motor - Torque constant [µNm/A]
DINT	**325**	Not used	680 .. 683	904 .. 907	RatedSpeedMotor	Motor - Rated speed [units/s]
DINT	**326**	Not used	684 .. 687	908 .. 911	CurrentStallMotor	Motor - Stall current [mA]
DINT	**327**	Not used	688 .. 691	912 .. 915	CurrentRatedMotor	Motor - Rated current [mA]
DINT	**328**	Not used	692 .. 695	916 .. 919	CurrentPeakMotor	Motor - Peak current [mA]
DINT	**329**	Not used	696 .. 699	920 .. 923	TorqueStallMotor	Motor - Stall torque [mNm]
DINT	**330**	Not used	700 .. 703	924 .. 927	TorquePeakMotor	Motor - Peak torque [mNm]
DINT	**331**	Not used	704 .. 707	928 .. 931	MomentOfInertiaMotor	Motor - Moment of inertia (optional) [µkgm²]
DINT	**332**	Not used	708 .. 711	932 .. 935	ExternalMomentofInertiaMotor	Motor - External moment of inertia (optional) [µkgm²]
DINT	**333**	Not used	712 .. 715	936 .. 939	Reserved	Reserved
DINT	**334**	Not used	716 .. 719	940 .. 943	SpeedTolSafeSpeedSSO	SSO - Speed tolerance safe speed [% motor rated speed]
DINT	**335**	Not used	720 .. 723	944 .. 947	InverterSwitchingFreqSSO	SSO - Inverter switching frequency [Hz]
DINT	**336**	Not used	724 .. 727	948 .. 951	InverterAdjAmplFactorSSO	SSO - Inverter adjustment amplification factor [*10^3]
DINT	**337**	Not used	728 .. 731	952 .. 955	InverterAdjExponentSSO	SSO - Inverter adjustment exponent [*10^3/A]
DINT	**338**	Not used	732 .. 735	956 .. 959	ExternalLoadEnabledSSO	SSO - External load enabled
DINT	**339**	Not used	736 .. 739	960 .. 963	TorqueLimitSLT	SLT - Torque limit (mNm)
DINT	**340**	Not used	740 .. 743	964 .. 967	DelaySLT	SLT - Enable delay time (us)
DINT	**341**	Not used	744 .. 747	968 .. 971	DelayFFSBM	BM - Delay time to FFS (µs)
DINT	**342**	Not used	748 .. 751	972 .. 975	ConfiguredSFBM	BM - Configured control word
Axis3 - Only for ACOPOS P3 SafeMOTION 3-axis modules						
DINT	**343**	Not used	Not used	976 .. 979	SbtThreshold	SBT - Threshold (uA)
DINT	**344**	Not used	Not used	980 .. 983	SbtExternalLoad	SBT - External load (uA)
DINT	**345**	Not used	Not used	984 .. 987	SbtPositionTolerance	SBT - Position tolerance (units)
DINT	**346**	Not used	Not used	988 .. 991	SbtDuration	SBT - Maximum torque duration (us)
DINT	**347**	Not used	Not used	992 .. 995	SbtInterval	SBT - Interval (s)
DINT	**348**	Not used	Not used	996 .. 999	DelaySBT	SBT - Enable delay time (us)
DINT	**349**	Not used	Not used	1000 .. 1003	PolePairsMotor	Motor - Number of pole pairs
DINT	**350**	Not used	Not used	1004 .. 1007	DirectionMotor	Motor - Direction [-]
DINT	**351**	Not used	Not used	1008 .. 1011	StatorResistanceMotor	Motor - Stator resistance [mOhm]
DINT	**352**	Not used	Not used	1012 .. 1015	StatorInductanceMotor	Motor - Stator inductance [µH]
DINT	**353**	Not used	Not used	1016 .. 1019	TorqueConstantMotor	Motor - Torque constant [µNm/A]
DINT	**354**	Not used	Not used	1020 .. 1023	RatedSpeedMotor	Motor - Rated speed [units/s]
DINT	**355**	Not used	Not used	1024 .. 1027	CurrentStallMotor	Motor - Stall current [mA]
DINT	**356**	Not used	Not used	1028 .. 1031	CurrentRatedMotor	Motor - Rated current [mA]
DINT	**357**	Not used	Not used	1032 .. 1035	CurrentPeakMotor	Motor - Peak current [mA]
DINT	**358**	Not used	Not used	1036 .. 1039	TorqueStallMotor	Motor - Stall torque [mNm]
DINT	**359**	Not used	Not used	1040 .. 1043	TorquePeakMotor	Motor - Peak torque [mNm]
DINT	**360**	Not used	Not used	1044 .. 1047	MomentOfInertiaMotor	Motor - Moment of inertia (optional) [µkgm²]
DINT	**361**	Not used	Not used	1048 .. 1051	ExternalMomentofInertiaMotor	Motor - External moment of inertia (optional) [µkgm²]
DINT	**362**	Not used	Not used	1052 .. 1055	Reserved	Reserved
DINT	**363**	Not used	Not used	1056 .. 1059	SpeedTolSafeSpeedSSO	SSO - Speed tolerance safe speed [% motor rated speed]
DINT	**364**	Not used	Not used	1060 .. 1063	InverterSwitchingFreqSSO	SSO - Inverter switching frequency [Hz]
DINT	**365**	Not used	Not used	1064 .. 1067	InverterAdjAmplFactorSSO	SSO - Inverter adjustment amplification factor [*10^3]
DINT	**366**	Not used	Not used	1068 .. 1071	InverterAdjExponentSSO	SSO - Inverter adjustment exponent [*10^3/A]
DINT	**367**	Not used	Not used	1072 .. 1075	ExternalLoadEnabledSSO	SSO - External load enabled
DINT	**368**	Not used	Not used	1076 .. 1079	TorqueLimitSLT	SLT - Torque limit (mNm)
DINT	**369**	Not used	Not used	1080 .. 1083	DelaySLT	SLT - Enable delay time (us)
DINT	**370**	Not used	Not used	1084 .. 1087	DelayFFSBM	BM - Delay time to FFS (µs)
DINT	**371**	Not used	Not used	1088 .. 1091	ConfiguredSFBM	BM - Configured control word

Table 262: Data structure of safe machine options in Safety Release 1.10 and later, hardware upgrade 1.10.2.x and later (SMC_Acp_P3_1A- x_R110_OptsV2_typ, SMC_Acp_P3_2Ax_R110_OptsV2_typ, SMC_Acp_P3_3Ax_R110_OptsV2_typ)

In order for the SafeMOTION module to interpret and verify the data correctly, information regarding module type, size and version must be entered in the structure. The structure elements "StructInfoAxisTypeID", "StructInfoSize" and "StructInfoVersion" are provided for this purpose.

For these structure elements, the correct values must be entered for the module type and structure version being used.

Variable	ACOPOSmulti SafeMOTION EnDat 2.2	ACOPOSmulti SafeMOTION SinCos	ACOPOSmotor SafeMOTION	ACOPOS P3 SafeMOTION		
				1-axis module	2-axis module	3-axis module
StructInfoAxisTypeID	1	2	1	3	4	5
StructInfoSize	196	220	196	224	448	672
StructInfoVersion	4	5	4	6	7	8

Safety Release 1.10 and later, hardware upgrade 1.10.2.x and later:

Variable	ACOPOSmulti SafeMOTION EnDat 2.2	ACOPOSmulti SafeMOTION SinCos	ACOPOSmotor SafeMOTION	ACOPOS P3 SafeMOTION		
				1-axis module	2-axis module	3-axis module
StructInfoAxisTypeID	1	2	1	3	4	5
StructInfoSize	204	228	196	340	680	1020
StructInfoVersion	13	12	4	9	10	11

Danger!

Entering the wrong values will cause the data to be interpreted incorrectly and may result in dangerous situations when using the SafeMOTION module.

6.5 LED status indicators

For ACOPOSmulti SafeMOTION inverter modules, see 2.2 "Status indicators" on page 30.

For ACOPOSmotor SafeMOTION modules, see 3.2 "Status indicators" on page 169.

For ACOPOS P3 SafeMOTION servo drives, see 4.1.2.1 "Status indicators" on page 207.

6.6 SafeMOTION register description

6.6.1 Parameters in the I/O configuration of the SafeMOTION module

Group: Function model

Parameter	Unit	Description	Default value
Function model	---	This parameter is reserved for future functional expansions.	Default

Table 263: SafeMOTION I/O configuration parameters: Function model

<table>
<tr><th>Parameter</th><th>Description</th><th>Default value</th><th>Unit</th></tr>
<tr><td rowspan="2">Module supervised</td><td>System behavior when a module is missing</td><td>Off</td><td>-</td></tr>
<tr><td colspan="3"><table><tr><th>Parameter value</th><th>Description</th></tr><tr><td>On</td><td>A missing module causes service mode to be activated.</td></tr><tr><td>Off</td><td>A missing module is ignored.</td></tr></table></td></tr>
<tr><td>SafeDOMAIN ID</td><td>In applications with multiple SafeLOGIC controllers, this parameter specifies the module's association with a particular SafeLOGIC controller.
• Permissible values: 1 to 1024</td><td>Assigned automatically</td><td>-</td></tr>
<tr><td>SafeNODE ID</td><td>Unique safety address of the module
• Permissible values: 2 to 1023</td><td>Assigned automatically</td><td>-</td></tr>
</table>

Table 264: I/O configuration parameters: General

Group: Extended

Parameter	Unit	Description	Default value
Turn-off delay in µs	[µs]	This parameter defines the delay before the SafeMOTION module should turn off if POWERLINK communication is lost. *This parameter is obsolete in hardware upgrade 1.10.2.x and later! The functionality is replaced by the blackout mode!*	0

Table 265: SafeMOTION I/O configuration parameters: Extended

Group: Encoders

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th></tr>
<tr><td rowspan="2">Encoder model</td><td rowspan="2">-</td><td>
SafeMOTION EnDat 2.2
Selects the encoder system and corresponding parameters
<table>
<tr><th>Parameter value</th><th>Description</th></tr>
<tr><td>EnDat 2.2 encoder</td><td>Configuration for an EnDat 2.1 encoder</td></tr>
<tr><td>Encoder not used</td><td>No encoder active</td></tr>
</table>
</td><td>EnDat 2.2 encoder</td></tr>
<tr><td>
SafeMOTION SinCos
Selects the encoder system and corresponding parameters
<table>
<tr><th>Parameter value</th><th>Description</th></tr>
<tr><td>EnDat 2.1 encoder</td><td>Configuration for an EnDat 2.1 encoder</td></tr>
<tr><td>SSI absolute encoder</td><td>Configuration for an SSI absolute encoder
Encoder scale: Increments per encoder revolution
SSI number of leading zeros
SSI number of data bits
SSI data coding
SSI parity check
Baud rate [kbaud]</td></tr>
<tr><td>SSI sinusoidal encoder</td><td>Configuration for an SSI sinusoidal encoder
Encoder scale: Increments per encoder revolution
SSI number of leading zeros
SSI number of data bits
SSI data coding
Serial resolution per sine period
Phasing of the serial position
Baud rate [kbaud]</td></tr>
<tr><td>Sine encoder</td><td>Configuration for a sinusoidal encoder
Encoder scale: Increments per encoder revolution</td></tr>
<tr><td>Sinusoidal encoder with DCM</td><td>Configuration for a sinusoidal encoder
Encoder scale: Increments per encoder revolution
DCM general distance [pulses]
DCM distance difference [pulses]</td></tr>
<tr><td>Encoder not used</td><td>No encoder active</td></tr>
</table>
</td><td>EnDat 2.1 encoder</td></tr>
</table>

Table 266: SafeMOTION parameter I/O configuration: Encoder (only ACOPOSmulti SafeMOTION EnDat 2.2 and ACOPOSmulti SafeMOTION SinCos)

Information:

For ACOPOS P3 SafeMOTION servo drives, the encoder group is located under the configuration of the power inverter.

The following settings are only available for ACOPOS P3 SafeMOTION servo drives:

Group: Safety features: Axis 1

These settings make it possible to hide parameters for unused function sets in SafeDESIGNER.

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th></tr>
<tr><td>Basic function set</td><td>-</td><td>Always enabled</td><td>Enabled</td></tr>
<tr><td>Speed function set</td><td>-</td><td>Makes it possible to hide the configuration parameters of the speed function set in SafeDESIGNER
<table>
<tr><th>Parameter value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>Configuration parameters are available.</td></tr>
<tr><td>Disabled</td><td>Configuration parameters are hidden.</td></tr>
</table></td><td>Enabled</td></tr>
<tr><td>Advanced function set</td><td>-</td><td>Makes it possible to hide the configuration parameters of the advanced function set in SafeDESIGNER
<table>
<tr><th>Parameter value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>Configuration parameters are available.</td></tr>
<tr><td>Disabled</td><td>Configuration parameters are hidden.</td></tr>
</table></td><td>Enabled</td></tr>
<tr><td>Position function set</td><td>-</td><td>Makes it possible to hide the configuration parameters of the position function set in SafeDESIGNER
<table>
<tr><th>Parameter value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>Configuration parameters are available.</td></tr>
<tr><td>Disabled</td><td>Configuration parameters are hidden.</td></tr>
</table></td><td>Enabled</td></tr>
</table>

Table 267: SafeMOTION I/O configuration parameters: Safety features: Axis 1

Information:

Group: Safety features: Axis 2 applies to 1-axis, 2-axis and 3-axis modules.

Group: Safety features: Axis 2

These settings make it possible to hide parameters for unused function sets in SafeDESIGNER.

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th></tr>
<tr><td>Basic function set</td><td>-</td><td>Always enabled</td><td>Enabled</td></tr>
<tr><td>Speed function set</td><td>-</td><td>Makes it possible to hide the configuration parameters of the speed function set in SafeDESIGNER<table><tr><th>Parameter value</th><th>Description</th></tr><tr><td>Enabled</td><td>Configuration parameters are available.</td></tr><tr><td>Disabled</td><td>Configuration parameters are hidden.</td></tr></table></td><td>Enabled</td></tr>
<tr><td>Advanced function set</td><td>-</td><td>Makes it possible to hide the configuration parameters of the advanced function set in SafeDESIGNER<table><tr><th>Parameter value</th><th>Description</th></tr><tr><td>Enabled</td><td>Configuration parameters are available.</td></tr><tr><td>Disabled</td><td>Configuration parameters are hidden.</td></tr></table></td><td>Enabled</td></tr>
<tr><td>Position function set</td><td>-</td><td>Makes it possible to hide the configuration parameters of the position function set in SafeDESIGNER<table><tr><th>Parameter value</th><th>Description</th></tr><tr><td>Enabled</td><td>Configuration parameters are available.</td></tr><tr><td>Disabled</td><td>Configuration parameters are hidden.</td></tr></table></td><td>Enabled</td></tr>
</table>

Table 268: SafeMOTION I/O configuration parameters: Safety features: Axis 2

Information:

Group: Safety features: Axis 2 applies only to 2-axis and 3-axis modules.

Group: Safety features: Axis 3

These settings make it possible to hide parameters for unused function sets in SafeDESIGNER.

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th></tr>
<tr><td>Basic function set</td><td>-</td><td>Always enabled</td><td>Enabled</td></tr>
<tr><td>Speed function set</td><td>-</td><td>Makes it possible to hide the configuration parameters of the speed function set in SafeDESIGNER<table><tr><th>Parameter value</th><th>Description</th></tr><tr><td>Enabled</td><td>Configuration parameters are available.</td></tr><tr><td>Disabled</td><td>Configuration parameters are hidden.</td></tr></table></td><td>Enabled</td></tr>
<tr><td>Advanced function set</td><td>-</td><td>Makes it possible to hide the configuration parameters of the advanced function set in SafeDESIGNER<table><tr><th>Parameter value</th><th>Description</th></tr><tr><td>Enabled</td><td>Configuration parameters are available.</td></tr><tr><td>Disabled</td><td>Configuration parameters are hidden.</td></tr></table></td><td>Enabled</td></tr>
<tr><td>Position function set</td><td>-</td><td>Makes it possible to hide the configuration parameters of the position function set in SafeDESIGNER<table><tr><th>Parameter value</th><th>Description</th></tr><tr><td>Enabled</td><td>Configuration parameters are available.</td></tr><tr><td>Disabled</td><td>Configuration parameters are hidden.</td></tr></table></td><td>Enabled</td></tr>
</table>

Table 269: SafeMOTION I/O configuration parameters: Safety features: Axis 3

Information:

Group: Safety features: Axis 3 applies only to 3-axis modules.

6.6.2 Parameters in SafeDESIGNER

Group: Basic

<table>
<tr><th>Parameter</th><th>Description</th><th>Default value</th><th>Unit</th></tr>
<tr><td>Min. required firmware revision</td><td>This parameter is reserved for future functional expansions.</td><td>Basic release</td><td>-</td></tr>
<tr><td rowspan="2">Availability</td><td>This parameter can be used to configure the module as "optional". Optional modules do not have to be present, i.e. the SafeLOGIC controller will not indicate that these modules are not present. However, this parameter does not influence the module's signal or status data.</td><td>Permanent</td><td>-</td></tr>
<tr><td colspan="3">
<table>
<tr><th>Parameter value</th><th>Description</th></tr>
<tr><td>Permanent</td><td>This module is mandatory for the application.

The module must be in OPERATIONAL mode after startup, and safe communication with the SafeLOGIC controller must be established without errors (SafeModuleOK = SAFETRUE). Processing of the safety application on the SafeLOGIC controller is delayed after startup until this state is achieved for all modules with "Availability = Permanent".

After startup, module problems are indicated by a quickly blinking "MXCHG" LED on the SafeLOGIC controller. An entry is also made in the logbook.</td></tr>
<tr><td>Optional</td><td>The module is not required for the application.

The module is not taken into account during startup, which means the safety application is started regardless of whether the modules with "Availability = Optional" are in OPERATIONAL mode or if safe communication is properly established between these modules and the SafeLOGIC controller.

After startup, module problems are NOT indicated by a quickly blinking "MXCHG" LED on the SafeLOGIC controller. An entry is NOT made in the logbook.</td></tr>
<tr><td>Startup</td><td>This module is optional. The system determines how the module will proceed during startup.

If it is determined that the module is physically present during startup (regardless of whether it is in OPERATIONAL mode or not), then the module behaves as if "Availability = Permanent" is set.

If it is determined that the module is not physically present during startup, then the module behaves as if "Availability = Optional" is set.</td></tr>
<tr><td>Never</td><td>The module is not required for the application.

The module is not taken into account during startup, which means the safety application is started regardless of whether the modules with "Availability = Never" are physically present.

Unlike when "Availability = Optional" is configured, the module is not started with "Availability = Never", which optimizes system startup behavior.

After startup, module problems are NOT indicated by a quickly blinking "MXCHG" LED on the SafeLOGIC controller. An entry is NOT made in the logbook.</td></tr>
</table>
</td></tr>
</table>

Table 270: SafeDESIGNER parameters: Basic

Group: Safety Responsetime

<table>
<tr><th>Parameter</th><th>Description</th><th>Default value</th><th>Unit</th></tr>
<tr><td>Manual configuration</td><td>This parameter makes it possible to manually and individually configure the safety response time for the module.

The parameters for the safety response time are generally set in the same way for all stations involved in the application. For this reason, these parameters are configured for the SafeLOGIC controller in SafeDESIGNER. For application situations in which individual safety functions require optimal response time behavior, the parameters for the safety response time can be configured individually on the respective module.</td><td>No</td><td>-</td></tr>
<tr><td></td><td colspan="3"><table>
<tr><th>Parameter value</th><th>Description</th></tr>
<tr><td>Yes</td><td>Data from the module's "Safety response time" group is used to calculate the safety response time for the module's signals.</td></tr>
<tr><td>No</td><td>The parameters for the safety response time are taken from the "Safety response time" group on the SafeLOGIC controller.</td></tr>
</table></td></tr>
<tr><td>Safe data duration</td><td>This parameter specifies the maximum permissible data transmission time between the SafeLOGIC controller and SafeIO module.
For more information about the actual data transmission time, see Automation Help under Diagnostics and service -> Diagnostics tools -> Network analyzer -> Editor -> Calculation of safety runtime.
The following formula can be used as the lower limit:
"Value of the Network Analyzer" * 2 + SafeLOGIC cycle time * 2
The stability of the system cannot be ensured for smaller values.
• Permissible values: 2000 to 10,000,000 µs (corresponds to 2 ms to 10 s)</td><td>20000</td><td>µs</td></tr>
<tr><td>Additional tolerated packet loss</td><td>This parameter specifies the number of additional tolerated lost packets during data transfer.
• Permissible values: 0 to 10</td><td>1</td><td>Packets</td></tr>
<tr><td>Node guarding packets</td><td>This parameter specifies the maximum number of packets used for node guarding.
• Permissible values: 1 to 255
Note
• The larger the configured value, the greater the amount of asynchronous data traffic.
• This setting is not critical to safety functionality. The time for safely cutting off actuators is determined independently of this.</td><td>5</td><td>Packets</td></tr>
</table>

Table 271: SafeDESIGNER parameters: Safety response time

Information:

Safe parameters are divided into module-specific and axis-specific parameters. Module-specific parameter apply once per module, while axis-specific parameters apply once per axis.

Information:

The following SafeMOTION parameter groups are module-specific:

- **Safe machine options**

Information:

The following SafeMOTION parameter groups are axis-specific:

- **General settings - ...**
- **Basic functions - ...**
- **Speed functions - ...**
- **Advanced functions - ...**
- **Absolute position functions - ...**

Group: Safe machine options (previously *Additional Parameter*)

Parameter	Unit	Description	Default value	Used starting in Safety Release
Safe machine options - Enable (previously *Activate Safe Machine Options*)	Enabled/ Disabled	Activates/Deactivates the "Safe machine options" safety function	Disabled	R 1.9

Table 272: SafeMOTION parameter group: Safe machine options

Group: General settings - Automatic reset on start (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Used Starting in Safety Release</th></tr>
<tr><td>Automatic reset on start - Enable

(previously Automatic Reset at Startup)</td><td>Enabled/
Disabled</td><td>Activates automatic reset of the function block at startup
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>After startup, the module automatically changes to state OPERATIONAL (Startreset). The reset input does not have to be controlled!</td></tr>
<tr><td>Disabled</td><td>After startup, the module remains in an Init state until a positive edge of the reset input is detected.</td></tr>
</table></td><td>Disabled</td><td>R1.3</td></tr>
</table>

Table 273: SafeMOTION parameter group: General settings - Automatic reset on start

Danger!

Parameter "Automatic reset on start" enables/disables the restart interlock during startup or when a network failure occurs on a reestablished network connection.

If parameter "Automatic reset on start" is set to "Enabled", then the module automatically changes to state OPERATIONAL state (i.e. pulse disabling and the motor holding brake are enabled)!

Configuring an automatic restart can result in critical safety conditions. Take additional measures to ensure proper safety-related functionality.

Group: General settings - Behavior of Functional Fail Safe (FFS) (previously *Behavior of Functional Fail Safe*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Used Starting in Safety Release</th></tr>
<tr><td>FFS - Mode

(previously Behavior of Functional Fail Safe)</td><td>STO /
STO1 and STO with time delay</td><td>In the FUNCTIONAL FAIL SAFE state, STO and SBC are activated immediately, or STO1 is activated and then STO after a delay.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>STO</td><td>In the FUNCTIONAL FAIL SAFE state, STO and SBC are activated immediately.</td></tr>
<tr><td>STO1 and STO with time delay</td><td>In the FUNCTIONAL FAIL SAFE state, STO1 and SBC are activated first, and then STO after a delay.</td></tr>
</table></td><td>STO</td><td>R 1.3</td></tr>
<tr><td>FFS - STO Enable delay time

(previously Delay for STO in Functional Fail Safe [µs])</td><td>[µs]</td><td>Delay time between STO1 and STO (and SBC) in the FUNCTIONAL FAIL SAFE state</td><td>0</td><td>R 1.3</td></tr>
<tr><td>FFS - Delay time until brake engages

(previously Delay time until the brake engages [µs])</td><td>[µs]</td><td>Delay time before the brake engages
The second enable channel is activated after this delay time if STO1 and time-delayed STO and SBC are configured for FUNCTIONAL FAIL SAFE.</td><td>0</td><td>R 1.3</td></tr>
<tr><td>FFS - Caused by encoder error
(1.10.1.x for ACOPOSmulti SafeMOTION and hardware upgrade 1.10.2.x or later for ACOPOS P3 SafeMOTION)</td><td>Always / Only if safety functions requiring an encoder are enabled</td><td>Enable FUNCTIONAL FAIL SAFE on encoder error:
Always:
FFS occurs if at least one safety function that requires an encoder is used and an encoder error is present.
Only if safety functions requiring an encoder are enabled:
FFS occurs if at least one safety function that requires an encoder is active and an encoder error is present.</td><td>Always</td><td>R 1.10.1</td></tr>
</table>

Table 274: SafeMOTION parameter group: General settings - Behavior of Functional Fail Safe (FFS)

Group: General settings - Blackout Mode

Parameter	Unit	Description	Default value	Used starting with Safety Release
BM - Mode (hardware upgrade 1.10.2.x and later)	Off / Prev. enabled SF / Prev. enabled and configured SF / Configured SF	The blackout mode defines the behavior in case of network failure. **Value** – **Description** Off – In the event of a network failure, as before the axis enters state IDLE of the SafeMOTION module's state machine. Prev. enabled SF – The safety functions requested at the time of the network failure remain active during the blackout mode. Prev. enabled and configured SF – The safety functions requested at the time of the network failure remain active during the blackout mode; in addition, the safety functions configured in "BM - Configured safety functions" are requested. Configured SF – At the time of the network failure, the safety functions configured in "BM - Configured safety functions" are requested.	Off	R 1.10
BM - Delay time to FFS (hardware upgrade 1.10.2.x and later)	[µs]	Delay time between start of blackout mode (detection of network failure) and the change to state FUNCTIONAL FAIL SAFE	0	R 1.10
BM - Configured safety functions (hardware upgrade 1.10.2.x and later)	-	Configuration mask of the safety functions (additionally) requested in blackout mode. Control bit = 0 ... Safety function requested Control bit = 1 ... Safety function not requested	4294967295 (0xFFFF FFFF)	R 1.10

Table 275: SafeMOTION parameter group: General settings - Blackout Mode

Group: General settings - Encoder Unit System (previously *Encoder Unit System*)

Parameter	Unit	Description	Default value	Starting in Safety Release

EUS - Encoder type
 	
(previously *Encoder Type*)
(SSO starting with hardware upgrade 1.10.2.x)
	Rotary encoder /
	Linear encoder /
	Encoder used /
	Encoder not used /
	Safe Speed Observer - Rotatory / Safe Speed Observer - Linear
		Determines the type of encoder used:
		• ACOPOSmulti SafeMOTION SinCos *(Safety Release 1.7 and later)*
		  ° Rotary encoder
		  ° Linear encoder
		  ° Encoder not used: No encoder being used
		• ACOPOSmulti SafeMOTION EnDat 2.2 *(Safety Release 1.9 or later)*
		  ACOPOSmotor SafeMOTION *(Safety Release 1.10 or later)*
		  ° Encoder used: Safe encoder evaluation enabled
		  ° Encoder not used: Safe encoder evaluation disabled
		• ACOPOS P3 SafeMOTION *(Safety Release 1.10 and later)*
		  ° Encoder used: Safe encoder evaluation enabled
		  ° Encoder not used: Safe encoder evaluation disabled
		  ° Safe Speed Observer - Rotatory: SSO enabled for rotary systems (hardware upgrade 1.10.2.x and later)
		  ° Safe speed observer - Linear: SSO enabled for linear systems (hardware upgrade 1.10.2.x and later)
			Rotary encoder (SinCos)
			
			Encoder used (EnDat 2.2)
				R 1.7
				
				R 1.9

EUS - Number of signal periods (previously *Number of signal periods*) (only with ACOPOSmulti SafeMOTION SinCos)	-	Number of signal periods per revolution (rotary encoder) or length of the physical reference system (linear encoder)	1	R 1.7
EUS - Count of physical reference system (previously *Count of physical reference system*)	-	Rotary encoder unit scale: X revolutions Linear encoder unit scale: X reference lengths (reference length = length of the physical reference system) Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration). For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.	1	R 1.4

Table 276: SafeMOTION parameter group: General settings - Encoder Unit System

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>EUS - Units per count of physical reference system

(previously Units per count of physical reference system [units])</td><td>[units]</td><td>Rotary encoder unit scale: Units per x revolutions
Linear encoder unit scale: Units per x reference lengths

Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration). For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.</td><td>1000</td><td>R 1.4</td></tr>
<tr><td>EUS - Counting direction

(previously Counting direction)</td><td>Standard / Inverse</td><td>Counting direction of the position or speed<table><tr><th>Value</th><th>Description</th></tr><tr><td>Default</td><td>Encoder counting direction is equal to the counting direction of the unit system.</td></tr><tr><td>Inverse</td><td>Encoder counting direction is negative to the counting direction of the unit system.</td></tr></table></td><td>Default</td><td>R 1.3</td></tr>
<tr><td>EUS - Length of physical reference system for linear encoder

(previously Length of physical reference system for linear encoder (nm))</td><td>[nm]</td><td>For linear measurement systems, the length of a physical reference system is defined here.
This value is not used for rotary encoders, where the reference system is a single revolution.</td><td>1000000000</td><td>R 1.4</td></tr>
<tr><td>EUS - Maximum speed to normalize speed range

(previously Maximum speed to normalize the speed range (units/s))</td><td>[units/s]</td><td>Maximum speed to which the displayed speed should be normalized</td><td>32767</td><td>R 1.3</td></tr>
<tr><td>EUS - Encoder acceleration limit

(previously Maximum acceleration (rad/s² or mm/s²))</td><td>[rad/s²] or [mm/s²]</td><td>Maximum permissible encoder acceleration</td><td>100000</td><td>R 1.4</td></tr>
</table>

Table 276: SafeMOTION parameter group: General settings - Encoder Unit System

Information:

The physical drive speed is not permitted to exceed the value set for parameter "EUS - Maximum speed to normalize speed range"; otherwise, the SafeMOTION module will switch to the error state!

Danger!

If the manufacturer of the measuring instrument specifies a limitation of the maximum acceleration, this must be monitored by the SafeMOTION module. The acceleration to be monitored can be configured using parameter "EUS - Encoder acceleration limit".

Danger!

Incorrectly configuring the unit system can result in dangerous situations.
When validating the application, the monitored speed limits must be intentionally violated and their physical values tested! The same must also be done for the monitored direction of rotation!

Group: General settings - Motor (only available for ACOPOS P3 SafeMOTION in hardware upgrade 1.10.2.x or later)

Parameter	Unit	Description	Default value	Starting in Safety Release
Motor - Number of pole pairs (hardware upgrade 1.10.2.x and later)	-	Number of pole pairs on the rotor circumference	1	1.10
Motor - Direction*) (hardware upgrade 1.10.2.x and later)	Standard / Inverse	Direction of rotation of the motor	Standard	1.10
Motor - Stator resistance (hardware upgrade 1.10.2.x and later)	mOhm	Ohmic stator resistance measured between two connections (phase - phase) of the motor	0	1.10
Motor - Stator inductance (hardware upgrade 1.10.2.x and later)	µH	Stator inductance measured between two connections (phase - phase) of the motor	0	1.10
Motor - Torque constant (hardware upgrade 1.10.2.x and later)	µNm / A	Torque constant of the motor	0	1.10
Motor - Rated speed (hardware upgrade 1.10.2.x and later)	units/s	Nominal speed of the motor	0	1.10
Motor - Stall current (hardware upgrade 1.10.2.x and later)	mA	Stall current of the motor	0	1.10
Motor - Rated current (hardware upgrade 1.10.2.x and later)	mA	Nominal current of the motor	0	1.10

Table 277: SafeMOTION parameter group: General settings - Motor

Parameter	Unit	Description	Default value	Starting in Safety Release
Motor - Peak current (hardware upgrade 1.10.2.x and later)	mA	Peak current of the motor	0	1.10
Motor - Stall torque (hardware upgrade 1.10.2.x and later)	mNm	Stall torque of the motor that is output when the stall current is applied	0	1.10
Motor - Peak torque (hardware upgrade 1.10.2.x and later)	mNm	Peak torque of the motor that is briefly output when the peak current is applied	0	1.10
Motor - Moment of inertia (optional) (hardware upgrade 1.10.2.x and later)	µkgm²	Mass moment of inertia of the motor. Consists of the sum of the inertias of the rotor, encoder and holding brake.	0	1.10
Motor - External moment of inertia (optional) (hardware upgrade 1.10.2.x and later)	µkgm²	External mass moment of inertia, depends on the total external load	0	1.10

Table 277: SafeMOTION parameter group: General settings - Motor

*) The direction of rotation of the motor is not related to the counting direction of the speed ("EUS - Counting direction"), i.e. the direction of rotation of the motor can be changed explicitly in the non-safe application and must therefore also be taken into account in SafeDESIGNER.

Group: General settings - SSO (only available for ACOPOS P3 SafeMOTION in hardware upgrade 1.10.2.x or later)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SSO - Speed tolerance safe speed
(hardware upgrade 1.10.2.x and later)</td><td>‰ of the nominal speed of the motor</td><td>Permissible deviation of the observed safe speed from the actual encoder speed</td><td>10</td><td>1.10</td></tr>
<tr><td>SSO - Inverter switching frequency
(hardware upgrade 1.10.2.x and later)</td><td>Hz</td><td>Switching frequency of the servo drive</td><td>5000</td><td>1.10</td></tr>
<tr><td>SSO - Inverter adjustment amplification factor
(hardware upgrade 1.10.2.x and later)</td><td>10^{-3}</td><td>Correction of the normalized gain factor of the inverter characteristic curve</td><td>0</td><td>1.10</td></tr>
<tr><td>SSO - Inverter adjustment exponent
(hardware upgrade 1.10.2.x and later)</td><td>10^{-3} / A</td><td>Correction of the exponent of the inverter characteristic curve</td><td>0</td><td>1.10</td></tr>
<tr><td>SSO - External load - Enable
(hardware upgrade 1.10.2.x and later)</td><td>Enabled/Disabled</td><td>Uses external energies (external load or suspended axes) with an enabled observer
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>An external load / suspended load is used.</td></tr>
<tr><td>Disabled</td><td>No external load / suspended load is used.</td></tr>
</table></td><td>Enabled</td><td>1.10</td></tr>
</table>

Table 278: SafeMOTION parameter group: General settings - SSO

Group: General settings - Encoder monitoring (previously *Encoder Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Encoder monitoring - Safe Encoder Mounting (Hardware upgrade 1.10.3.x and later)</td><td>From motor data record / Approved by user</td><td>Status of the proof of fatigue strength of the encoder mounting<table><tr><th>Value</th><th>Description</th></tr><tr><td>From motor data record</td><td>The status of the encoder mounting is determined using the motor data record.</td></tr><tr><td>Approved by user</td><td>The user confirms safe encoder mounting / no mounting information available in the motor data record.</td></tr></table></td><td>From motor data record</td><td>R1.10</td></tr>
<tr><td>Encoder monitoring - Position error monitoring - Enable

(previously Encoder Position monitoring)</td><td>Enabled/
Disabled</td><td>Enables/Disables monitoring of the position lag error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error monitoring - Enable

(previously Encoder Speed monitoring)</td><td>Enabled/
Disabled</td><td>Activates/Deactivates monitoring of the speed error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position setpoint alive testing (SPA) - Enable

(previously Set position alive testing)</td><td>Enabled/
Disabled</td><td>Activates/Deactivates the monitor that detects whether the position setpoint generated on the SafeMOTION module is frozen.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Disabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position error tolerance

(previously Encoder monitoring Position tolerance (units))</td><td>[units]</td><td>Position lag error tolerance for shaft breakage monitoring</td><td>0</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error tolerance

(previously Encoder monitoring Speed tolerance (units/s))</td><td>[units/s]</td><td>Speed error tolerance for encoder monitoring</td><td>0</td><td>R1.3</td></tr>
</table>

Table 279: SafeMOTION parameter group: General settings - Encoder monitoring

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 280: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr>
<tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr>
</table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 281: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 282: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Basic functions - STO1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>STO1 - Channel

(previously Channel selection for One Channel STO (STO1))</td><td>High-side/
Low-side</td><td>Selects the high-side or low-side IGBT in the STO1 function
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>High-side</td><td>The high-side IGBTs are actuated with the function STO1.</td></tr>
<tr><td>Low-side</td><td>The low-side IGBTs are actuated with the function STO1.</td></tr>
</table></td><td>High-side</td><td>R 1.3</td></tr>
</table>

Table 283: SafeMOTION parameter group: Basic functions - STO1

Group: Basic functions - SS1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS1 - Ramp monitoring - Enable

(previously Rampmonitoring for SS1)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SS1 function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When transitioning to the safe state of the SS1 function, a deceleration ramp is monitored in addition to the configurable time.</td></tr><tr><td>Disabled</td><td>When transitioning to the safe state of the SS1 function, only a configurable time is monitored.</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SS1 (us))</td><td>[μs]</td><td>Deceleration ramp monitoring time for SS1</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 284: SafeMOTION parameter group: Basic functions - SS1

Group: Basic functions - SBC (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBC - Enable delay time (previously *Delay time to start SBC (us)*	[μs]	Delay time between the SBC request and activation of the safety function	0	R 1.3

Table 285: SafeMOTION parameter group: Basic functions - SBC

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SS2 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS2 - Ramp monitoring - Enable

(previously Rampmonitoring for SS2)</td><td>Enabled/
Disabled</td><td>Activates ramp monitoring (in addition to time-based monitoring) when the SS2 function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When changing to the safe state of the SS2 function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr><tr><td>Disabled</td><td>When changing to the safe state of the SS2 function, only a configurable time is monitored</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>Ramp Monitoring Time for SS2 (us)</td><td>[μs]</td><td>Deceleration ramp monitoring time for SS2</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 286: SafeMOTION parameter group: Speed functions - SS2

Group: Speed functions - SLA (previously *Safely Limited Acceleration*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLA - Acceleration limit in positive direction (previously *Safe acceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for acceleration in the positive direction of movement	0	R 1.9
SLA - Deceleration limit in positive direction (previously *Safe deceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for deceleration in the positive direction of movement	0	R 1.9
SLA - Acceleration limit in negative direction (previously *Safe acceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for acceleration in the negative direction of movement	0	R 1.9
SLA - Deceleration limit in negative direction (previously *Safe deceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for deceleration in the negative direction of movement	0	R 1.9
SLA - Enable delay time (previously *Delay time to start SLA (us)*)	[µs]	Delay time between the SLA request and activation of the safety function	0	R 1.9

Table 287: SafeMOTION parameter group: Speed functions - SLA

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SMS - Enable (previously *Safe Maximum Speed*)	Enabled/ Disabled	Activates the SMS safety function by configuration **Value** – **Description** Enabled – SMS activated Disabled – SMS deactivated	Enabled	R 1.3
SMS - Speed limit (previously *Maximum Speed for SMS (units/s)*)	[units/s]	Speed limit of the maximum speed (SMS)	0	R 1.3
SLS1 - Speed limit (previously *Safe Speedlimit 1 for SLS (units/s)*)	[units/s]	Speed limit 1 for SLS (SLS1)	0	R 1.3
SLS2 - Speed limit (previously *Safe Speedlimit 2 for SLS (units/s)*)	[units/s]	Speed limit 2 for SLS (SLS2)	0	R 1.3
SLS3 - Speed limit (previously *Safe Speedlimit 3 for SLS (units/s)*)	[units/s]	Speed limit 3 for SLS (SLS3)	0	R 1.3
SLS4 - Speed limit (previously *Safe Speedlimit 4 for SLS (units/s)*)	[units/s]	Speed limit 4 for SLS (SLS4)	0	R 1.3
SLS - Ramp monitoring - Enable (previously *Rampmonitoring for SLS*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested **Value** – **Description** Enabled – When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time Disabled – When changing to the safe state of the SLS function, only a configurable time is monitored	Enabled	R 1.3

Table 288: SafeMOTION parameter group: Speed functions - SMS/SLS

Parameter	Unit	Description	Default value	Starting in Safety Release
SLS1 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS1 (us)*)	[µs]	Deceleration ramp monitoring time for SLS1	0	R 1.3
SLS2 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS2 (us)*)	[µs]	Deceleration ramp monitoring time for SLS2	0	R 1.3
SLS2 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS3 (us)*)	[µs]	Deceleration ramp monitoring time for SLS3	0	R 1.3
SLS4 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS4 (us)*)	[µs]	Deceleration ramp monitoring time for SLS4	0	R 1.3

Table 288: SafeMOTION parameter group: Speed functions - SMS/SLS

Danger!

The respective monitored speed limit must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous speed cannot be exceeded in the event of error.
The dangerous speed must be determined by a risk analysis.

Information:

The following application rule must be observed:

LIM_{SOS} ≤ LIM_{SLS4} ≤ LIM_{SLS3} ≤ LIM_{SLS2} ≤ LIM_{SLS1} ≤ LIM_{SMS} ≤ EUS - Maximum speed to normalize speed range

This is required for setting priority of the safety functions on the SafeMOTION module.

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 289: SafeMOTION parameter group: Advanced functions - SDI

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Advanced functions - SLI (previously *Safely Limited Increment*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLI - Position limit (previously *Safe Increments (units)*)	[units]	Maximum movable increments when SLI is active	0	R 1.3
SLI - Disable delay time (previously *SLI Off Delay (µs)*)	[µs]	Switch off delay of SLI	0	R 1.3

Table 290: SafeMOTION parameter group: Advanced functions - SLI

Danger!

The maximum increment range must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SBT (previously *Safe Brake Test*) (only available for ACOPOSmulti SafeMOTION SinCos and ACOPOS P3 SafeMOTION (hardware upgrade 1.10.2.x or later)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBT - Threshold (previously *Safe Brake Test threshold (uA)*)	[µA]	Threshold value for the stator current that must be exceeded during the brake test	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - External load (previously *Safe Brake Test external load (uA)*)	[µA]	External load	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Position tolerance (previously *Safe Brake Test position tolerance (units)*)	[units]	Position tolerance	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Maximum torque duration (previously *Safe Brake Test maximum torque duration (us)*)	[µs]	Duration of the test for which the maximum torque must be present	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Test interval (previously *Safe Brake Test interval (s)*)	[s]	Retry interval for the safe brake test	28800	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Enable delay time (previously *Delay Time to start SBT (us)*)	[µs]	Delay time between the SBT request and activation of the safety function	0	R 1.7 SinCos R 1.10 ACOPOS P3

Table 291: SafeMOTION parameter group: Advanced functions - SBT

Group: Advanced functions - SLT (only available for ACOPOS P3 SafeMOTION in hardware upgrade 1.10.2.x or later)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLT - Torque limit	[mNm]	Torque limitation monitored during activation of SLT	0	R 1.10
SLT - Enable delay time	[µs]	Delay time between the SLT request and activation of the safety function	0	R 1.10

Table 292: SafeMOTION parameter group: Advanced functions - SLT

Group: Absolute position functions - Homing (previously *Homing*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Mode (previously *Mode*)	Direct / Reference switch / *Home Offset /* *Home offset with correction*	Selects the homing mode *Modes "Home offset" and "Home offset with correction" are only available for ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	Direct	R 1.4
Homing - Home position or home offset (previously *Home Position or Home Offset (units)*)	[units]	Home position or home offset	0	R 1.4
Homing - Enable RSP (Remanent safe position) *(previously Remanent safe position)*	*Enabled/ Disabled*	*Selects whether or not to use the remanent safe position* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*Disabled*	R 1.9
Homing - Edge of reference switch (previously *Edge of reference switch*)	Positive / Negative	Selects the switching edge for the reference switch The switching edge for the reference switch input is positive if the logical state of the reference switch changes from SAFEFALSE to SAFETRUE in the positive direction of movement.	Positive	R 1.4
Homing - Trigger direction (previously *Trigger direction*)	Positive / Negative	Selects the trigger direction If the homing procedure requires a movement, then this parameter specifies the direction for evaluating the reference switch / reference pulse.	Positive	R 1.4
Homing - Enable reference pulse *(previously Reference pulse)*	*Enabled/ Disabled*	*Selects whether or not to use a reference pulse for homing* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*Disabled*	R 1.4
Homing - Blocking distance *(previously Blocking distance (% encoder reference system))*	*%*	*Distance within which evaluation of the reference pulse will be suppressed.* *This is calculated starting at the configured reference switch edge and indicated as a percentage of the encoder reference system.* *A single revolution is used as the encoder reference system for rotary encoders.* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*0*	R 1.4
Homing - Maximum trigger speed (previously *Max. trigger speed (units/s)*)	[units/s]	Maximum permissible speed for evaluating the reference switch / reference pulse	0	R 1.4
Homing - Monitoring time (previously *Homing Monitoring Time (µs)*)	[µs]	Monitoring time for the homing procedure	0	R 1.4

Table 293: SafeMOTION parameter group: Absolute position functions - Homing

Group: Absolute position functions - SMP/SLP (previously *Safety Position Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SMP - Enable (previously *Safe Maximum Position*)	Enabled/ Disabled	Activates the SMP safety function from the configuration **Value** – **Description** Enabled – SMP is activated Disabled – SMP is deactivated	Disabled	R 1.4
SMP - Lower position limit (previously *Safe Lower Position Limit for SMP (units)*)	[units]	Lower position limit for the machine's full travel range	0	R 1.4
SMP - Upper position limit (previously *Safe Upper Position Limit for SMP (units)*)	[units]	Upper position limit for the machine's full travel range	0	R 1.4
SLP - Lower position limit (previously *Safe Lower Position Limit for SLP (units)*)	[units]	Lower position limit for the monitoring range	0	R 1.4
SLP - Upper position limit (previously *Safe Upper Position Limit for SLP (units)*)	[units]	Upper position limit for the monitoring range	0	R 1.4
SLP - Enable delay time (previously *Delay time to start SLP (us)*)	[µs]	Delay time between the SLP request and start of monitoring	0	R 1.4

Table 294: SafeMOTION parameter group: Absolute position functions - SMP/SLP

Danger!

The position limits being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement, a dangerous movement cannot occur in the event of a worst case scenario.

The dangerous movement must be determined by a risk analysis.

Information:

The following application rule must be observed:

$LIM_{SMP,NEG} \leq LIM_{SLP,NEG} \leq LIM_{SLP,POS} \leq LIM_{SMP,POS}$

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

6.6.3 Parameter names

Changed parameter names in Safety Release 1.10 and later

Parameter		
Previous name	**Name in Safety Release 1.10 and later**	**Formula symbols**
Basic	Basic	
Min_required_FW_Rev	Min required firmware revision	
Optional	Availability	
External_UDID	-	
Safety_Response_Time	Safety Responsetime	
Manual_Configuration	Manual Configuration	
Max_X2X_CycleTime_us	-	
Max_Powerlink_CycleTime_us	-	
Max_CPU_CrossLinkTask_CycleTime_us	-	
Min_X2X_CycleTime_us	-	
Min_Powerlink_CycleTime_us	-	
Min_CPU_CrossLinkTask_CycleTime_us	-	
Worst_Case_Response_Time_us	-	
-	Safe data duration	
-	Additional tolerated packet loss	
-	Node guarding packets	
Additional Parameter	Safe machine options	
Activate Safe Machine Options	Safe machine options - Enable	
General Settings	General settings - Automatic reset on start	
Automatic Reset at Startup	Automatic reset on start - Enable	
Behavior of Functional Fail Safe	General settings - Behavior of Functional Fail Safe (FFS)	
Behavior of Functional Fail Safe	FFS - Mode	
Delay for STO in Functional Fail Safe [µs]	FFS - STO Enable delay time	t_{FFS_STO}
Delay time until the brake engages [µs]	FFS - Delay time until brake engages	t_{FFS_BRAKE}
-	FFS - Caused by encoder error	
-	General settings - Blackout mode	
-	BM - Mode	
-	BM - Delay time to IDLE	
-	BM - Configured safety functions	
Encoder Unit System	General settings - Encoder Unit System (EUS)	
Encoder Type	EUS - Encoder type	
Number of signal periods	EUS - Number of signal periods	
Count of physical reference system	EUS - Count of physical reference system	
Units per count of physical reference system [units]	EUS - Units per count of physical reference system	
Counting direction	EUS - Counting direction	
Length of physical reference system for linear encoder (nm)	EUS - Length of physical reference system for linear encoder	
Maximum speed to normalize the speed range (units/s)	EUS - Maximum speed to normalize speed range	$v_{EUS\_MAX\_NORM}$
Maximum acceleration (rad/s² or mm/s²)	EUS - Encoder acceleration limit	$a_{EUS\_ENC\_L}$
-	General settings - Motor	
-	Motor - Number of pole pairs	
-	Motor - Direction	
-	Motor - Stator resistance	
-	Motor - Stator inductance	
-	Motor - Torque constant	k_T
-	Motor - Rated speed	
-	Motor - Stall current	I_0
-	Motor - Rated current	
-	Motor - Peak current	I_P
-	Motor - Stall torque	T_0
-	Motor - Peak torque	T_P
-	Motor - Moment of inertia	
-	Motor - External moment of inertia (optional)	
	General settings - SSO	
-	SSO - Speed tolerance safe speed	
-	SSO - Inverter switching frequency	
-	SSO - Inverter adjustment amplification factor	
-	SSO - Inverter adjustment exponent	
-	SSO - External load enabled	
Encoder Monitoring	General settings - Encoder monitoring	
-	Encoder monitoring - Safe Encoder Mounting	
Encoder Position monitoring	Encoder monitoring - Position error monitoring - Enable	
Encoder Speed monitoring	Encoder monitoring - Speed error monitoring - Enable	
Set position alive testing	Encoder monitoring - Position setpoint alive testing (SPA) - Enable	
Encoder Monitoring Tolerances	-	
Encoder monitoring Position tolerance (units)	Encoder monitoring - Position error tolerance	s_{EM_T}

Table 295: SafeMOTION parameters

Parameter		
Previous name	**Name in Safety Release 1.10 and later**	**Formula symbols**
Encoder monitoring Speed tolerance (units/s)	Encoder monitoring - Speed error tolerance	v_{EM_T}
Safety Standstill and Direction Tolerances	General settings - Standstill monitoring	
Speed Tolerance (units/s)	Standstill monitoring - Speed tolerance	v_{SM_T}
Position Tolerance (units)	Standstill monitoring - Position tolerance	s_{SM_T}
Early Limit Monitoring	General settings - Early limit monitoring	
Early Limit Monitoring	Early limit monitoring - Enable	
Early Limit Monitoring time	Early limit monitoring - Time	t_{ELM}
Safety Deceleration Ramp	General settings - Ramp monitoring	
Deceleration Ramp [units/s²]	Ramp monitoring - Speed deceleration limit	a_{RM_L}
Safety Additional Parameters	-	
Delay time to start ramp monitoring (us)	Ramp monitoring - Enable delay time	t_{RM_ED}
General Settings	Basic functions - STO1	
Channel selection for One Channel STO (STO1)	STO1 - Channel	
General Settings	Basic functions - SS1	
Rampmonitoring for SS1	SS1 - Ramp monitoring - Enable	
Safety Ramp Monitoring Times	-	
Ramp Monitoring Time for SS1 (us)	SS1 - Ramp monitoring - Time	t_{SS1_RM}
Safety Additional Parameters	Basic functions - SBC	
Delay time to start SBC (us)	SBC - Enable delay time	t_{SBC_ED}
General Settings	Speed functions - SS2	
Rampmonitoring for SS2	SS2 - Ramp monitoring - Enable	
Safety Ramp Monitoring Times	-	
Ramp Monitoring Time for SS2 (us)	SS2 - Ramp monitoring - Time	t_{SS2_RM}
Safely Limited Acceleration	Speed functions - SLA	
Safe acceleration limit for SLA (units/s²) in positive direction	SLA - Acceleration limit in positive direction	$a_{SLA\_ACC\_P\_L}$
Safe deceleration limit for SLA (units/s²) in positive direction	SLA - Deceleration limit in positive direction	$a_{SLA\_DEC\_P\_L}$
Safe acceleration limit for SLA (units/s²) in negative direction	SLA - Acceleration limit in negative direction	$a_{SLA\_ACC\_N\_L}$
Safe deceleration limit for SLA (units/s²) in negative direction	SLA - Deceleration limit in negative direction	$a_{SLA\_DEC\_N\_L}$
Safety Additional Parameters	-	
Delay time to start SLA (us)	SLA - Enable delay time	t_{SLA_ED}
General Settings	Speed functions - SMS/SLS	
Safe Maximum Speed	SMS - Enable	
Rampmonitoring for SLS	SLS - Ramp monitoring - Enable	
Safety Speed Limits	-	
Maximum Speed for SMS (units/s)	SMS - Speed limit	v_{SMS_L}
Safe Speedlimit 1 for SLS (units/s)	SLS1 - Speed limit	v_{SLS1_L}
Safe Speedlimit 2 for SLS (units/s)	SLS2 - Speed limit	v_{SLS2_L}
Safe Speedlimit 3 for SLS (units/s)	SLS3 - Speed limit	v_{SLS3_L}
Safe Speedlimit 4 for SLS (units/s)	SLS4 - Speed limit	v_{SLS4_L}
Safety Ramp Monitoring Times	-	
Ramp Monitoring Time for SLS1 (us)	SLS1 - Ramp monitoring - Time	t_{SLS1_RM}
Ramp Monitoring Time for SLS2 (us)	SLS2 - Ramp monitoring - Time	t_{SLS2_RM}
Ramp Monitoring Time for SLS3 (us)	SLS3 - Ramp monitoring - Time	t_{SLS3_RM}
Ramp Monitoring Time for SLS4 (us)	SLS4 - Ramp monitoring - Time	t_{SLS4_RM}
Safety Additional Parameters	Advanced functions - SDI	
Delay time to start SDI (us)	SDI - Enable delay time	t_{SDI_ED}
Safely Limited Increment	Advanced functions - SLI	
Safe Increments (units)	SLI - Position limit	s_{SLI_L}
SLI Off Delay (µs)	SLI - Disable delay time	t_{SLI_DD}
Safe Brake Test	Advanced functions - SBT	
Safe Brake Test threshold (uA)	SBT - Threshold	i_{SBT_TRESH}
Safe Brake Test external load (uA)	SBT - External load	i_{SBT_LOAD}
Safe Brake Test position tolerance (units)	SBT - Position tolerance	s_{SBT_L}
Safe Brake Test maximum torque duration (us)	SBT - Maximum torque duration	t_{SBT_D}
Safe Brake Test interval (s)	SBT - Test interval	t_{SBT_TI}
	Advanced functions - SLT	
-	SLT - Torque limit	T_{SLT_L}
-	SLT - Enable delay time	T_{SLT_ED}
Safety Additional Parameters	-	
Delay Time to start SBT (us)	SBT - Enable delay time	t_{SBT_ED}
Homing	Absolute position functions - Homing	
Mode	Homing - Mode	
Home Position or Home Offset (units)	Homing - Home position or home offset	s_{HOME}
Remanent Safe Position	Homing - Enable RSP (Remanent safe position)	
Edge of reference switch	Homing - Edge of reference switch	
Trigger direction	Homing - Trigger direction	
Reference pulse	Homing - Enable reference pulse	
Blocking distance (% encoder reference system)	Homing - Blocking distance	
Max. trigger speed (units/s)	Homing - Maximum trigger speed	v_{HOME_MAX}

Table 295: SafeMOTION parameters

Parameter		
Previous name	**Name in Safety Release 1.10 and later**	**Formula symbols**
Homing Monitoring Time (µs)	Homing - Monitoring time	t_{HOME_M}
General Settings	Absolute position functions - SMP/SLP	
Safe Maximum Position	SMP - Enable	
Safety Position Limits	-	
Safe Lower Positionlimit for SMP (units)	SMP - Lower position limit	s_{SMP_LL}
Safe Upper Positionlimit for SMP (units)	SMP - Upper position limit	s_{SMP_UL}
Safe Lower Positionlimit for SLP (units)	SLP - Lower position limit	s_{SLP_LL}
Safe Upper Positionlimit for SLP (units)	SLP - Upper position limit	s_{SLP_UL}
Safety Additional Parameters	-	
Delay time to start SLP (us)	SLP - Enable delay time	t_{SLP_ED}

Table 295: SafeMOTION parameters

Associated group name

6.6.4 Channel list
For ACOPOSmulti SafeMOTION and ACOPOSmotor SafeMOTION

Channel name	Starting with Safety Release	Access via Automation Studio	Access via SafeDESIGNER	Data type	Description
ModuleOK	R 1.3	Read	---	BOOL	Indicates if the module is OK
SerialNumber	R 1.3	Read [1]	---	UDINT	Module serial number
ModuleID	R 1.3	Read [1]	---	UINT	Module code
HardwareVariant	R 1.3	Read [1]	---	UINT	Hardware variant
FirmwareVersion	R 1.3	Read [2]	---	UINT	Module firmware version
UDID_low	R 1.3	(Read) [2]	---	UDINT	UDID, lower 4 bytes
UDID_high	R 1.3	(Read) [2]	---	UINT	UDID, upper 2 bytes
SafetyFWversion1	R 1.3	(Read) [2]	---	UINT	Firmware version of safety processor 1
SafetyFWversion2	R 1.3	(Read) [2]	---	UINT	Firmware version of safety processor 2
Diag1_Temp	R 1.3	(Read) [2]	---	UINT	Module temperature in °C
Diag1_24V	R 1.3	(Read) [2]	---	UINT	Voltage measurement µP1 - 24V
Diag1_3V3	R 1.3	(Read) [2]	---	UINT	Voltage measurement µP1 - 3V3
Diag1_5V	R 1.3	(Read) [2]	---	UINT	Voltage measurement µP1 - 5V
Diag2_24V	R 1.3	(Read) [2]	---	UINT	Voltage measurement µP2 - 24V
Diag2_3V3	R 1.3	(Read) [2]	---	UINT	Voltage measurement µP2 - 3V3
Diag2_5V	R 1.3	(Read) [2]	---	UINT	Voltage measurement µP2 - 5V
SafeModuleOK	R 1.3	---	Read	SAFEBOOL	Indicates if the safe communication channel is OK
SafetyActiveSTO	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of STO safety function (TRUE = safe state)
SafetyActiveSBC	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of SBC safety function (TRUE = safe state)
SafetyActiveSOS	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of SOS safety function (TRUE = safe state)
SafetyActiveSS1	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of SS1 safety function (TRUE = safe state)
SafetyActiveSS2	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of SS2 safety function (TRUE = safe state)
SafetyActiveSLS1	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of SLS1 safety function (TRUE = safe state)
SafetyActiveSLS2	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of SLS2 safety function (TRUE = safe state)
SafetyActiveSLS3	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of SLS3 safety function (TRUE = safe state)
SafetyActiveSL4	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of SLS4 safety function (TRUE = safe state)
SafetyActiveSTO1	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of STO1 safety function (TRUE = safe state)
SafetyActiveSDIpos	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of SDIpos safety function (TRUE = safe state)
SafetyActiveSLI	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of SLI safety function (TRUE = safe state)
SafetyActiveSDIneg	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of SDIneg safety function (TRUE = safe state)
SafetyActiveSLP	R 1.4	Read	(Read) [3]	SAFEBOOL	Status of SLP safety function (TRUE = safe state)
SafetyActiveSMP	R 1.4	Read	(Read) [3]	SAFEBOOL	Status of SMP safety function (TRUE = safe state)
SafePositionValid	R 1.4	Read	(Read) [3]	SAFEBOOL	Status of the safe position (TRUE = valid position referencing and no errors found)
SafetyActiveSLA	R 1.9	Read	(Read) [3]	SAFEBOOL	Status of the SLA safety function (TRUE = safe status)
StatusSetPosAlive	R 1.3	Read	---	SAFEBOOL	Status of position setpoint "Alive Testing" (TRUE = valid)
ReqHomingOK	R 1.9	(Read) [4]	(Read) [3]	SAFEBOOL	Feedback for homing in SafeDESIGNER (TRUE = safe position is valid and request for safe homing is TRUE)
AllReqFuncAct	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of the requested safety functions (TRUE = all requested safety functions are active)
SafetyActiveSDC	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of the delay monitor (TRUE = delay monitoring is active)
Operational	R 1.3	Read	---	SAFEBOOL	Status of the function block (TRUE = function block is in the state OPERATIONAL, SAFE or WAIT FOR CONFIRMATION)
NotErrENC	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of the safe encoder (FALSE = pending encoder error)
NotErrFUNC	R 1.3	Read	(Read) [3]	SAFEBOOL	Status of the SafeMOTION module (FALSE = SafeMOTION module is in the FUNCTIONAL FAIL SAFE error state)
ScaledSpeed	R 1.3	Read	(Read) [3]	SAFEINT	Safe scaled speed
SafePos	R 1.4	Read	(Read) [3]	SAFEDINT	Safe position
SafetyActiveSBT	R 1.7	Read	(Read) [3]	SAFEBOOL	SBT Active bit (TRUE = active)
SafetyStatusSBT	R 1.7	Read	(Read) [3]	SAFEBOOL	SBT Status bit (TRUE = valid)

Table 296: SafeMOTION channel list for ACOPOSmulti SafeMOTION and ACOPOSmotor SafeMOTION

Channel name	Starting with Safety Release	Access via Automation Studio	Access via SafeDESIGNER	Data type	Description
RSPValid	R 1.9	Read	(Read) 3)	SAFEBOOL	Remanent safe position is validated and saved (TRUE = safe position is saved, Power Off for homing with RSP is possible)
RequestSTO	R 1.3	(Read) 4)	(Write) 5)	SAFEBOOL	Selects/Deselects the STO safety function
RequestSBC	R 1.3	(Read) 4)	(Write) 5)	SAFEBOOL	Selects/Deselects the SBC safety function
RequestSOS	R 1.3	(Read) 4)	(Write) 5)	SAFEBOOL	Selects/Deselects the SOS safety function
RequestSS1	R 1.3	(Read) 4)	(Write) 5)	SAFEBOOL	Selects/Deselects the SS1 safety function
RequestSS2	R 1.3	(Read) 4)	(Write) 5)	SAFEBOOL	Selects/Deselects the SS2 safety function
RequestSLS1	R 1.3	(Read) 4)	(Write) 5)	SAFEBOOL	Selects/Deselects the SLS1 safety function
RequestSLS2	R 1.3	(Read) 4)	(Write) 5)	SAFEBOOL	Selects/Deselects the SLS2 safety function
RequestSLS3	R 1.3	(Read) 4)	(Write) 5)	SAFEBOOL	Selects/Deselects the SLS3 safety function
RequestSLS4	R 1.3	(Read) 4)	(Write) 5)	SAFEBOOL	Selects/Deselects the SLS4 safety function
RequestSTO1	R 1.3	(Read) 4)	(Write) 5)	SAFEBOOL	Selects/Deselects the STO1 safety function
RequestSDIpos	R 1.3	(Read) 4)	(Write) 5)	SAFEBOOL	Selects/Deselects the SDIpos safety function
RequestSLI	R 1.3	(Read) 4)	(Write) 5)	SAFEBOOL	Selects/Deselects the SLI safety function
RequestSDIneg	R 1.3	(Read) 4)	(Write) 5)	SAFEBOOL	Selects/Deselects the SDIneg safety function
RequestSLP	R 1.4	(Read) 4)	(Write) 5)	SAFEBOOL	Selects/Deselects the SLP safety function
RequestHoming	R 1.4	(Read) 4)	(Write) 5)	SAFEBOOL	Requests safe homing
ReferenceSwitch	R 1.4	(Read) 4)	(Write) 5)	SAFEBOOL	Safe input for using a reference switch
RequestSBT	R 1.7	(Read) 4)	(Write) 5)	SAFEBOOL	SBT control bit
RequestSLA	R 1.9	(Read) 4)	(Write) 5)	SAFEBOOL	Selects/Deselects the SLA safety function
SwitchHomingMode	R 1.9	(Read) 4)	(Write) 5)	SAFEBOOL	Activates homing with RSP (TRUE = RSP homing mode is active)
Activate	R 1.3	(Read) 4)	(Write) 5)	SAFEBOOL	Enables the function block
Reset	R 1.3	(Read) 4)	(Write) 5)	SAFEBOOL	Reset input to acknowledge the FUNCTIONAL FAIL SAFE state

Table 296: SafeMOTION channel list for ACOPOSmulti SafeMOTION and ACOPOSmotor SafeMOTION

1) Channel only visible if parameter "*Module Information*" has been set to "on".
2) This data is accessed in Automation Studio using the ASIOACC library.
3) This data is accessed indirectly via the outputs of the function blocks SF_SafeMC_BR, SF_SafeMC_BR_V2, SF_SafeMC_Speed_BR, SF_SafeMC_Position_BR or SF_SafeMC_Position_BR_V2.
4) This data can be accessed via NC Action or Trace.
5) This data is accessed indirectly via the inputs of the function blocks SF_SafeMC_BR, SF_SafeMC_BR_V2 or SF_SafeMC_BR_V3.

6.6.5 Channel list
For ACOPOS P3 SafeMOTION

Channel name	Starting with Safety Release	Access via Automation Studio	Access via SafeDESIGNER	Data type	Description
ModuleOK	R 1.10	Read	---	BOOL	Indicates if the module is OK
SerialNumber	R 1.10	Read[1)]	---	UDINT	Module serial number
ModuleID	R 1.10	Read[1)]	---	UINT	Module code
HardwareVariant	R 1.10	Read[1)]	---	UINT	Hardware variant
FirmwareVersion	R 1.10	Read[2)]	---	UINT	Module firmware version
UDID_low	R 1.10	(Read)[2)]	---	UDINT	UDID, lower 4 bytes
UDID_high	R 1.10	(Read)[2)]	---	UINT	UDID, upper 2 bytes
SafetyFWversion1	R 1.10	(Read)[2)]	---	UINT	Firmware version of safety processor 1
SafetyFWversion2	R 1.10	(Read)[2)]	---	UINT	Firmware version of safety processor 2
SCError	R 1.10	(Read)[2)]	---	USINT	Error in safety communication
SCErrorQuit	R 1.10	(Read)[2)]	---	UINT	Error in safety communication
SCErrorEnable	R 1.10	(Read)[2)]	---	UINT	Error in safety communication
Diag1_Temp	R 1.10	(Read)[2)]	---	INT	Module temperature in °C
Diag2_24V	R 1.10	(Read)[2)]	---	UINT	Voltage measurement µP2 - 24V
Diag2_3V3	R 1.10	(Read)[2)]	---	UINT	Voltage measurement µP2 - 3V3
Diag2_5V	R 1.10	(Read)[2)]	---	UINT	Voltage measurement µP2 - 5V
SafeModuleOK	R 1.10	---	Read	SAFEBOOL	Indicates if the safe communication channel is OK
For ACOPOS P3 SafeMOTION 1-axis, 2-axis and 3-axis modules					
AX1_StatusNotErrorFunc	R 1.10	Read	(Read)[3)]	SAFEBOOL	FUNCTIONAL FAIL SAFE status bit (FALSE = functional error) for axis 1
AX1_StatusOperational	R 1.10	Read	(Read)[3)]	SAFEBOOL	Function block axis 1 is in state OPERATIONAL.
AX1_StatusSTO	R 1.10	Read	(Read)[3)]	SAFEBOOL	STO status bit (TRUE = active)
AX1_StatusSBC	R 1.10	Read	(Read)[3)]	SAFEBOOL	SBC status bit (TRUE = active)
AX1_StatusSS1	R 1.10	Read	(Read)[3)]	SAFEBOOL	SS1 status bit (TRUE = active)
AX1_StatusNotErrorEnc	R 1.10	Read	(Read)[3)]	SAFEBOOL	Encoder error status bit (FALSE = encoder error)
AX1_StatusSTO1	R 1.10	Read	(Read)[3)]	SAFEBOOL	STO1 status bit (TRUE = active)
AX1_StatusSDC	R 1.10	Read	(Read)[3)]	SAFEBOOL	SDC status bit (TRUE = active)
AX1_StatusSOS	R 1.10	Read	(Read)[4)]	SAFEBOOL	SOS status bit (TRUE = active)
AX1_StatusSS2	R 1.10	Read	(Read)[4)]	SAFEBOOL	SS2 status bit (TRUE = active)
AX1_StatusSLA	R 1.10	Read	(Read)[4)]	SAFEBOOL	SLA status bit (TRUE = active)
AX1_StatusSLS1	R 1.10	Read	(Read)[4)]	SAFEBOOL	SLS1 status bit (TRUE = active)
AX1_StatusSLS2	R 1.10	Read	(Read)[4)]	SAFEBOOL	SLS2 status bit (TRUE = active)
AX1_StatusSLS3	R 1.10	Read	(Read)[4)]	SAFEBOOL	SLS3 status bit (TRUE = active)
AX1_StatusSLS4	R 1.10	Read	(Read)[4)]	SAFEBOOL	SLS4 status bit (TRUE = active)
AX1_StatusSDI_Pos	R 1.10	Read	(Read)[5)]	SAFEBOOL	SDI pos status bit (TRUE = active)
AX1_StatusSDI_Neg	R 1.10	Read	(Read)[5)]	SAFEBOOL	SDI neg status bit (TRUE = active)
AX1_StatusSLI	R 1.10	Read	(Read)[5)]	SAFEBOOL	SLI status bit (TRUE = active)
Ax1_StatusSBTValid	R1.10	Read	(Read)[5)]	SAFEBOOL	SBT Status bit (TRUE = Valid)
Ax1_StatusSBT	R1.10	Read	(Read)[5)]	SAFEBOOL	SBT Active bit (TRUE = Active)
AX1_StatusSLT	R1.10	Read	(Read)[5)]	SAFEBOOL	STL status bit (TRUE = Active)
AX1_StatusAllReqActive	R 1.10	Read	(Read)[5)]	SAFEBOOL	All requested safety functions are active
AX1_StatusHoming	R 1.10	Read	(Read)[6)]	SAFEBOOL	Safe position valid bit (TRUE = valid)
AX1_StatusRequestHomingOK	R 1.10	Read	(Read)[6)]	SAFEBOOL	Status of the request for safe homing
AX1_StatusSLP	R 1.10	Read	(Read)[6)]	SAFEBOOL	SLP status bit (TRUE = active)
AX1_StatusSMP	R 1.10	Read	(Read)[6)]	SAFEBOOL	SMP status bit (TRUE = active)
AX1_StatusRSPValid	R 1.10	Read	(Read)[6)]	SAFEBOOL	RSP Valid Bit
AX1_StatusSetPosAlive	R 1.10	Read	(Read)[6)]	SAFEBOOL	"Alive testing" of position setpoint is valid.
AX1_SafePOSITION_4Byte	R 1.10	Read	(Read)[8)]	SAFEBOOL	Safe position
AX1_ScaledSafeSPEED_2Byte	R 1.10	Read	(Read)[7)]	SAFEBOOL	Scaled safe speed
Only for ACOPOS P3 SafeMOTION 2-axis and 3-axis modules					
AX2_StatusNotErrorFunc	R 1.10	Read	(Read)[3)]	SAFEBOOL	FUNCTIONAL FAIL SAFE status bit (FALSE = functional error) for axis 2
AX2_StatusOperational	R 1.10	Read	(Read)[3)]	SAFEBOOL	Function block axis 2 is in state OPERATIONAL.
AX2_StatusSTO	R 1.10	Read	(Read)[3)]	SAFEBOOL	STO status bit (TRUE = active)
AX2_StatusSBC	R 1.10	Read	(Read)[3)]	SAFEBOOL	SBC status bit (TRUE = active)
AX2_StatusSS1	R 1.10	Read	(Read)[3)]	SAFEBOOL	SS1 status bit (TRUE = active)
AX2_StatusNotErrorEnc	R 1.10	Read	(Read)[3)]	SAFEBOOL	Encoder error status bit (FALSE = encoder error)
AX2_StatusSTO1	R 1.10	Read	(Read)[3)]	SAFEBOOL	STO1 status bit (TRUE = active)
AX2_StatusSDC	R 1.10	Read	(Read)[3)]	SAFEBOOL	SDC status bit (TRUE = active)
AX2_StatusSOS	R 1.10	Read	(Read)[4)]	SAFEBOOL	SOS status bit (TRUE = active)
AX2_StatusSS2	R 1.10	Read	(Read)[4)]	SAFEBOOL	SS2 status bit (TRUE = active)
AX2_StatusSLA	R 1.10	Read	(Read)[4)]	SAFEBOOL	SLA status bit (TRUE = active)
AX2_StatusSLS1	R 1.10	Read	(Read)[4)]	SAFEBOOL	SLS1 status bit (TRUE = active)
AX2_StatusSLS2	R 1.10	Read	(Read)[4)]	SAFEBOOL	SLS2 status bit (TRUE = active)
AX2_StatusSLS3	R 1.10	Read	(Read)[4)]	SAFEBOOL	SLS3 status bit (TRUE = active)
AX2_StatusSLS4	R 1.10	Read	(Read)[4)]	SAFEBOOL	SLS4 status bit (TRUE = active)
AX2_StatusSDI_Pos	R 1.10	Read	(Read)[5)]	SAFEBOOL	SDI pos status bit (TRUE = active)

Table 297: SafeMOTION channel list for ACOPOS P3 SafeMOTION

Channel name	Starting with Safety Release	Access via Automation Studio	Access via SafeDESIGNER	Data type	Description
AX2_StatusSDI_Neg	R 1.10	Read	(Read)[5]	SAFEBOOL	SDI neg status bit (TRUE = active)
AX2_StatusSLI	R 1.10	Read	(Read)[5]	SAFEBOOL	SLI status bit (TRUE = active)
Ax2_StatusSBTValid	R1.10	Read	(Read)[5]	SAFEBOOL	SBT Status bit (TRUE = Valid)
Ax2_StatusSBT	R1.10	Read	(Read)[5]	SAFEBOOL	SBT Active bit (TRUE = Active)
AX2_StatusSLT	R1.10	Read	(Read)[5]	SAFEBOOL	STL status bit (TRUE = Active)
AX2_StatusAllReqActive	R 1.10	Read	(Read)[5]	SAFEBOOL	All requested safety functions are active
AX2_StatusHoming	R 1.10	Read	(Read)[6]	SAFEBOOL	Safe position valid bit (TRUE = valid)
AX2_StatusRequestHomingOK	R 1.10	Read	(Read)[6]	SAFEBOOL	Status of the request for safe homing
AX2_StatusSLP	R 1.10	Read	(Read)[6]	SAFEBOOL	SLP status bit (TRUE = active)
AX2_StatusSMP	R 1.10	Read	(Read)[6]	SAFEBOOL	SMP status bit (TRUE = active)
AX2_StatusRSPValid	R 1.10	Read	(Read)[6]	SAFEBOOL	RSP Valid Bit
AX2_StatusSetPosAlive	R 1.10	Read	(Read)[6]	SAFEBOOL	"Alive testing" of position setpoint is valid.
AX2_SafePOSITION_4Byte	R 1.10	Read	(Read)[8]	SAFEBOOL	Safe position
AX2_ScaledSafeSPEED_2Byte	R 1.10	Read	(Read)[7]	SAFEBOOL	Scaled safe speed
Only for ACOPOS P3 SafeMOTION 3-axis modules					
AX3_StatusNotErrorFunc	R 1.10	Read	(Read)[3]	SAFEBOOL	FUNCTIONAL FAIL SAFE bit (FALSE = functional error) for axis 3
AX3_StatusOperational	R 1.10	Read	(Read)[3]	SAFEBOOL	Function block axis 2 is in state OPERATIONAL.
AX3_StatusSTO	R 1.10	Read	(Read)[3]	SAFEBOOL	STO status bit (TRUE = active)
AX3_StatusSBC	R 1.10	Read	(Read)[3]	SAFEBOOL	SBC status bit (TRUE = active)
AX3_StatusSS1	R 1.10	Read	(Read)[3]	SAFEBOOL	SS1 status bit (TRUE = active)
AX3_StatusNotErrorEnc	R 1.10	Read	(Read)[3]	SAFEBOOL	Encoder error status bit (FALSE = encoder error)
AX3_StatusSTO1	R 1.10	Read	(Read)[3]	SAFEBOOL	STO1 status bit (TRUE = active)
AX3_StatusSDC	R 1.10	Read	(Read)[3]	SAFEBOOL	SDC status bit (TRUE = active)
AX3_StatusSOS	R 1.10	Read	(Read)[4]	SAFEBOOL	SOS status bit (TRUE = active)
AX3_StatusSS2	R 1.10	Read	(Read)[4]	SAFEBOOL	SS2 status bit (TRUE = active)
AX3_StatusSLA	R 1.10	Read	(Read)[4]	SAFEBOOL	SLA status bit (TRUE = active)
AX3_StatusSLS1	R 1.10	Read	(Read)[4]	SAFEBOOL	SLS1 status bit (TRUE = active)
AX3_StatusSLS2	R 1.10	Read	(Read)[4]	SAFEBOOL	SLS2 status bit (TRUE = active)
AX3_StatusSLS3	R 1.10	Read	(Read)[4]	SAFEBOOL	SLS3 status bit (TRUE = active)
AX3_StatusSLS4	R 1.10	Read	(Read)[4]	SAFEBOOL	SLS4 status bit (TRUE = active)
AX3_StatusSDI_Pos	R 1.10	Read	(Read)[5]	SAFEBOOL	SDI pos status bit (TRUE = active)
AX3_StatusSDI_Neg	R 1.10	Read	(Read)[5]	SAFEBOOL	SDI neg status bit (TRUE = active)
AX3_StatusSLI	R 1.10	Read	(Read)[5]	SAFEBOOL	SLI status bit (TRUE = active)
Ax3_StatusSBTValid	R1.10	Read	(Read)[5]	SAFEBOOL	SBT Status bit (TRUE = Valid)
Ax3_StatusSBT	R1.10	Read	(Read)[5]	SAFEBOOL	SBT Active bit (TRUE = Active)
AX3_StatusSLT	R1.10	Read	(Read)[5]	SAFEBOOL	STL status bit (TRUE = Active)
AX3_StatusAllReqActive	R 1.10	Read	(Read)[5]	SAFEBOOL	All requested safety functions are active
AX3_StatusHoming	R 1.10	Read	(Read)[6]	SAFEBOOL	Safe position valid bit (TRUE = valid)
AX3_StatusRequestHomingOK	R 1.10	Read	(Read)[6]	SAFEBOOL	Status of the request for safe homing
AX3_StatusSLP	R 1.10	Read	(Read)[6]	SAFEBOOL	SLP status bit (TRUE = active)
AX3_StatusSMP	R 1.10	Read	(Read)[6]	SAFEBOOL	SMP status bit (TRUE = active)
AX3_StatusRSPValid	R 1.10	Read	(Read)[6]	SAFEBOOL	RSP Valid Bit
AX3_StatusSetPosAlive	R 1.10	Read	(Read)[6]	SAFEBOOL	"Alive testing" of position setpoint is valid.
AX3_SafePOSITION_4Byte	R 1.10	Read	(Read)[8]	SAFEBOOL	Safe position
AX3_ScaledSafeSPEED_2Byte	R 1.10	Read	(Read)[7]	SAFEBOOL	Scaled safe speed
For ACOPOS P3 SafeMOTION 1-axis, 2-axis and 3-axis modules					
AX1_ControlReset	R 1.10	(Read)[9]	(Write)[3]	SAFEBOOL	Reset bit
AX1_ControlActivate	R 1.10	(Read)[9]	(Write)[3]	SAFEBOOL	Activates the SafeMOTION component
AX1_ControlSTO	R 1.10	(Read)[9]	(Write)[3]	SAFEBOOL	STO control bit
AX1_ControlSBC	R 1.10	(Read)[9]	(Write)[3]	SAFEBOOL	SBC control bit
AX1_ControlSS1	R 1.10	(Read)[9]	(Write)[3]	SAFEBOOL	SS1 control bit
AX1_ControlSTO1	R 1.10	(Read)[9]	(Write)[3]	SAFEBOOL	STO1 control bit
AX1_ControlSOS	R 1.10	(Read)[9]	(Write)[4]	SAFEBOOL	SOS control bit
AX1_ControlSS2	R 1.10	(Read)[9]	(Write)[4]	SAFEBOOL	SS2 control bit
AX1_ControlSLA	R 1.10	(Read)[9]	(Write)[4]	SAFEBOOL	SLA control bit
AX1_ControlSLS1	R 1.10	(Read)[9]	(Write)[4]	SAFEBOOL	SLS1 control bit
AX1_ControlSLS2	R 1.10	(Read)[9]	(Write)[4]	SAFEBOOL	SLS2 control bit
AX1_ControlSLS3	R 1.10	(Read)[9]	(Write)[4]	SAFEBOOL	SLS3 control bit
AX1_ControlSLS4	R 1.10	(Read)[9]	(Write)[4]	SAFEBOOL	SLS4 control bit
AX1_ControlSDI_Pos	R 1.10	(Read)[9]	(Write)[5]	SAFEBOOL	SDI pos control bit
AX1_ControlSDI_Neg	R 1.10	(Read)[9]	(Write)[5]	SAFEBOOL	SDI neg control bit
AX1_ControlSLI	R 1.10	(Read)[9]	(Write)[5]	SAFEBOOL	SLI control bit
AX1_ControlSBT	R1.10	(Read)[9]	(Write)[5]	SAFEBOOL	SBT control bit
AX1_ControlSLT	R1.10	(Read)[9]	(Write)[5]	SAFEBOOL	SLT control bit
AX1_ControlHoming	R 1.10	(Read)[9]	(Write)[6]	SAFEBOOL	Homing control bit
AX1_ControlReferenceSwitch	R 1.10	(Read)[9]	(Write)[6]	SAFEBOOL	Reference switch bit
AX1_ControlSLP	R 1.10	(Read)[9]	(Write)[6]	SAFEBOOL	SLP control bit
AX1_ControlSwitchHomingMode	R 1.10	(Read)[9]	(Write)[6]	SAFEBOOL	Switching between the configured homing mode (SAFE FALSE) and restore remanent safe position (SAFE TRUE)

Table 297: SafeMOTION channel list for ACOPOS P3 SafeMOTION

Channel name	Starting with Safety Release	Access via Automation Studio	Access via SafeDESIGNER	Data type	Description
Only for ACOPOS P3 SafeMOTION 2-axis and 3-axis modules					
AX2_ControlReset	R 1.10	(Read)[9)]	(Write)[3)]	SAFEBOOL	Reset bit
AX2_ControlActivate	R 1.10	(Read)[9)]	(Write)[3)]	SAFEBOOL	Activates the SafeMOTION component
AX2_ControlSTO	R 1.10	(Read)[9)]	(Write)[3)]	SAFEBOOL	STO control bit
AX2_ControlSBC	R 1.10	(Read)[9)]	(Write)[3)]	SAFEBOOL	SBC control bit
AX2_ControlSS1	R 1.10	(Read)[9)]	(Write)[3)]	SAFEBOOL	SS1 control bit
AX2_ControlSTO1	R 1.10	(Read)[9)]	(Write)[3)]	SAFEBOOL	STO1 control bit
AX2_ControlSOS	R 1.10	(Read)[9)]	(Write)[4)]	SAFEBOOL	SOS control bit
AX2_ControlSS2	R 1.10	(Read)[9)]	(Write)[4)]	SAFEBOOL	SS2 control bit
AX2_ControlSLA	R 1.10	(Read)[9)]	(Write)[4)]	SAFEBOOL	SLA control bit
AX2_ControlSLS1	R 1.10	(Read)[9)]	(Write)[4)]	SAFEBOOL	SLS1 control bit
AX2_ControlSLS2	R 1.10	(Read)[9)]	(Write)[4)]	SAFEBOOL	SLS2 control bit
AX2_ControlSLS3	R 1.10	(Read)[9)]	(Write)[4)]	SAFEBOOL	SLS3 control bit
AX2_ControlSLS4	R 1.10	(Read)[9)]	(Write)[4)]	SAFEBOOL	SLS4 control bit
AX2_ControlSDI_Pos	R 1.10	(Read)[9)]	(Write)[5)]	SAFEBOOL	SDI pos control bit
AX2_ControlSDI_Neg	R 1.10	(Read)[9)]	(Write)[5)]	SAFEBOOL	SDI neg control bit
AX2_ControlSLI	R 1.10	(Read)[9)]	(Write)[5)]	SAFEBOOL	SLI control bit
AX2_ControlHoming	R 1.10	(Read)[9)]	(Write)[6)]	SAFEBOOL	Homing control bit
AX2_ControlReferenceSwitch	R 1.10	(Read)[9)]	(Write)[6)]	SAFEBOOL	Reference switch bit
AX2_ControlSLP	R 1.10	(Read)[9)]	(Write)[6)]	SAFEBOOL	SLP control bit
AX2_ControlSwitchHomingMode	R 1.10	(Read)[9)]	(Write)[6)]	SAFEBOOL	Switching between the configured homing mode (SAFE FALSE) and restore remanent safe position (SAFE TRUE)
Only for ACOPOS P3 SafeMOTION 3-axis modules					
AX3_ControlReset	R 1.10	(Read)[9)]	(Write)[3)]	SAFEBOOL	Reset bit
AX3_ControlActivate	R 1.10	(Read)[9)]	(Write)[3)]	SAFEBOOL	Activates the SafeMOTION component
AX3_ControlSTO	R 1.10	(Read)[9)]	(Write)[3)]	SAFEBOOL	STO control bit
AX3_ControlSBC	R 1.10	(Read)[9)]	(Write)[3)]	SAFEBOOL	SBC control bit
AX3_ControlSS1	R 1.10	(Read)[9)]	(Write)[3)]	SAFEBOOL	SS1 control bit
AX3_ControlSTO1	R 1.10	(Read)[9)]	(Write)[3)]	SAFEBOOL	STO1 control bit
AX3_ControlSOS	R 1.10	(Read)[9)]	(Write)[4)]	SAFEBOOL	SOS control bit
AX3_ControlSS2	R 1.10	(Read)[9)]	(Write)[4)]	SAFEBOOL	SS2 control bit
AX3_ControlSLA	R 1.10	(Read)[9)]	(Write)[4)]	SAFEBOOL	SLA control bit
AX3_ControlSLS1	R 1.10	(Read)[9)]	(Write)[4)]	SAFEBOOL	SLS1 control bit
AX3_ControlSLS2	R 1.10	(Read)[9)]	(Write)[4)]	SAFEBOOL	SLS2 control bit
AX3_ControlSLS3	R 1.10	(Read)[9)]	(Write)[4)]	SAFEBOOL	SLS3 control bit
AX3_ControlSLS4	R 1.10	(Read)[9)]	(Write)[4)]	SAFEBOOL	SLS4 control bit
AX3_ControlSDI_Pos	R 1.10	(Read)[9)]	(Write)[5)]	SAFEBOOL	SDI pos control bit
AX3_ControlSDI_Neg	R 1.10	(Read)[9)]	(Write)[5)]	SAFEBOOL	SDI neg control bit
AX3_ControlSLI	R 1.10	(Read)[9)]	(Write)[5)]	SAFEBOOL	SLI control bit
AX3_ControlHoming	R 1.10	(Read)[9)]	(Write)[6)]	SAFEBOOL	Homing control bit
AX3_ControlReferenceSwitch	R 1.10	(Read)[9)]	(Write)[6)]	SAFEBOOL	Reference switch bit
AX3_ControlSLP	R 1.10	(Read)[9)]	(Write)[6)]	SAFEBOOL	SLP control bit
AX3_ControlSwitchHomingMode	R 1.10	(Read)[9)]	(Write)[6)]	SAFEBOOL	Switching between the configured homing mode (SAFE FALSE) and restore remanent safe position (SAFE TRUE)

Table 297: SafeMOTION channel list for ACOPOS P3 SafeMOTION

1) Channel only visible if parameter "*Module Information*" is set to "on".
2) This data is accessed in Automation Studio using library ASIOACC.
3) This data is accessed indirectly via the inputs/outputs of function block SF_oS_MOTION_Basic_BR or SF_oS_MOTION_BR.
4) This data is accessed indirectly via the inputs/outputs of function block SF_oS_MOTION_Speed_BR or SF_oS_MOTION_BR.
5) This data is accessed indirectly via the inputs/outputs of function block SF_oS_MOTION_Advanced_BR or SF_oS_MOTION_BR.
6) This data is accessed indirectly via the inputs/outputs of function block SF_oS_MOTION_AbsPos_BR or SF_oS_MOTION_BR.
7) This data is accessed indirectly via the inputs/outputs of function block SF_oS_MOTION_ScaledSpeed_BR or SF_oS_MOTION_BR.
8) This data is accessed indirectly via the inputs/outputs of function block SF_oS_MOTION_Position_BR or SF_oS_MOTION_BR.
9) This data can only be accessed via NC Action or Trace.

6.7 Configuring the safety functions

The concept of integrated safety technology is based on keeping all functional control in the inverter unit, with the SafeMOTION module dedicated to monitoring configurable limits.

The only exception is that the SafeMOTION module activates safe pulse disabling and the safe motor holding brake.

The standard application must react accordingly to the request for a safety function.

To ensure proper interaction between the standard and the safety application (and thereby ensuring maximum availability of the system), the different timing of the two applications must be taken into account.

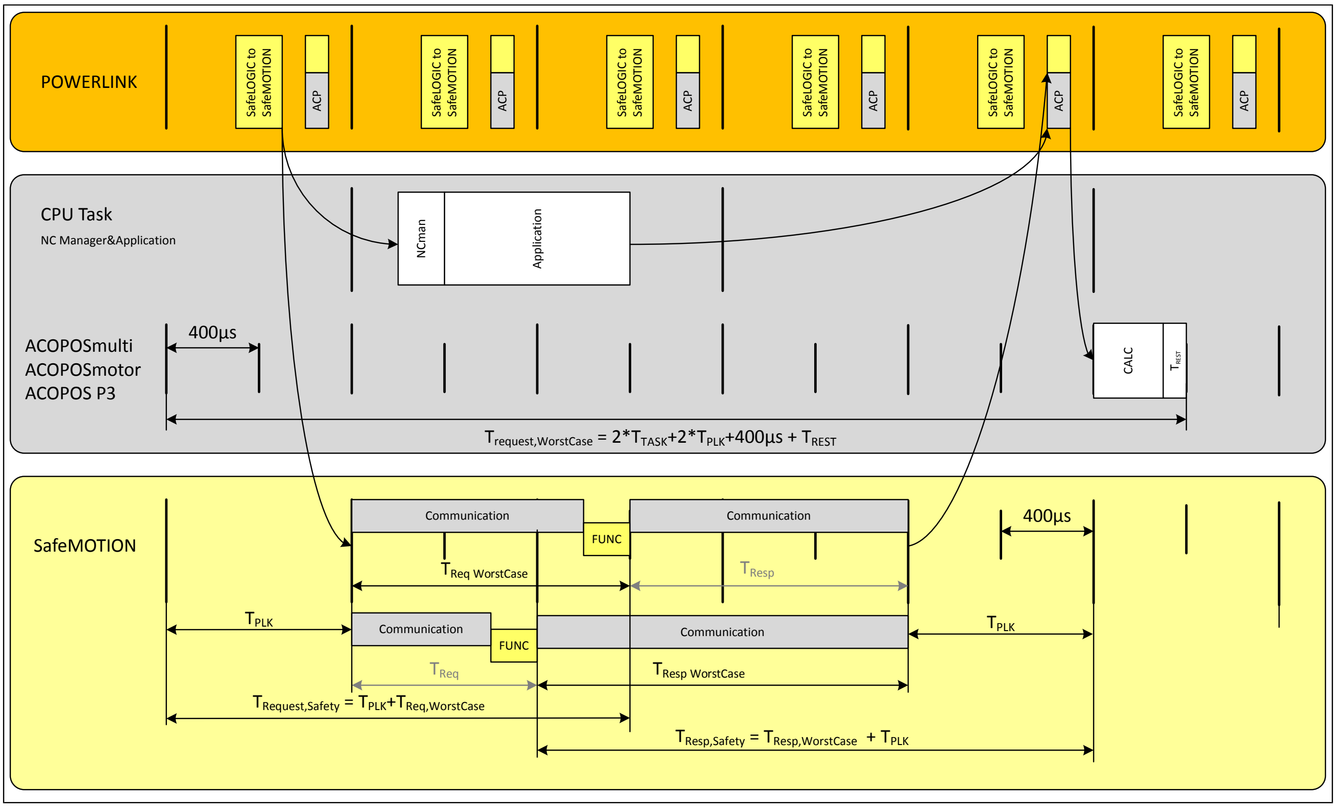


Figure 95: Inverter unit timing - SafeMOTION module

Delay time	ACOPOSmulti SafeMOTION	ACOPOS P3 SafeMOTION
Request control bits ($T_{ReqWorstCase}$)	1200 µs	1250 µs
Response status bits ($T_{RespWorstCase}$)	1600 µs	1550 µs

Table 298: SafeMOTION module - Delay time

The differing runtimes of the standard and the safety application can be taken into account with the "Delay times for requesting a safety function".

Parameter	Unit	Description	Default value
Delay time to start ramp monitoring (us)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0
Delay time to start SDI (us)	[µs]	Delay time between the SDI request and activation of the safety function	0
Delay time to start SBC (us)	[µs]	Delay time between the SBC request and activation of the safety function	0
Delay time to start SLP (us) 1)	[µs]	Delay time between the SLP request and start of monitoring	0
Delay Time to start SBT (us) 2)	[µs]	Delay time between the SBT request and activation of the safety function	0
Delay Time to start SLA (us) 3)	[µs]	Delay time between the SLA request and activation of the safety function	0

Table 299: Delay times for requesting a safety function

1) Only available with Safety Release 1.4 or later!
2) Only available with Safety Release 1.7 or later and only for ACOPOSmulti SafeMOTION SinCos!
3) Only available with Safety Release 1.9 or later!

6.7.1 SafeMOTION Help Tool

The SafeMOTION Help Tool assists in the development of SafeMOTION projects. This program can be used to make calculations that are required frequently.

Starting with V6.0 of the SafeMOTION Help Tool, two variants of the SafeMOTION Help Tool are available:

- mapp Safety
- Legacy safety

The variant can be changed under 6.7.1.8 ""Options" tab" on page 476 tab "Options".

Information:

The parameters can be limited to different maximum values. If an impermissible value is entered, section *Invalid input* in the SafeDESIGNER parameters must be read.

6.7.1.1 "Status and control bits" tab

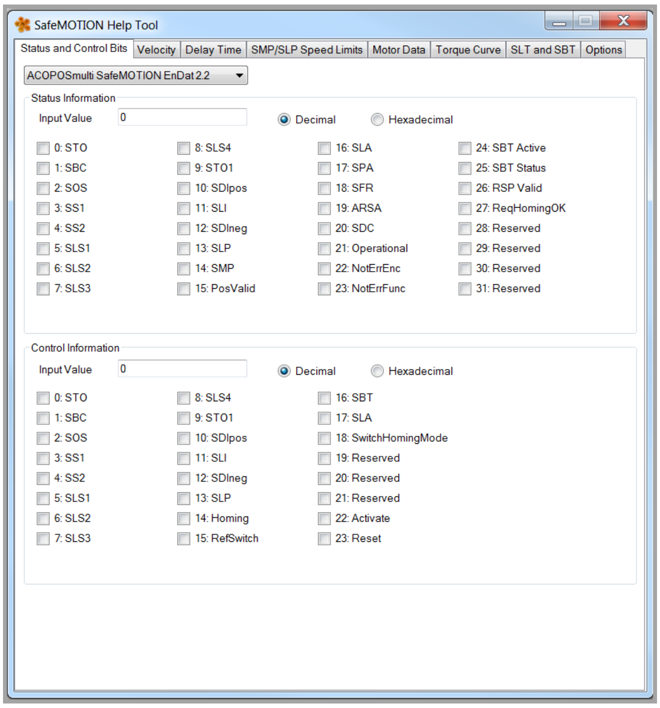


Figure 96: SafeMOTION Help Tool - Tab "Status and control bits" (legacy safety)

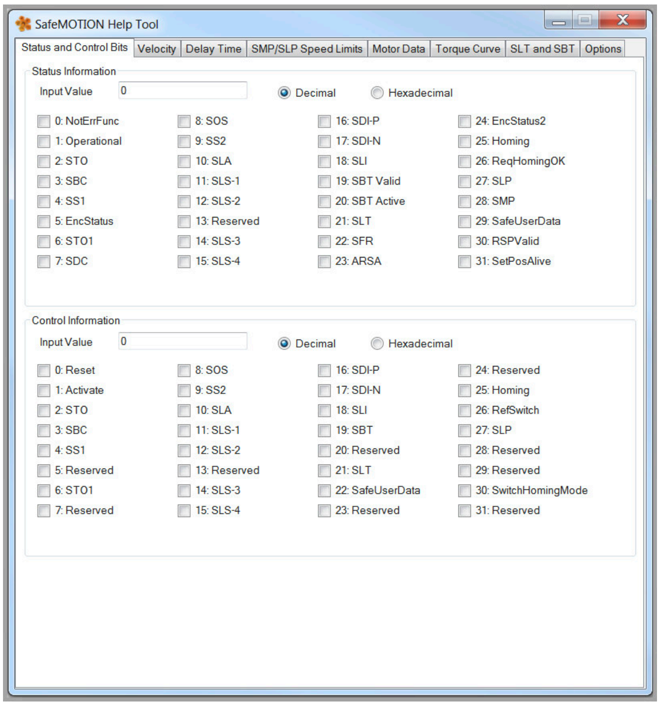


Figure 97: SafeMOTION Help Tool - Tab "Status and control bits" (mapp Safety)

"Status Information" section

Information:

Status information can be determined by running a trace on the cyclic data (ParID 4).

<u>Showing status bits for the status information that has been determined</u>

1. Specify whether the value that has been determined for the status information is decimal or hexadecimal.
2. Enter the value that has been determined in the *Input value* field.
   → The checkboxes now show the status bits for the determined status information.

<u>Determining the input value for a combination of status bits</u>

1. Specify whether the input value should be displayed as a decimal or hexadecimal value.

2. Set the desired combination of status bits by selecting the checkboxes.
   → The input value that corresponds with the combination of status bits is shown.

"Control Information" section

Information:

Control information can be determined by running a trace on the cyclic data (ParID 5).

<u>Showing status bits for the control information that has been determined</u>

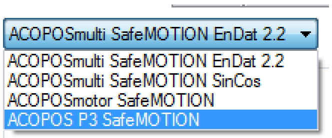
1. Specify whether the value that has been determined for the control information is decimal or hexadecimal.
2. Enter the value that has been determined in the *Input value* field.
   → The check boxes now show the control bits for the determined control information.

<u>Determining the input value for a combination of control bits</u>

1. Specify whether the input value should be displayed as a decimal or hexadecimal value.
2. Set the desired combination of control bits by selecting the check boxes.
   → The input value that corresponds with the combination of control bits is shown.

Information:

Selecting the SafeMOTION module displays the corresponding status and control bits. This only applies to "legacy safety"; there is no distinction in mapp Safety.



6.7.1.2 "Velocity" tab

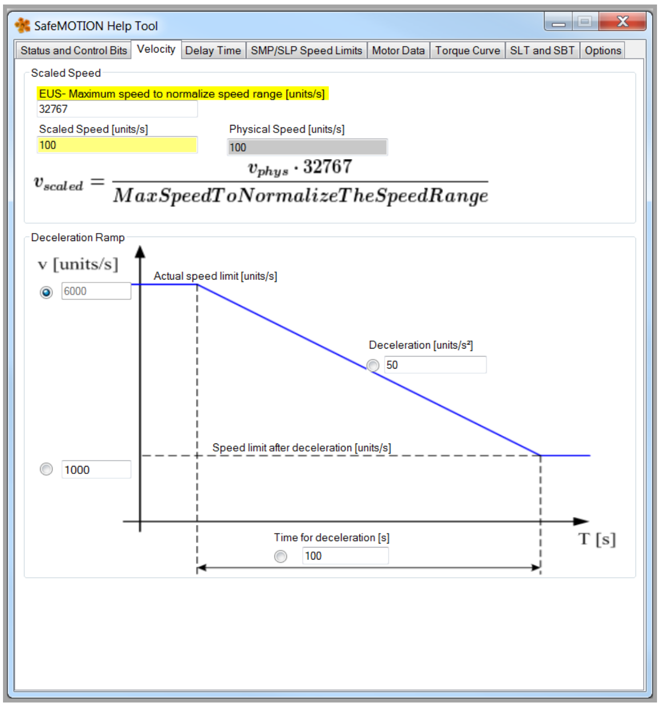


Figure 98: SafeMOTION Help Tool
- Tab "Velocity" (legacy safety)

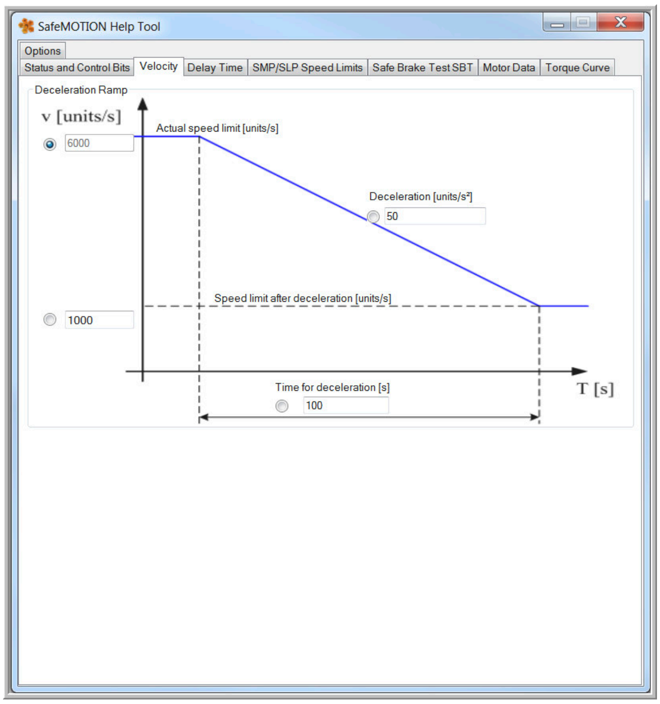


Figure 99: SafeMOTION Help Tool
- Tab "Velocity" (mapp Safety)

"Scaled Speed" section

In section *Scaled speed*, a scaled speed can be converted to a physical speed [units/s] and back again based on the "Maximum speed to normalize the speed range [units/s]" value.

Parameter names marked in yellow correspond to parameters in SafeDESIGNER.

Scaled → physical speed conversion

1. Enter the value for "Maximum speed to normalize the speed range [units/s]".
2. Enter the value for the scaled speed [units/s].
   → The respective value for the physical speed [units/s] is shown.

Physical → scaled speed conversion

1. Enter the value for "Maximum speed to normalize the speed range [units/s]".
2. Enter the value for the physical speed [units/s].
   → The respective value for the scaled speed [units/s] is shown.

"Deceleration Ramp" section

In section *Deceleration Ramp*, three parameters are used to calculate a fourth parameter in order to define a deceleration ramp. Which parameter to be determined can be freely selected.

Procedure

1. Choose the parameter to determine:
   - Current speed limit [units/s]
   - Delay [units/s]
   - Speed limit after the delay [units/s]
   - Delay time [s]
2. Enter the values for the three remaining parameters in their respective fields.
   → The calculated value for the fourth parameter is displayed.

6.7.1.3 "Delay Time" tab

This tab can be used to calculate the delay time to be set on the SafeMOTION module (e.g. "Delay time to start ramp monitoring"), see "Inverter unit timing - SafeMOTION module" on page 465. The delay time is the difference between the times $T_{Request, Safety}$ and $T_{Request, WorstCase}$.

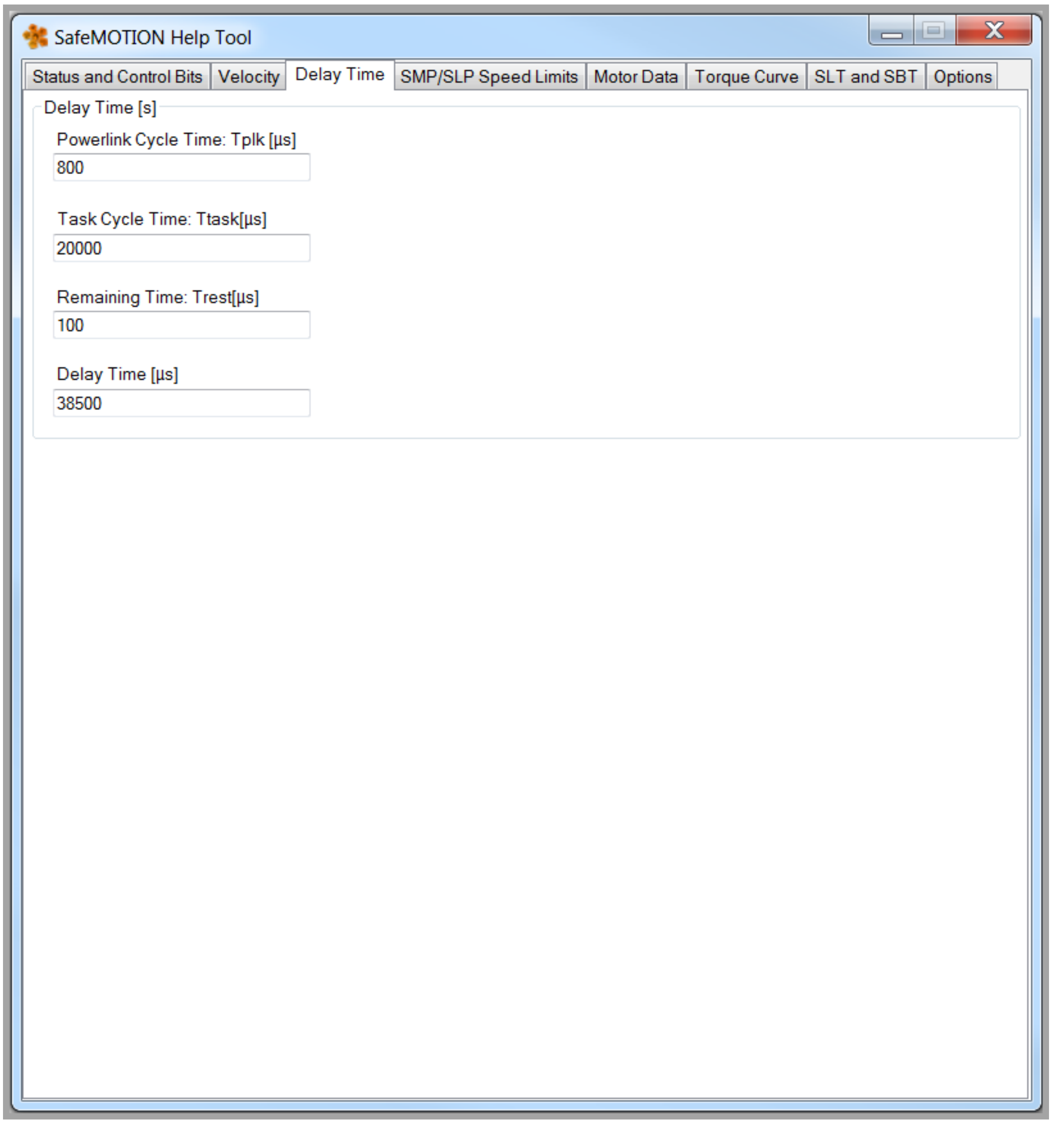


Figure 100: SafeMOTION Help Tool tab "Delay time" (legacy safety, mapp Safety)

"Delay Time" section

<u>Procedure</u>

1. Enter value for the POWERLINK cycle time [µs].
2. Enter value for the task cycle time [µs].
3. Enter value for the remaining time [µs].
   → The value calculated for the delay time [µs] is displayed.

6.7.1.4 "SMP/SLP Speed Limits" tab

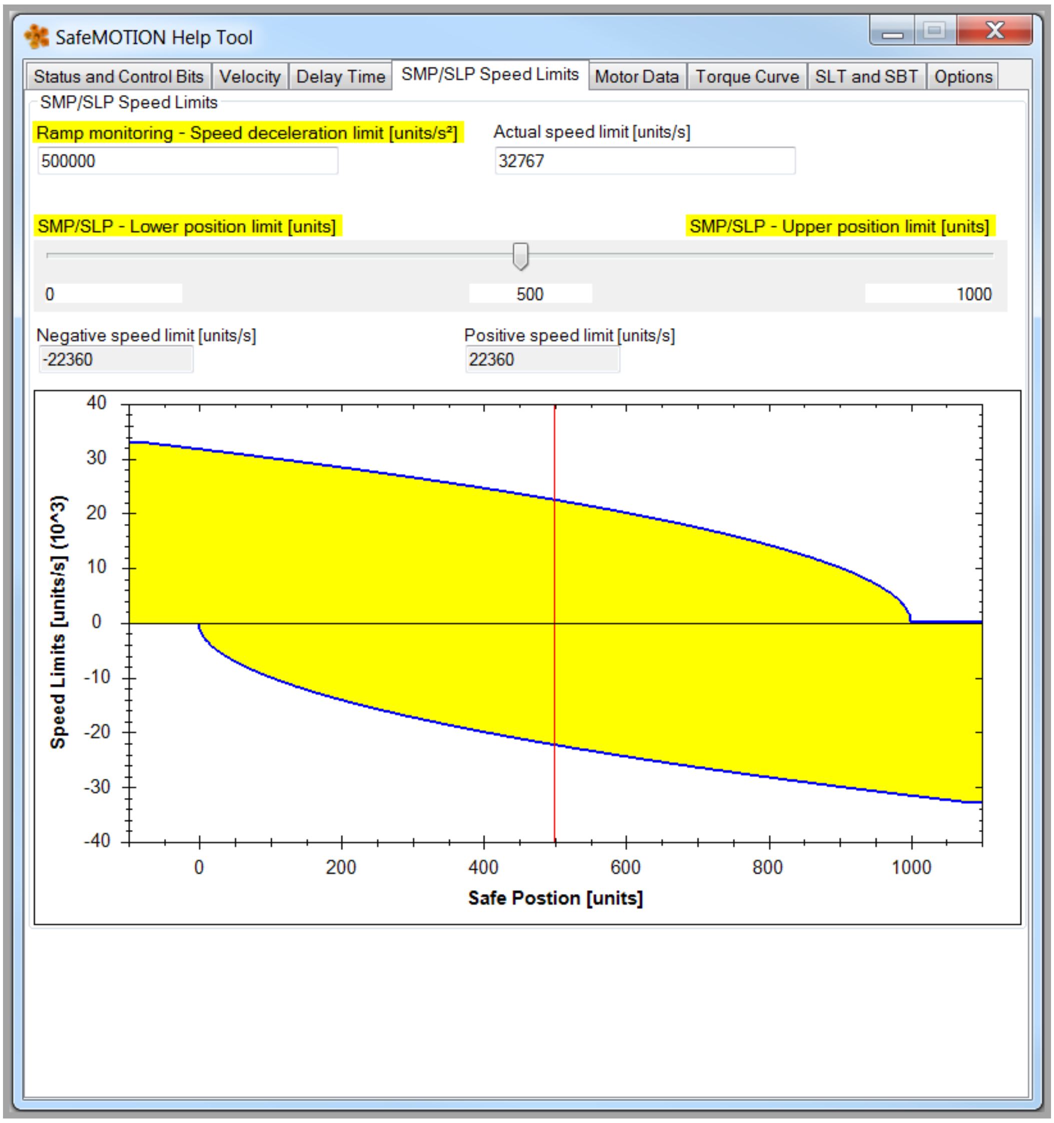


Figure 101: SafeMOTION Help Tool tab "SMP/SLP speed limits" (legacy safety, mapp Safety)

SMP/SLP Speed Limits section

In section *SMP/SLP speed limits*, parameters "Deceleration Ramp [units/s²]" and "Actual speed limit [units/s]" are used to determine the negative and positive speed limit and display them in a diagram.

The "Safe Lower Position Limit for SMP/SLP [units]" and the "Safe Upper Position Limit for SMP/SLP [units]" values can be preset. When a value between these limits is entered, the corresponding values for the negative and positive speed limit [units/s] are determined and displayed.

Parameter names marked in yellow correspond to parameters in SafeDESIGNER.

<u>Calculating negative and positive speed limits</u>

1. Enter the value for "Deceleration Ramp [units/s²]".
2. Enter the value for "Actual speed limit [units/s]".
3. Preset the values for "Safe Lower Position Limit for SMP/SLP [units]" and the "Safe Upper Position Limit for SMP/SLP [units]".
4. Enter a value between the limits or move the arrow with the left mouse button
   This value is shown in the diagram as a red vertical line. The red line can be scrolled or shifted using the arrow pointer.
   → The corresponding values for the negative and positive speed limit [units/s] are displayed in the fields and in the diagram.

Diagram

The following diagram illustrates the speed limit [units/s] in relation to the safe position [units].

Displaying and using the diagram

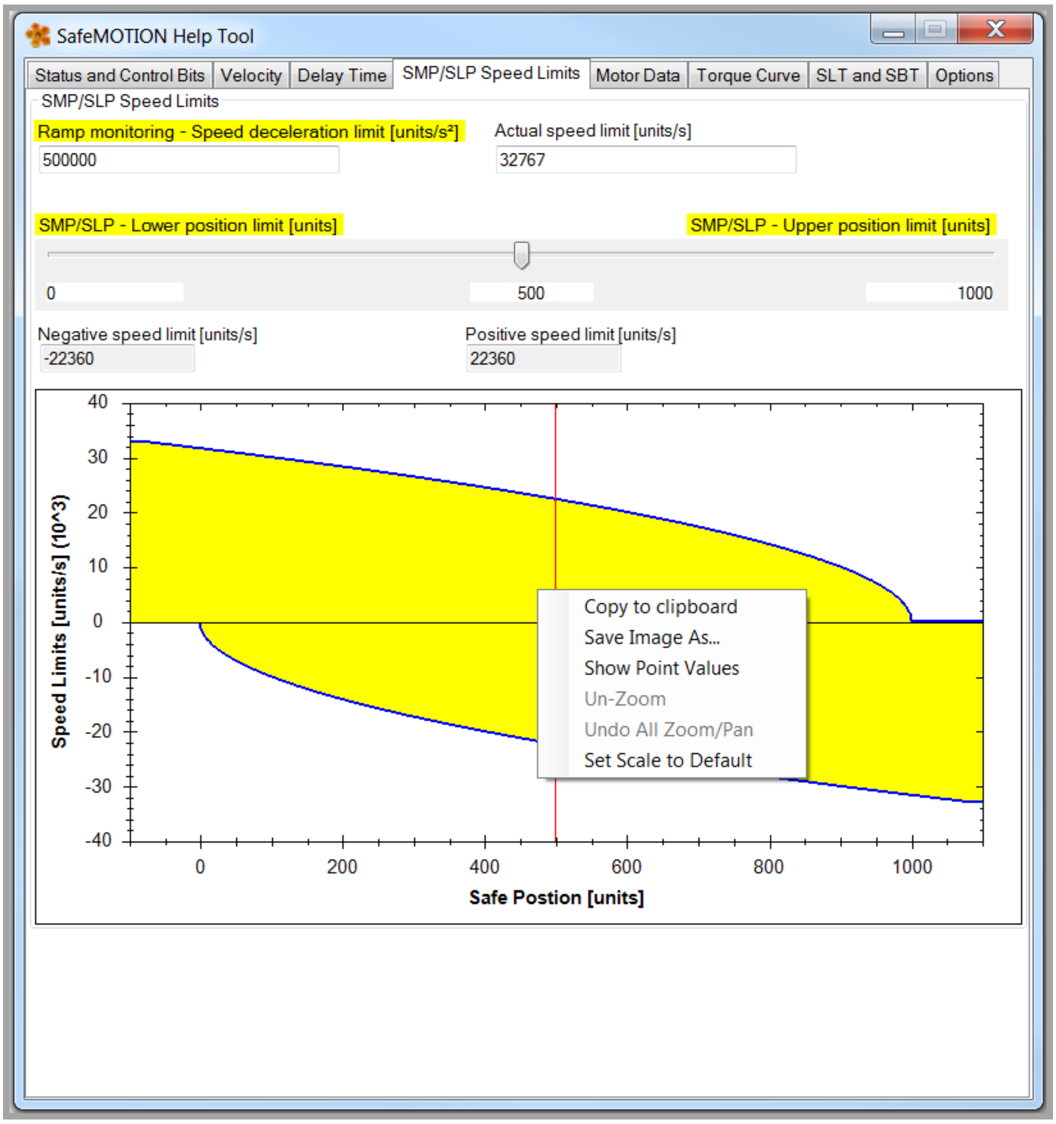


Figure 102: Display diagram with the selection menu (legacy safety, mapp Safety)

Move the mouse pointer over the diagram.
→ A cross-hair pointer appears.
Holding the left mouse button and marking a section zooms in the diagram.
Scrolling with the mouse also zooms in the diagram.

Right-click inside the diagram.
→ A selection menu appears.
Select a menu item with the left mouse button.

Copy to clipboard	Copies the image to the clipboard
Save image as...	Saves the image
Show point values	Displays the values of individual points when moving the cross-hair pointer over the line in the diagram
Undo last zoom action	Reverts back to the previous zoom setting
Undo all zoom/pan actions	Resets all zoom/pan actions
Set scale to default value	Sets scaling to the default values

6.7.1.5 Tab "Motor data"

Figure 103: SafeMOTION Help Tool tab "Safe Speed Observer SSO" (legacy safety, mapp Safety)

The SafeMOTION Help Tool provides support for rescaling the parameters of ACOPOS P3 SafeMOTION servo drives to the SafeDESIGNER unit system.

"Hardware" section

In section "Hardware", the required parameters can be entered in the original units (i.e. in the units specified in the motor data sheets or in the units included with the read-out parameter IDs).

As soon as a parameter is entered, it is immediately converted into the SafeDESIGNER unit system.

In addition to the respective parameter designation, the corresponding parameter ID, to which the parameter can be read out, is shown in brackets.

"SafeDESIGNER parameters" section

The yellow parameter names in section "SafeDESIGNER parameters" correspond to the parameters converted into the correct system of units, which are then entered in SafeDESIGNER.

6.7.1.6 Tab "Torque characteristic"

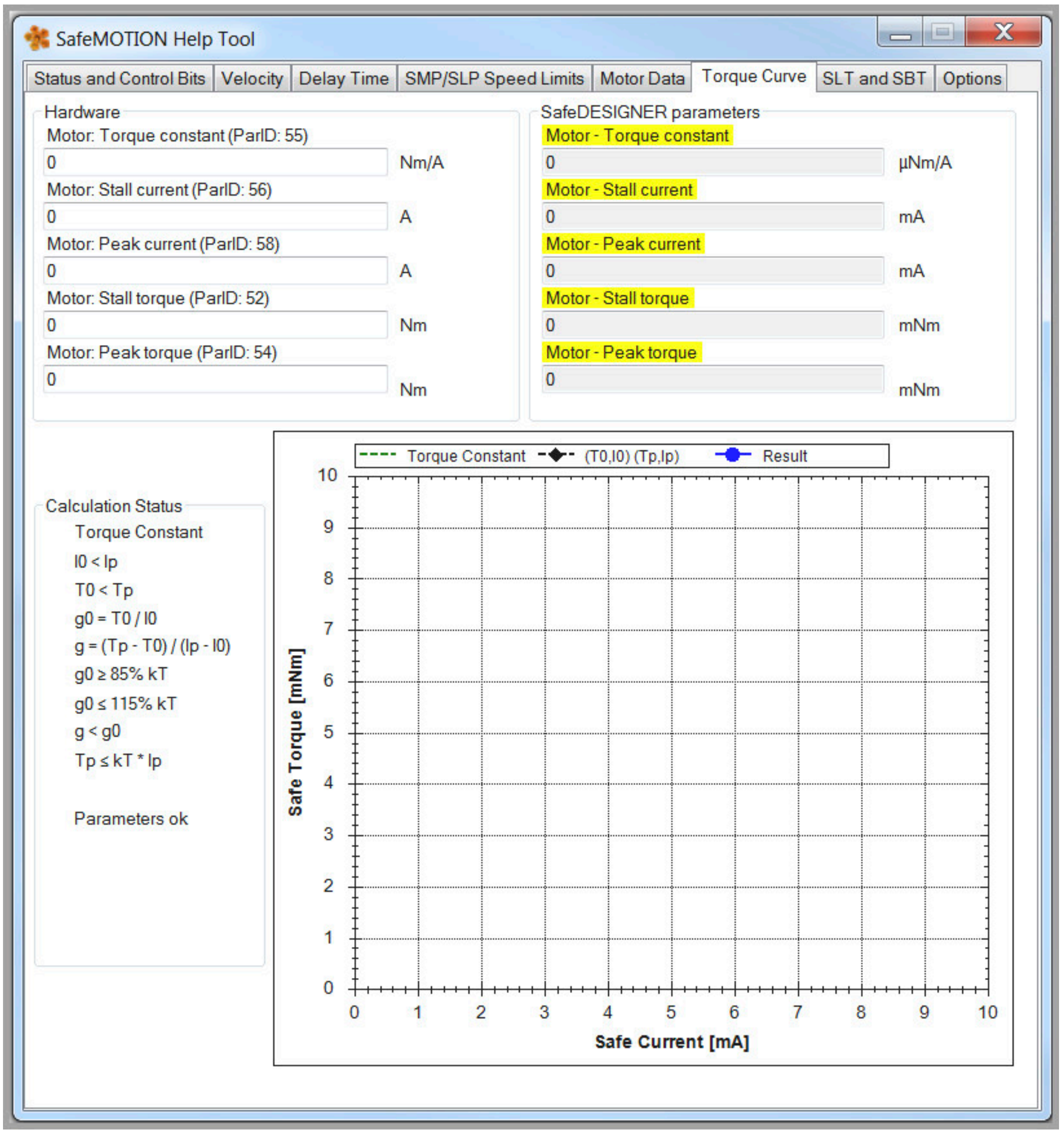


Figure 104: SafeMOTION Help Tool tab "Torque characteristic" (legacy safety, mapp Safety)

"Hardware" section

In section "Hardware", the required parameters can be entered in the original units (i.e. in the units specified in the motor data sheets or in the units included with the read-out parameter IDs). As soon as a parameter is entered, it is immediately converted into the SafeDESIGNER system of units.

Section "SafeDESIGNER parameters"

The yellow parameter names in section "SafeDESIGNER parameters" correspond to the parameters converted into the correct system of units, which are then entered in SafeDESIGNER.

Section "Calculation status"

The parameters entered here are used to check whether they are valid and result in an intersection point. These checks are also performed in the firmware. In addition, the intersection point of the two lines is specified if all parameter entries are correct.

6.7.1.7 Tab "SLT and SBT"

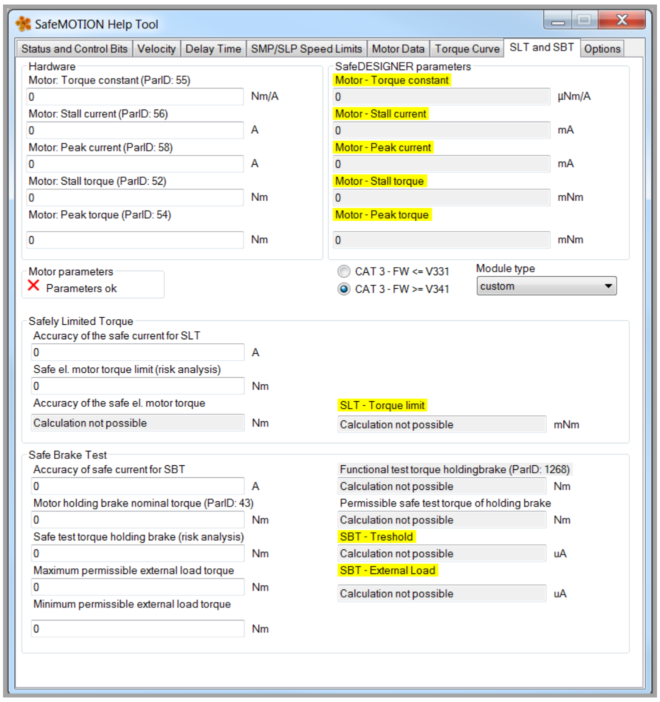


Figure 105: SafeMOTION Help Tool - Tab "SLT and SBT" (legacy safety)

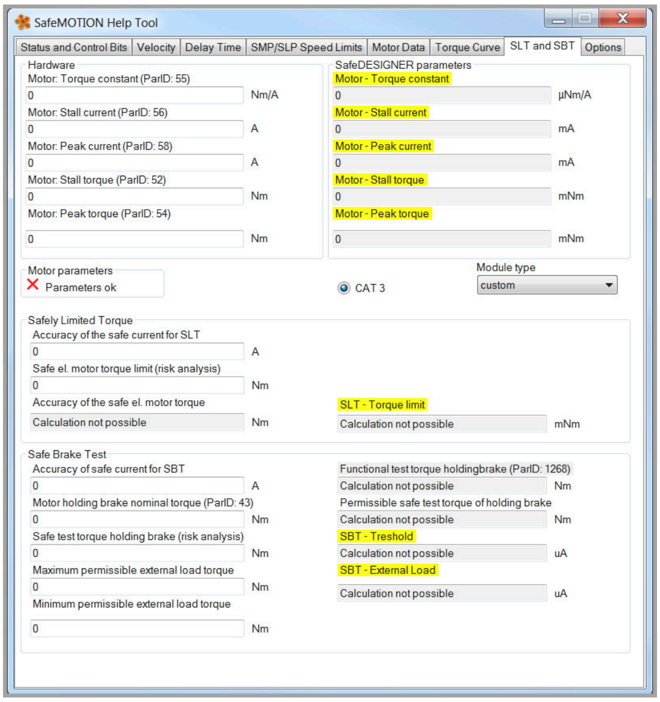


Figure 106: SafeMOTION Help Tool - Tab "SLT and SBT" (mapp Safety)

The SafeMOTION Help Tool provides support for calculating the configuration for safety functions SLT and SBT for ACOPOSmulti SafeMOTION SinCos inverter modules (SBT only) and ACOPOS P3 SafeMOTION (SLT and SBT).

The calculation is performed according to the user documentation ACOPOSmulti SafeMOTION / Safety technology / Integrated safety functions / Safe Brake Test, SBT or ACOPOSmulti SafeMOTION / Safety technology / Integrated safety functions / Safely Limited Torque, SLT.

"Hardware" section

In section "Hardware", the required motor parameters can be entered in the original units (i.e. in the units specified in the motor data sheets or in the units included with the read-out parameter IDs). As soon as a parameter is entered, it is immediately converted into the SafeDESIGNER system of units.

Section "SafeDESIGNER parameters"

The yellow parameter names in section "SafeDESIGNER parameters" correspond to the parameters converted into the correct system of units, which are then entered in SafeDESIGNER.

Section "Motor parameters"

The parameters entered here are used to check whether they are valid and result in an intersection point. These checks are also performed in the firmware.

Section "Module type"

The inverter module and firmware version (for legacy safety) can be set in section "Module type". If an inverter module is selected here, the values for the accuracy of the safe current measurement (SLT and SBT) are applied automatically and the corresponding fields are read-only.

Section "Safely Limited Torque"

The safe electrical motor torque limit (from the risk analysis) can be entered in section "Safely Limited Torque". This is used to determine the limit to be configured in SafeDESIGNER, taking into account the accuracy of the safe current for SLT.

The entered torque limit is checked for the worst-case deviation.

Section "Safe Brake Test"

The motor holding brake nominal torque, safe holding brake test torque (from the risk analysis) and any maximum/minimum permissible external load torque can be configured in section "Safe Brake Test".

The values to be configured – *standard test torque of the holding brake (ParID 1268)*, *SBT - Threshold (SafeDESIGNER)* for the current threshold to be monitored in SafeDESIGNER and *SBT - External Load (SafeDESIGNER)* for configuring the external load in SafeDESIGNER – are determined from the entered values, taking into account the system accuracies.

The system checks whether the resulting permissible safe test torque of the holding brake is below the *motor holding brake nominal torque (ParID 43)* for the safe test torque of the holding brake used (from the risk analysis), 6.4.22.9 "Permissible safe test torque of the holding brake" on page 413.

Information:

The SafeMC Help Tool is not designed according to strict safety criteria. It simply provides support for calculating the values to be set. The calculation and its results must be checked!

6.7.1.8 "Options" tab

Section "SafeMOTION"

Variant selection mapp Safety or legacy safety

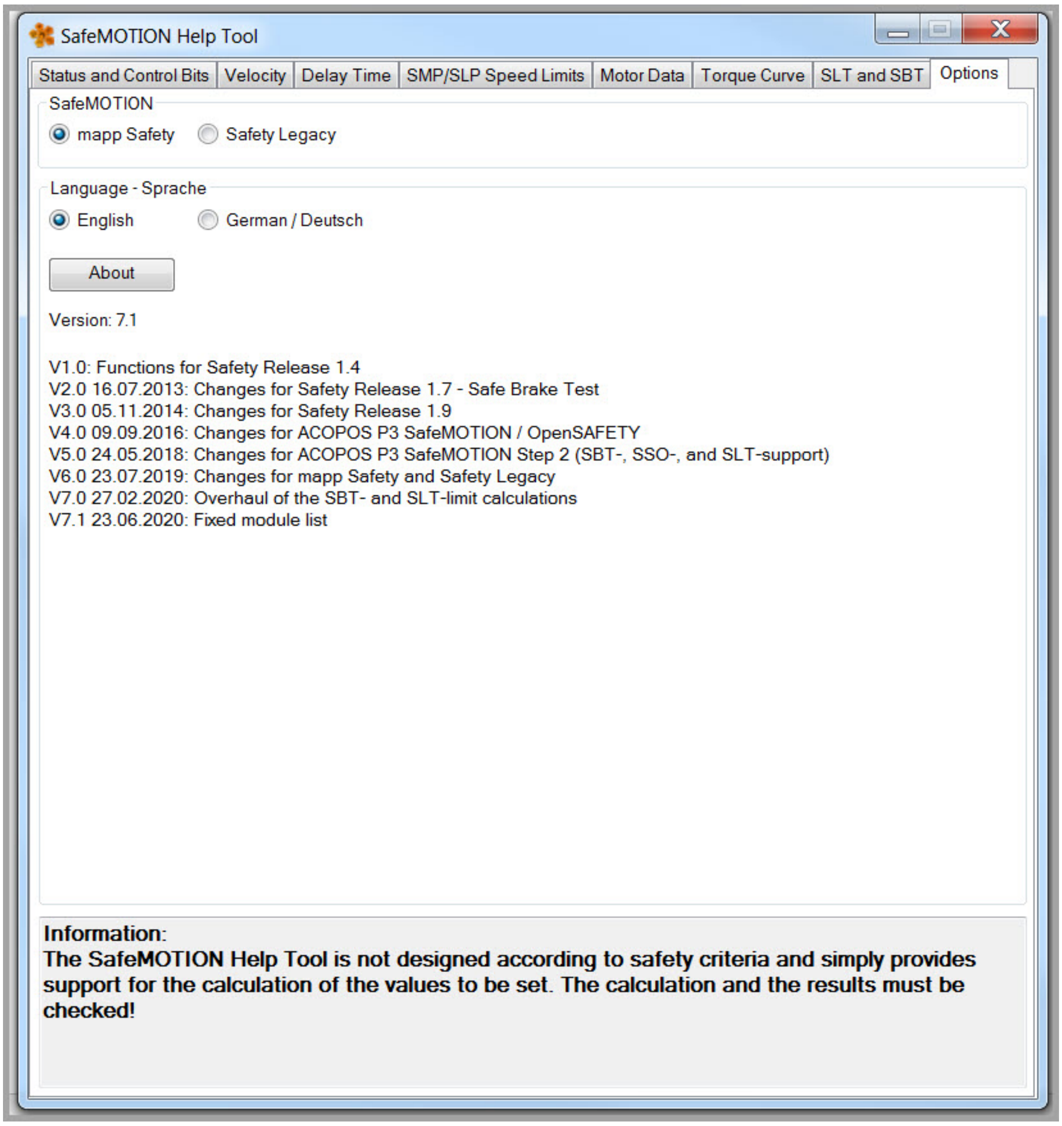
Here, the tool can be repositioned according to the SafeMOTION variant currently being used. This allows it to cover the corresponding available functionalities.

"Language" section

Select English or German.

"About" button

Clicking on "About" displays information about the manufacturer.



6.7.2 The application in SafeDESIGNER

The safety application is implemented in SafeDESIGNER.

Library PLCopen_Motion_SF_2

The following function blocks in library PLCopen_Motion_SF_2 are available for controlling ACOPOSmulti SafeMOTION inverter modules and ACOPOSmotor SafeMOTION modules:

Function block	Safety Release
SF_SafeMC_BR SF_SafeMC_Speed_BR	Safety Release 1.3 or later
SF_SafeMC_BR_V2 SF_SafeMC_Position_BR	Safety Release 1.4 or later
SF_SafeMC_SBT_BR	Safety Release 1.7 or later
SF_SafeMC_BR_V3 SF_SafeMC_Position_BR_V2	Safety Release 1.9 or later

Table 300: Function blocks in library PLCopen_Motion_SF_2

For information about using these function blocks as well as the underlying safety functions and associated safe parameters, see 7 "PLCopen_Motion_SF_2" on page 494.

Library openSAFETY_BuR_Motion_SF

ACOPOS P3 SafeMOTION servo drives support the openSAFETY Safe Motion profile. For this reason, the function blocks in library openSAFETY_BuR_Motion_SF must be used to control the safety functions.

Function block	Safety Release
SF_oS_MOTION_Basic_BR	Safety Release 1.10 and later:
SF_oS_MOTION_Speed_BR	
SF_oS_MOTION_Advanced_BR	
SF_oS_MOTION_AbsPos_BR	
SF_oS_MOTION_BR	
SF_oS_MOTION_ScaledSpeed_BR	
SF_oS_MOTION_Position_BR	

Table 301: Function blocks in library openSAFETY_BuR_Motion_SF

For information about using these function blocks as well as the underlying safety functions and associated safe parameters, see 8 "openSAFETY_BuR_Motion_SF" on page 733.

> ## Danger!
>
> **Safety applications are only permitted to be created by qualified personnel.**
> **The respective processes specified in the standards must be followed!**

The information provided in the "Integrated safety" user's manual (MASAFETY-ENG) under SafeDESIGNER must also be taken into consideration.

> ## Danger!
>
> **All of the safety functions that are being used must be tested.**
> **A function is considered to be "in use" if the corresponding input is connected or the safety function has been configured!**

6.7.3 Accessing data on the SafeMOTION module from Automation Studio

There are three ways to access safety-related data from a safe axis in Automation Studio.

6.7.3.1 I/O mapping

The states of individual safety functions can be accessed via the I/O mapping window for the respective SafeMOTION module. This information is provided in the form of status bits.

To connect PVs to the status bits, the "I/O mapping" window must be opened. As can be seen in the following image, the PV can then be selected in the "PV or channel name" column.

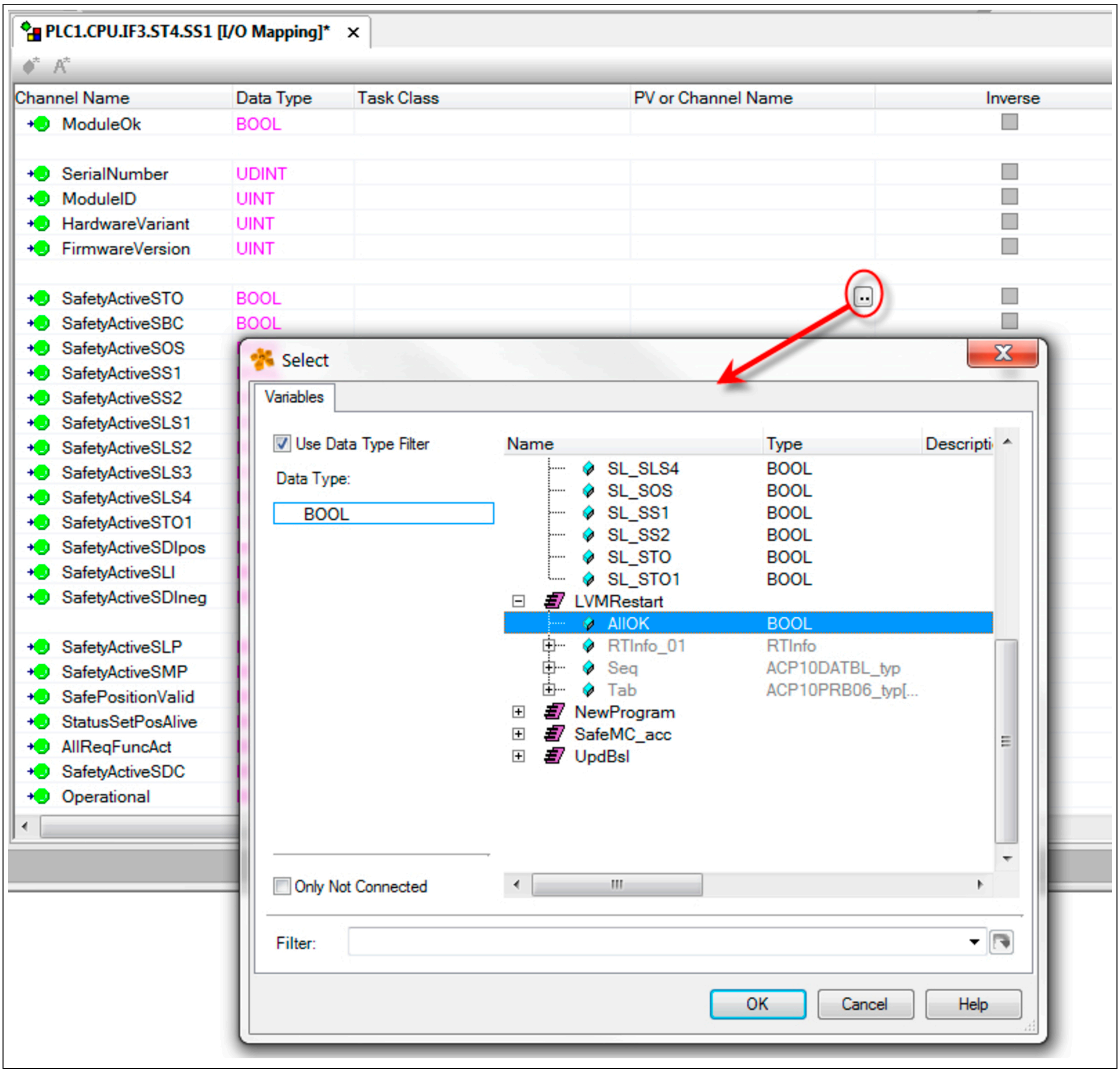


Figure 107: PV mapping

6.7.3.2 ACOPOS parameter ID

The following parameter IDs are available to make SafeMOTION data available to the non-safety-related part of the ACOPOSmulti SafeMOTION inverter module, ACOPOS P3 SafeMOTION servo drive and ACOPOSmotor SafeMOTION.

ParID	Data type	NC constant (Define)	Description
4	UDINT	SAFEMC_STATUS	Status bits
5	UDINT	SAFEMC_CONTROL	Control bits
6	INT	SAFEMC_SPEED_ACT	Actual speed [scaled units/s]
7	INT	SAFEMC_SPEED_LIM	Speed limit value [scaled units/s], currently monitored speed limit
309	DINT	SAFEMC_POS_ACT	Safe position [units]

Table 302: ACOPOS parameter ID for SafeMOTION

With these Par IDs, you can use all the familiar features of the SafeMOTION module (e.g. NC Trace, reading parameters via service channel, SPT function block connections, etc.).

NC Trace can be used, for example, to optimize how the standard application handles approaching speed limit values. This also provides an easy way of checking whether the values configured for "Delay times for requesting a safety function" are correct or sufficient.

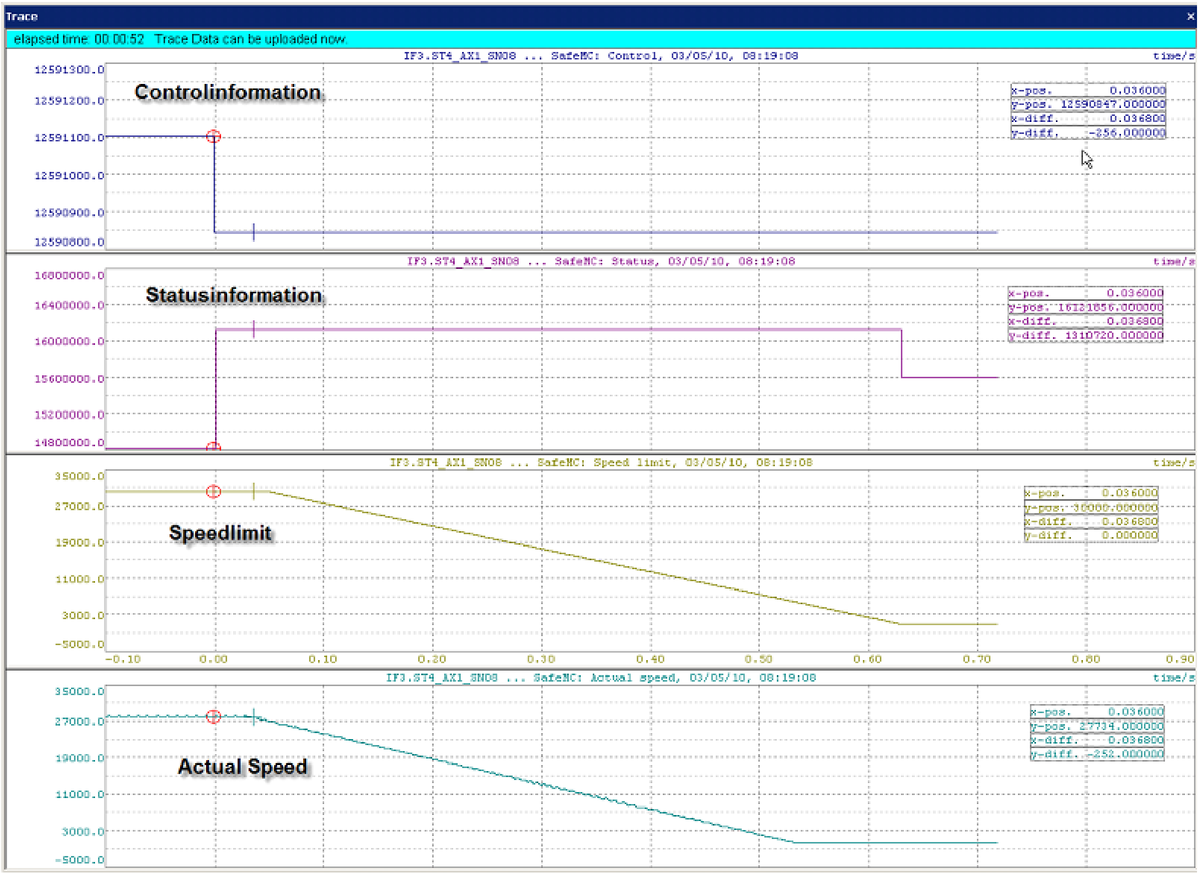


Figure 108: NC Trace: Example with SafeMOTION data

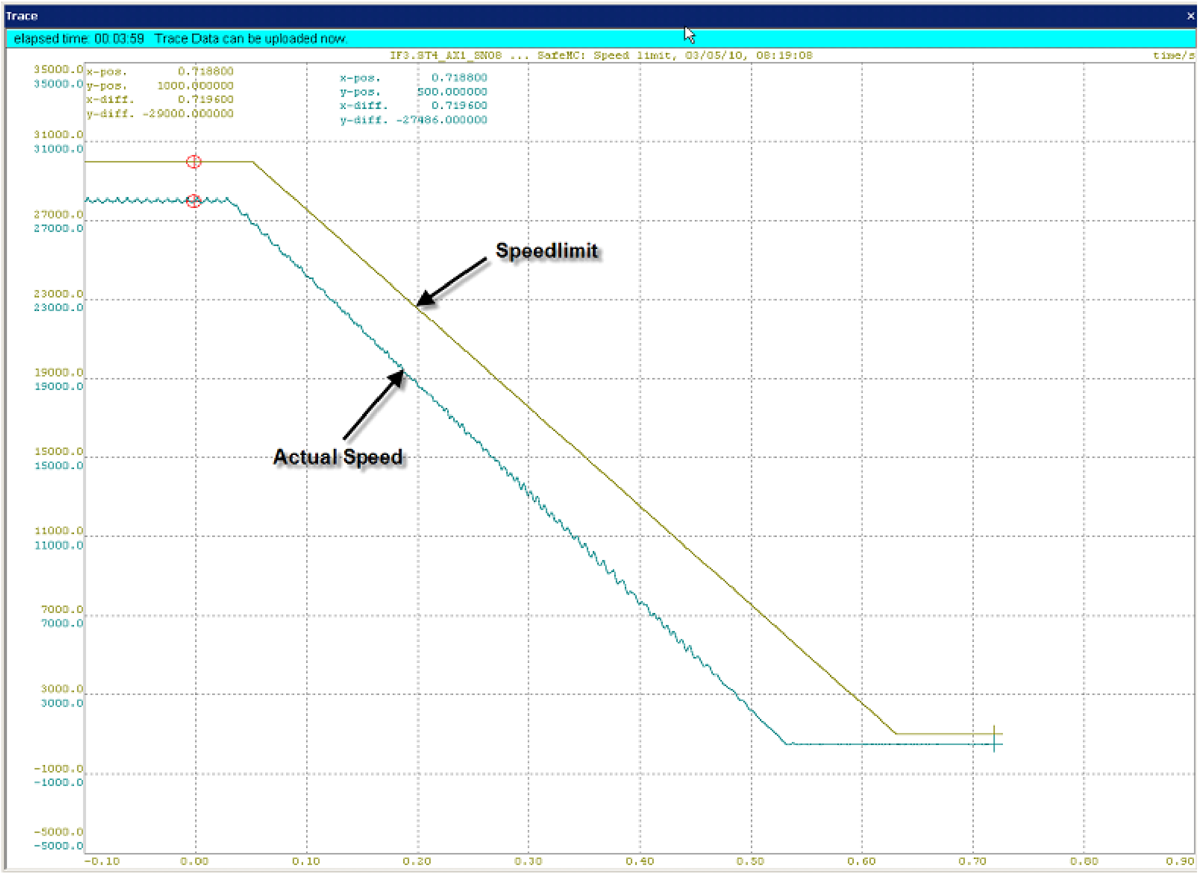


Figure 109: NC Trace: Speed reserve

The parameter IDs "4 status bits" and "5 control bits" are bit-coded, with only the lower three bytes actually relevant. The following tables indicate the bit assignments:

Bit	ACOPOSmulti SafeMOTION EnDat 2.2 ACOPOSmulti SafeMOTION SinCos ACOPOSmotor SafeMOTION EnDat 2.2	ACOPOS P3 SafeMOTION *(Basic function set)*
0	Status STO	Status Not Err Func
1	Status SBC	Status Operational
2	Status SOS	Status STO
3	Status SS1	Status SBC
4	Status SS2	Status SS1
5	Status SLS1	Status Not Err Enc
6	Status SLS2	Status STO1
7	Status SLS3	Status SDC

Table 303: Status bits - Byte 0

Bit	ACOPOSmulti SafeMOTION EnDat 2.2 ACOPOSmulti SafeMOTION SinCos ACOPOSmotor SafeMOTION EnDat 2.2	ACOPOS P3 SafeMOTION *(Speed function set)*
8	Status SLS4	Status SOS
9	Status STO1	Status SS2
10	Status SDIpos	Status SLA
11	Status SLI	Status SLS1
12	Status SDIneg	Status SLS2
13	Status SLP[1)]	*Reserved for openSAFETY*
14	Status SMP[1)]	Status SLS3
15	Status PosValid[1)]	Status SLS4

Table 304: Status bits - Byte 1

1) Only available with Safety Release 1.4 or later!

Bit	ACOPOSmulti SafeMOTION EnDat 2.2 ACOPOSmulti SafeMOTION SinCos ACOPOSmotor SafeMOTION EnDat 2.2	ACOPOS P3 SafeMOTION *(Advanced function set)*
16	Status SLA[1)]	Status SDIpos
17	Status SPA	Status SDIneg
18	Status SFR	Status SLI
19	Status All requested safety functions active	*Reserved for SBT*
20	Status SDC	*Reserved for SBT valid*
21	Status Operational	*Reserved for SLT*
22	Status Not Err Enc	Status SFR
23	Status Not Err Func	Status All requested safety functions active

Table 305: Status bits - Byte 2

1) Only available with Safety Release 1.9 or later!

Bit	ACOPOSmulti SafeMOTION EnDat 2.2 ACOPOSmulti SafeMOTION SinCos ACOPOSmotor SafeMOTION EnDat 2.2	ACOPOS P3 SafeMOTION *(Absolute position function set)*
24	Status SBT_ACTIVE[1)]	Status Not err enc (copy of bit 5)
25	Status SBT_STATUS[1)]	Status SafePositionValid
26	Status RSPValid[2)]	Status ReqHomingOK
27	Status ReqHomingOK[3)]	Status SLP
28	*Not used*	Status SMP
29	*Not used*	*Reserved for openSAFETY*
30	*Not used*	Status RSPValid
31	*Not used*	Status SetPosAlive

Table 306: Status bits - Byte 3

1) Only available with Safety Release 1.7 or later and only for ACOPOSmulti SafeMOTION SinCos!
2) Only available with Safety Release 1.9 and later and only for SafeMOTION EnDat 2.2!
3) Only available with Safety Release 1.9 or later!

Bit	ACOPOSmulti SafeMOTION EnDat 2.2 ACOPOSmulti SafeMOTION SinCos ACOPOSmotor SafeMOTION EnDat 2.2	ACOPOS P3 SafeMOTION *(Basic function set)*
0	Control STO	Control Reset
1	Control SBC	Control Activate
2	Control SOS	Control STO
3	Control SS1	Control SBC
4	Control SS2	Control SS1
5	Control SLS1	*Reserved for openSAFETY*
6	Control SLS2	Control STO1
7	Control SLS3	Not used

Table 307: Control bits - Byte 0

Bit	ACOPOSmulti SafeMOTION EnDat 2.2 ACOPOSmulti SafeMOTION SinCos ACOPOSmotor SafeMOTION EnDat 2.2	ACOPOS P3 SafeMOTION *(Speed function set)*
8	Control SLS4	Control SOS
9	Control STO1	Control SS2
10	Control SDIpos	Control SLA
11	Control SLI	Control SLS1
12	Control SDIneg	Control SLS2
13	Control SLP[1)]	*Reserved for openSAFETY*
14	Homing[1)]	Control SLS3
15	RefSwitch[1)]	Control SLS4

Table 308: Control bits - Byte 1

1) Only available with Safety Release 1.4 or later!

Bit	ACOPOSmulti SafeMOTION EnDat 2.2 ACOPOSmulti SafeMOTION SinCos ACOPOSmotor SafeMOTION EnDat 2.2	ACOPOS P3 SafeMOTION *(Advanced function set)*
16	Control SBT[1)]	Control SDIpos
17	Control SLA[2)]	Control SDIneg
18	SwitchHomingMode[3)]	Control SLI
19	*Not used*	Control SBT

Table 309: Control bits - Byte 2

Bit	ACOPOSmulti SafeMOTION EnDat 2.2 ACOPOSmulti SafeMOTION SinCos ACOPOSmotor SafeMOTION EnDat 2.2	ACOPOS P3 SafeMOTION *(Advanced function set)*
20	*Not used*	*Reserved for openSAFETY*
21	*Not used*	Control SLT
22	Control Activate	*Not used*
23	Control Reset	*Not used*

Table 309: Control bits - Byte 2

1) Only available with Safety Release 1.7 or later and only for ACOPOSmulti SafeMOTION SinCos!
2) Only available with Safety Release 1.9 or later!
3) Only available with Safety Release 1.9 and later and only for SafeMOTION EnDat 2.2!

Bit	ACOPOSmulti SafeMOTION EnDat 2.2 ACOPOSmulti SafeMOTION SinCos ACOPOSmotor SafeMOTION EnDat 2.2	ACOPOS P3 SafeMOTION *(Absolute position function set)*
24	*Not used*	*Reserved for openSAFETY*
25	*Not used*	Control Homing
26	*Not used*	Control Reference Switch
27	*Not used*	Control SLP
28	*Not used*	*Reserved for openSAFETY*
29	*Not used*	*Reserved for openSAFETY*
30	*Not used*	Control SwitchHomingMode
31	*Not used*	*Not used*

Table 310: Control bits - Byte 3

6.7.3.3 SafeMC library

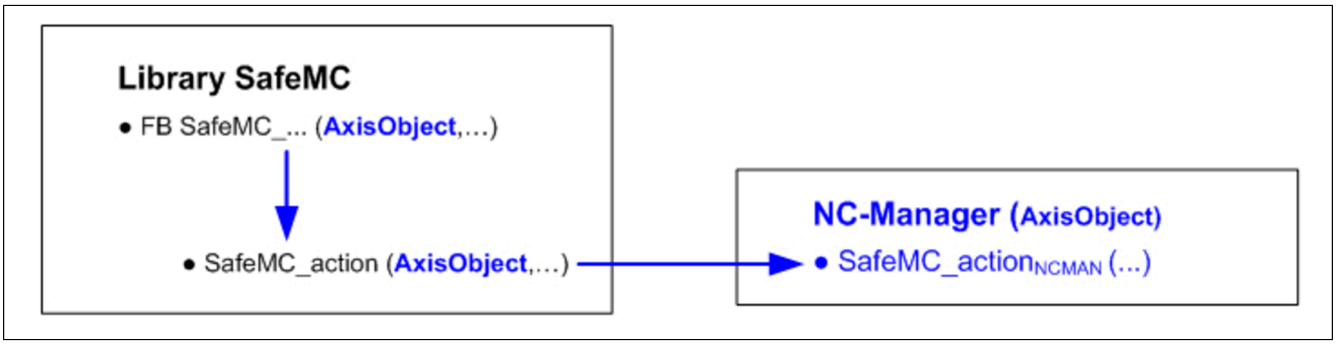
If SafeMOTION modules are being used, it is sometimes necessary to be able to read SafeMOTION data for an axis:

- **Safe OUT**: Data from the SafeLOGIC (SL) controller to the SafeMOTION module
- **Safe IN**: Data from the SafeMOTION module to the SafeLOGIC (SL) controller

For **Safe IN** data, it would be possible in the I/O configuration to define PVs to which the data would then be copied cyclically. However, this data must be explicitly assigned to specific axes by the user.

Automation Studio does not include a mechanism for read access to **Safe OUT** data.

The **SafeMC_action()** function in the SafeMC library makes it possible to access the SafeMOTION data of an axis (described below). The SafeMOTION function blocks call the global **SafeMC_action()** function. Using the specified axis object, **SafeMC_action()** calls a **SafeMC_action$_{NCMAN}$()** function that is included in the NC Manager belonging to this NC object.



Information:

The SafeMC_action() function only contains a call frame. The actual functionality is part of the corresponding NC Manager function.

For this reason, the constants and data types for the functionalities implemented for the SafeMC_action() function are not included in the SafeMC library:

- **Constants are included in library NcGlobal.**
- **Data types are included in library Acp10man.**

6.7.3.3.1 Function SafeMC_action(): Perform SafeMOTION action

status = SafeMC_action(nc_object, action, par_ptr, par_size)		
Input parameters:		
nc_object	UDINT	NC object
action	UDINT	Action to be executed
par_ptr	UDINT	Address of the parameter data
par_size	UDINT	Size of the parameter data in bytes
Output parameters:		
status	UINT	ncOK or error code

Table 311: SafeMC_action()

Error codes (also used for function blocks SafeMC_ReadSafeOutData(2) and SafeMC_ReadSafeInData(2)):

10720	Invalid function pointer: • Error during NC software initialization (see Logger) • The NC Manager version on the PLC does not yet contain the SafeMC_action() function.
10721	Invalid NC object (parameter: "nc_object")
10723	The action (parameter "action") is not defined or not permitted for this NC object.
10724	Invalid NC object type
10726	This action is not allowed since the corresponding initializations are not yet complete.
10729	Parameter "par_ptr" is zero.
10731	Invalid NC object data (is a PV being used as an NC object for which an INIT value is defined in the variable declaration?)
10732	Parameter "par_size" is not valid for this action.
10733	The network status is not valid for this action.
10734	Invalid network type (the NC object does not belong to a module on the POWERLINK network)
10735	Invalid length of corresponding network data
10736	The type of network data is not compatible with "action": • SafeOUT/IN data compatible with "action = ..._DATA" • SafeOUT/IN data 2 compatible with "action = ..._DATA2"

In addition, the following error codes are output for some actions, which suggests an initialization error in the SafeMOTION data:

10712	NC object not enabled (channel number too high or no PDO data defined)
20918	"data_len" provided by plAction(plACTION_GET_DP_INFO) too large
20953	"direction_id" provided by plAction(plACTION_GET_DP_INFO) invalid

All other error codes are provided by the functions in the "Powerlnk" library. The following error code deserves special mention:

20923	Data point not available (not entered in the PDO mapping)

6.7.3.3.2 Accessing SafeMOTION data with the SafeMC_action() function

6.7.3.3.2.1 READ_SAFEOUT_DATA: Read SafeOUT data

Information:

Function READ_SAFEOUT_DATA and associated data type ACP10SAFEOUTDAT_typ are only available for ACOPOSmulti SafeMOTION inverter modules (EnDat 2.2 and SinCos) and ACOPOSmotor SafeMOTION EnDat 2.2.

Parameter:

```
ACP10SAFEOUTDAT_typ safeout_data;
```

Function call:

```
SafeMC_action(ax_obj,SafeMC_action_READ_SAFEOUT_DATA,
&safeout_data,sizeof(safeout_data));
```

Condition(s):

```
p_ax_dat->network.init == ncTRUE
```

ACP10SAFEOUTDAT_typ data structure (also used for function block SafeMC_ReadSafeOutData):

RequestSTO	USINT	STO control bit
RequestSBC	USINT	SBC control bit
RequestSOS	USINT	SOS control bit
RequestSS1	USINT	SS1 control bit
RequestSS2	USINT	SS2 control bit
RequestSLS1	USINT	SLS1 control bit
RequestSLS2	USINT	SLS2 control bit

RequestSLS3	USINT	SLS3 control bit
RequestSLS4	USINT	SLS4 control bit
RequestSTO1	USINT	STO1 control bit
RequestSDIpos	USINT	SDI control bit (positive direction)
RequestSLI	USINT	SLI control bit
RequestSDIneg	USINT	SDI control bit (negative direction)
RequestSLP [1)]	USINT	SLP control bit [1)]
RequestHoming [1)]	USINT	Homing control bit [1)]
RequestSwitch [1)]	USINT	Reference Switch [1)]
RequestSBT [2)]	USINT	SBT control bit [2)]
RequestSLA[3)]	USINT	SLA control bit [3)]
SwitchHomingMode [4)]	USINT	Switch Homing Mode Bit [4)]
reserved_ctrl_b19	*USINT*	*Reserved*
reserved_ctrl_b20	*USINT*	*Reserved*
reserved_ctrl_b21	*USINT*	*Reserved*
Activate	USINT	Activates the SafeMOTION module
Reset	USINT	Reset bit

1) Available with V2.250 or later for Safety Release 1.4.
2) Available with V2.340 or later for Safety Release 1.7 and only for ACOPOSmulti SafeMOTION SinCos!
3) Available with V2.480 or later for Safety Release 1.9!
4) Available with V2.480 and later for Safety Release 1.9 and only for SafeMOTION EnDat 2.2!

6.7.3.3.2.2 READ_SAFEIN_DATA: Read SafeIN data

Information:

Function READ_SAFEIN_DATA and associated data type ACP10SAFEINDAT_typ are only available for ACOPOSmulti SafeMOTION inverter modules (EnDat 2.2 and SinCos) and ACOPOSmotor SafeMOTION EnDat 2.2.

Parameter:

```
ACP10SAFEINDAT_typ safein_data;
```

Function call:

```
SafeMC_action(ax_obj,SafeMC_action_READ_SAFEIN_DATA,
&safein_data,sizeof(safein_data));
```

Condition(s):

```
p_ax_dat->network.init == ncTRUE
```

ACP10SAFEINDAT_typ data structure (also used for SafeMC_ReadSafeInData function block):

SafetyActiveSTO	USINT	STO status bit
SafetyActiveSBC	USINT	SBC status bit
SafetyActiveSOS	USINT	SOS status bit
SafetyActiveSS1	USINT	SS1 status bit
SafetyActiveSS2	USINT	SS2 status bit
SafetyActiveSLS1	USINT	SLS1 status bit
SafetyActiveSLS2	USINT	SLS2 status bit
SafetyActiveSLS3	USINT	SLS3 status bit
SafetyActiveSLS4	USINT	SLS4 status bit
SafetyActiveSTO1	USINT	STO1 status bit
SafetyActiveSDIpos	USINT	SDI status bit (positive direction)
SafetyActiveSLI	USINT	SLI status bit
SafetyActiveSDIneg	USINT	SDI status bit (negative direction)
SafetyActiveSLP [1)]	USINT	SLP status bit [1)]
SafetyActiveSMP [1)]	USINT	SMP status bit [1)]
SafePositionValid [1)]	USINT	Safe position successfully homed and is valid [1)]
SafetyActiveSLA [4)]	USINT	SLA status bit
StatusSetPosAlive	USINT	Position setpoint has been tested
StatusSFR	USINT	At least one safety function has been requested
AllReqFuncAct	USINT	All requested safety functions are active
SafetyActiveSDC	USINT	Delay monitoring is active
Operational	USINT	Function block is in the OPERATIONAL state
NotErrENC	USINT	Encoder error status bit
NotErrFUNC	USINT	Functional fail safe status bit
SafetyActiveSBT [2)]	USINT	SBT is active [2)]
SaftetyStatusSBT [2)]	USINT	SBT status bit [2)]
RSPValid [3)]	USINT	RSP Valid Bit [3)]
ReqHomingOK [4)]	USINT	Request Homing OK Bit [4)]
reserved_stat_b28	*USINT*	*Reserved*
reserved_stat_b29	*USINT*	*Reserved*

reserved_stat_b30	*USINT*	*Reserved*
reserved_stat_b31	*USINT*	*Reserved*
ScaledSpeed	INT	Scaled safe speed
SafePosition [1)]	DINT	Safe position [1)]

1) Available with V2.250 or later for Safety Release 1.4.
2) Available with V2.340 or later for Safety Release 1.7 and only for ACOPOSmulti SafeMOTION SinCos!
3) Available with V2.480 and later for Safety Release 1.9 and only for SafeMOTION EnDat 2.2!
4) Available with V2.480 or later for Safety Release 1.9!

6.7.3.3.2.3 READ_SAFEOUT_DATA2: Read SafeOUT data 2

Information:

Function READ_SAFEOUT_DATA2 and associated data type ACP10SAFEOUTDAT2_typ are only available for ACOPOS P3 SafeMOTION EnDat 2.2 servo drives.

Parameter:

```
ACP10SAFEOUTDAT2_typ safeout_data;
```

Function call:

```
SafeMC_action(ax_obj,SafeMC_action_READ_SAFEOUT_DATA2,
&safeout_data2,sizeof(safeout_data2));
```

Condition(s):

```
p_ax_dat->network.init == ncTRUE
```

Data structure ACP10SAFEOUTDAT2_typ (also used for function block SafeMC_ReadSafeOutData2):

Reset	USINT	Reset bit
Activate	USINT	Activates the SafeMOTION module
RequestSTO	USINT	STO control bit
RequestSBC	USINT	SBC control bit
RequestSS1	USINT	SS1 control bit
reserved_ctrl_b5	*USINT*	*Reserved*
RequestSTO1	USINT	STO1 control bit
reserved_ctrl_b7	*USINT*	*Reserved*
RequestSOS	USINT	SOS control bit
RequestSS2	USINT	SS2 control bit
RequestSLA	USINT	SLA control bit
RequestSLS1	USINT	SLS1 control bit
RequestSLS2	USINT	SLS2 control bit
reserved_ctrl_b13	*USINT*	*Reserved*
RequestSLS3	USINT	SLS3 control bit
RequestSLS4	USINT	SLS4 control bit
RequestSDIpos	USINT	SDI control bit (positive direction)
RequestSDIneg	USINT	SDI control bit (negative direction)
RequestSLI	USINT	SLI control bit
RequestSBT	USINT	SBT control bit
reserved_ctrl_b20	*USINT*	*Reserved*
RequestSLT	USINT	SLT control bit (V5.030 and later)
reserved_ctrl_b22	*USINT*	*Reserved*
reserved_ctrl_b23	*USINT*	*Reserved*
reserved_ctrl_b24	*USINT*	*Reserved*
RequestHoming	USINT	Homing control bit
RequestSwitch	USINT	Reference Switch
RequestSLP	USINT	SLP control bit
reserved_ctrl_b28	*USINT*	*Reserved*
reserved_ctrl_b29	*USINT*	*Reserved*
SwitchHomingMode	USINT	Switch Homing Mode Bit
reserved_ctrl_b31	*USINT*	*Reserved*

6.7.3.3.2.4 READ_SAFEIN_DATA2: Read SafeIN data 2

Information:

Function READ_SAFEIN_DATA2 and associated data type ACP10SAFEINDAT2_typ are only available for ACOPOS P3 SafeMOTION EnDat 2.2 servo drives.

Parameter:

```
ACP10SAFEINDAT2_typ safein_data2;
```

Function call:

```
SafeMC_action(ax_obj,SafeMC_action_READ_SAFEIN_DATA2,
&safein_data2,sizeof(safein_data2));
```

Condition(s):

```
p_ax_dat->network.init == ncTRUE
```

Data structure ACP10SAFEINDAT2_typ (also used for function block SafeMC_ReadSafeInData2):

NotErrFUNC	USINT	Functional fail safe status bit
Operational	USINT	Function block is in the OPERATIONAL state
SafetyActiveSTO	USINT	STO status bit
SafetyActiveSBC	USINT	SBC status bit
SafetyActiveSS1	USINT	SS1 status bit
NotErrENC	USINT	Encoder error status bit
SafetyActiveSTO1	USINT	STO1 status bit
SafetyActiveSDC	USINT	Delay monitoring is active
SafetyActiveSOS	USINT	SOS status bit
SafetyActiveSS2	USINT	SS2 status bit
SafetyActiveSLA	USINT	SLA status bit
SafetyActiveSLS1	USINT	SLS1 status bit
SafetyActiveSLS2	USINT	SLS2 status bit
reserved_stat_b13	*USINT*	*Reserved*
SafetyActiveSLS3	USINT	SLS3 status bit
SafetyActiveSLS4	USINT	SLS4 status bit
SafetyActiveSDIpos	USINT	SDI status bit (positive direction)
SafetyActiveSDIneg	USINT	SDI status bit (negative direction)
SafetyActiveSLI	USINT	SLI status bit
SafetyActiveSBT	USINT	SBT is active
SafetyStatusSBT	USINT	SBT status bit
SafetyActiveSLT	USINT	SLT status bit (V5.030 and later)
StatusSFR	USINT	At least one safety function has been requested
AllReqFuncAct	USINT	All requested safety functions are active
NotErrENC2	USINT	Encoder error status bit 2
SafePositionValid	USINT	Safe position successfully homed and is valid
ReqHomingOK	USINT	Request Homing OK Bit
SafetyActiveSLP	USINT	SLP status bit
SafetyActiveSMP	USINT	SMP status bit
reserved_stat_b29	*USINT*	*Reserved*
RSPValid	USINT	RSP Valid Bit
StatusSetPosAlive	USINT	Position setpoint has been tested
ScaledSpeed	INT	Scaled safe speed
SafePosition	DINT	Safe position
reserve1	*UINT*	*Reserved*
reserve2	*UDINT*	*Reserved*

6.7.3.3.2.5 Example: Accessing SafeOUT and SafeIN data

```
#include <bur/plctypes.h>
#include <SafeMC.h>
_LOCAL UINT                status_ncaccess;
_LOCAL UINT                status_safeout;
_LOCAL UINT                status_safein;
_LOCAL UDINT               ax_obj;
_LOCAL ACP10AXIS_typ       *p_ax_dat;
_LOCAL ACP10SAFEOUTDAT_typ safeout_data;
_LOCAL ACP10SAFEINDAT_typ  safein_data;
void _INIT SafeMC_accessINIT( void )
{
    status_ncaccess = ncaccess(ncACP10MAN,"AxisObj1",(void *)&ax_obj);
    p_ax_dat = (ACP10AXIS_typ*)ax_obj;
}
void _CYCLIC SafeMC_accessCYCLIC( void )
{
    if ( status_ncaccess != ncOK )
    {
        return;
    }
    if ( p_ax_dat->network.init == ncTRUE )
    {
        status_safeout = SafeMC_action(ax_obj, SafeMC_action_READ_SAFEOUT_DATA,
                                       &safeout_data,sizeof(safeout_data));
        status_safein  = SafeMC_action(ax_obj, SafeMC_action_READ_SAFEIN_DATA,
```

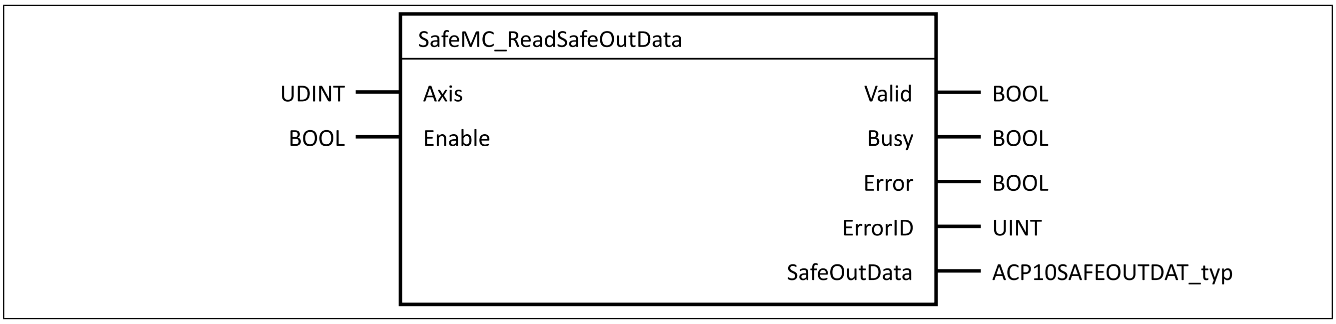
```
                                            &safein_data,sizeof(safein_data));
    }
}
```

6.7.3.3.3 Accessing SafeMOTION data using SafeMOTION function blocks

6.7.3.3.3.1 Function block SafeMC_ReadSafeOutData: Read SafeOUT data

> ## Information:
> **Function SafeMC_ReadSafeOutData and associated data type ACP10SAFEOUTDAT_typ are only available for ACOPOSmulti SafeMOTION inverter modules (EnDat 2.2 and SinCos) and ACOPOSmotor SafeMOTION EnDat 2.2.**

Function block



Parameter

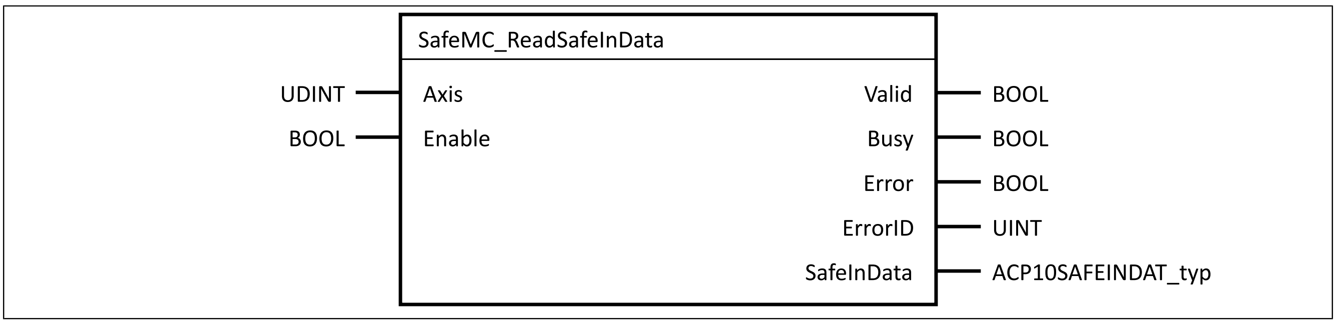
I/O	Parameter	Data type	Description
IN	Axis	UDINT	Axis reference (NC object)
IN	Enable	BOOL	If "Enable" is set, then the data will be read.
OUT	Valid	BOOL	Indicates that data in the output data structure is valid
OUT	Busy	BOOL	Function block not yet completed
OUT	Error	BOOL	Indicates a function block error
OUT	ErrorID	UINT	Function block error code (see 6.7.3.3.1 "function SafeMC_action(): Perform SafeMOTION action / Error codes" on page 483)
OUT	SafeOutData	ACP10SAFEOUTDAT_typ	Output data structure

Data structure ACP10SAFEOUTDAT_typ, see 6.7.3.3.2.1 "READ_SAFEOUT_DATA: ReadSafeOUT data / data structure" on page 483

6.7.3.3.3.2 Function block SafeMC_ReadSafeInData: Read SafeIN data

> ## Information:
> **Function SafeMC_ReadSafeInData and associated data type ACP10SAFEINDAT_typ are only available for ACOPOSmulti SafeMOTION inverter modules (EnDat 2.2 and SinCos) and ACOPOSmotor SafeMOTION EnDat 2.2.**

Function block



Parameter

I/O	Parameter	Data type	Description
IN	Axis	UDINT	Axis reference (NC object)
IN	Enable	BOOL	If "Enable" is set, then the data will be read.
OUT	Valid	BOOL	Indicates that data in the output data structure is valid

I/O	Parameter	Data type	Description
OUT	Busy	BOOL	Function block not yet completed
OUT	Error	BOOL	Indicates a function block error
OUT	ErrorID	UINT	Function block error code (see "function SafeMC_action(): Perform SafeMOTION action / Error codes" on page)6.7.3.3.1 "Function SafeMC_action(): Perform SafeMOTION action" on page 483
OUT	SafeInData	ACP10SAFEINDAT_typ	Output data structure

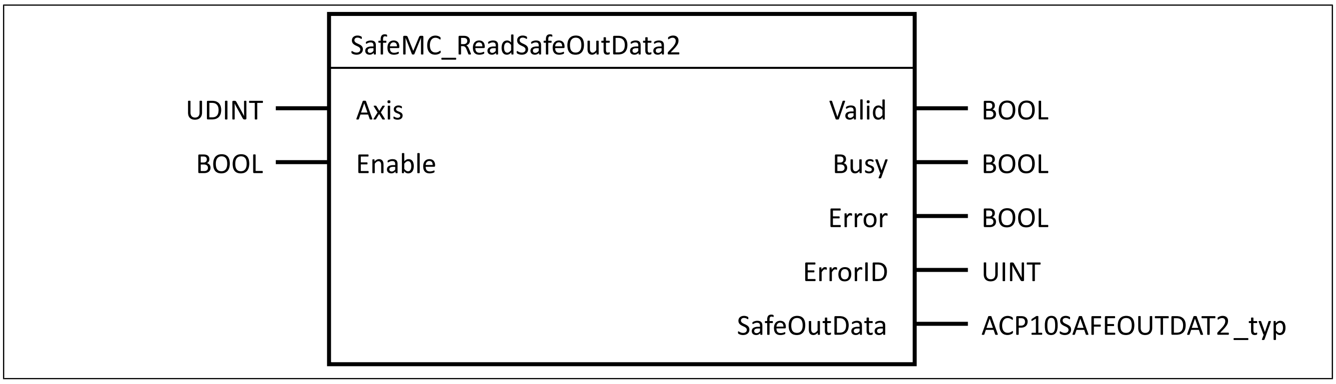
Data structure ACP10SAFEINDAT_typ, see 6.7.3.3.2.2 "READ_SAFEIN_DATA: Read SafeIN data / data structure" on page 484

6.7.3.3.3.3 Function block SafeMC_ReadSafeOutData2: Read SafeOut data 2

Information:

Function block SafeMC_ReadSafeOutData2 and associated data type ACP10SAFEOUTDAT2_typ are only available for ACOPOS P3 SafeMOTION EnDat 2.2 servo drives.

Function block



Parameter

I/O	Parameter	Data type	Description
IN	Axis	UDINT	Axis reference (NC object)
IN	Enable	BOOL	If "Enable" is set, then the data will be read.
OUT	Valid	BOOL	Indicates that data in the output data structure is valid
OUT	Busy	BOOL	Function block not yet completed
OUT	Error	BOOL	Indicates a function block error
OUT	ErrorID	UINT	Function block error code (see 6.7.3.3.1 "function SafeMC_action(): Perform SafeMOTION action / Error codes" on page 483)
OUT	SafeOutData	ACP10SAFEOUTDAT2_typ	Output data structure

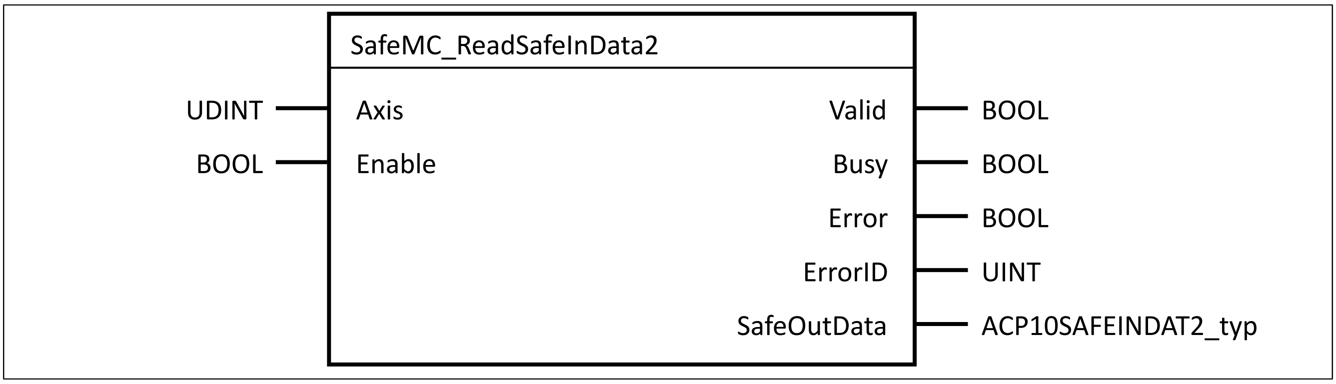
Data structure ACP10SAFEOUTDAT2_typ, see 6.7.3.3.2.3 "READ_SAFEOUT_DATA2: Read SafeOUT data 2 / data structure" on page 485

6.7.3.3.3.4 Function block SafeMC_ReadSafeInData2: Read SafeIN data 2

Information:

Function block SafeMC_ReadSafeInData2 and associated data type ACP10SAFEINDAT2_typ are only available for ACOPOS P3 SafeMOTION EnDat 2.2 servo drives.

Function block



Parameter

I/O	Parameter	Data type	Description
IN	Axis	UDINT	Axis reference (NC object)
IN	Enable	BOOL	If "Enable" is set, then the data will be read.
OUT	Valid	BOOL	Indicates that data in the output data structure is valid
OUT	Busy	BOOL	Function block not yet completed
OUT	Error	BOOL	Indicates a function block error
OUT	ErrorID	UINT	Function block error code (see "function SafeMC_action(): Perform SafeMOTION action / Error codes" on page)6.7.3.3.1 "Function SafeMC_action(): Perform SafeMOTION action" on page 483
OUT	SafeInData	ACP10SAFEINDAT2_typ	Output data structure

Data structure ACP10SAFEINDAT_typ, see 6.7.3.3.2.4 "READ_SAFEIN_DATA2: Read SafeIN data 2 / data structure" on page 485

6.7.3.3.3.5 Example: Accessing SafeOUT and SafeIN data

```
#include <bur/plctypes.h>
#include <SafeMC.h>
_LOCAL UINT                         status_ncaccess;
_LOCAL UDINT                        ax_obj;
_LOCAL ACP10AXIS_typ                *p_ax_dat;
_LOCAL SafeMC_ReadSafeOutData_typ SafeMC_ReadSafeOutData_0;
_LOCAL SafeMC_ReadSafeInData_typ  SafeMC_ReadSafeInData_0;
void _INIT SafeMC_accessINIT( void )
{
    status_ncaccess = ncaccess(ncACP10MAN,"AxisObj1",(void *)&ax_obj);
    p_ax_dat = (ACP10AXIS_typ*)ax_obj;
    SafeMC_ReadSafeOutData_0.Axis = ax_obj;
    SafeMC_ReadSafeInData_0.Axis  = ax_obj;
}
void _CYCLIC SafeMC_accessCYCLIC( void )
{
    if ( status_ncaccess != ncOK )
    {
        return;
    }
    SafeMC_ReadSafeOutData_0.Enable = p_ax_dat->network.init;
    SafeMC_ReadSafeOutData(&SafeMC_ReadSafeOutData_0);
    SafeMC_ReadSafeInData_0.Enable  = p_ax_dat->network.init;
    SafeMC_ReadSafeInData(&SafeMC_ReadSafeInData_0);
}
```

6.7.4 Validating the safety functions

Danger!

You are responsible for the functional testing of protective equipment.

You must therefore validate the protective equipment!

Information:

Applicable standards specify certain processes that must be followed when developing safety-related applications. You are solely responsible for establishing and adhering to these processes.

Danger!

Safety applications are only permitted to be developed by qualified personnel. Acceptance of the final product, validation and verification in particular, must also be performed by qualified personnel.

When commissioning a machine, the complete safety application must be tested, validated and verified in accordance with the SRS (Safety Requirements Specification).

When performing a comprehensive safety function test, all specified limits and timing values must be tested in accordance with the SRS. All monitored limits must be violated and the respective error responses then evaluated.

Each of the safety functions being used must be fully tested in regard to their respective limit values.
The physical units of the monitored limits must be tested! A function is considered "in use" if the respective function block input is used in the safety application.

The following tests are mandatory in all cases:

Safety function	Selects/Deselects the safety function	Checks the safe outputs	Violation of the deceleration ramp	Violation of the monitored speed limit	Violation of the monitored path
STO	✓	✓	---	---	---
STO1	✓	✓	---	---	---
SBC	✓	✓	---	---	---
SOS	✓	---	---	✓	✓
SS1	✓	✓	✓	---	---
SS2	✓	---	✓	✓	---
SLS1	✓	---	✓	✓	---
SLS2	✓	---	✓	✓	---
SLS3	✓	---	✓	✓	---
SLS4	✓	---	✓	✓	---
SMS	---	---	---	✓	---
SDIpos	✓	---	---	---	✓
SDIneg	✓	---	---	---	✓
SLI	✓	---	---	---	✓
SLP	✓	---	✓ 1)	✓ 1)	✓
SMP	---	---	✓ 1)	✓ 1)	✓
SBT 2)	✓	Violation of upper/lower limit for test torque or torque of external load			✓
SLA 3)	✓	Violation of monitored limit for acceleration or deceleration with respect to current direction of movement			---
RSP 4)	Checked by performing the RSP procedure				
SLT 5)	✓	Monitored torque limit exceeded			

Table 312: Test matrix for the safety functions

1) Speed limit calculated dynamically according to the current position.
2) Available with Safety Release 1.7 or later and only for ACOPOSmulti SafeMOTION SinCos!
3) Available with Safety Release 1.9 or later!
4) Available with Safety Release 1.9 and later and only for SafeMOTION EnDat 2.2!
5) Safety Release 1.10 and later, hardware upgrades 1.10.2.x and later for ACOPOS P3 SafeMOTION only!

Danger!

Check the parameter settings for the unit system! An incorrectly configured unit system can cause dangerous situations since the monitored limits may not correspond to the physical limits under certain conditions!

6.7.5 Maintenance scenarios

6.7.5.1 Commissioning

When commissioning a machine, its safety functions must always undergo comprehensive testing, as described in 6.7.4 "Validating the safety functions" on page 491.

Danger!

All of the safety functions that are being used must be tested.
A function is considered to be "in use" if the corresponding input is connected or the safety function has been configured!

6.7.5.2 Replacing safe modules

The SafeLOGIC controller independently detects when safe modules have been replaced. Following a module replacement, the overall system (SafeLOGIC, openSAFETY) automatically ensures that the module is operated again using the correct parameters and that incompatible modules are rejected.

Replacing a safe ACOPOSmulti SafeMOTION inverter module or ACOPOS P3 SafeMOTION servo drive can result in the following potential errors. These errors must be excluded through testing:

- Wiring errors in the motor connection
- Wiring errors in the motor holding brake connection
- Connection of the wrong encoder

Danger!

Check all safety functions that are implemented on the replaced SafeMOTION inverter module!
Always validate the entire safety function!

6.7.5.3 Replacing a safe encoder/motor

If a safe EnDat 2.2 FS encoder is replaced on a safe ACOPOSmulti SafeMOTION EnDat 2.2 inverter module or safe ACOPOS P3 SafeMOTION servo drive, this will be detected as a module replacement on the SafeLOGIC controller and must be acknowledged accordingly.

The SafeLOGIC controller does not detect when a motor or encoder is replaced on the safe ACOPOSmulti SafeMOTION SinCos inverter!

After the replacement, test the safety functions configured on the affected axis.

Danger!

An ACOPOSmotor SafeMOTION module can only be replaced in its entirety.

Replacing individual components is not possible since they are permanently installed.

Danger!

Check all safety functions that are implemented on the replaced SafeMOTION inverter module!
Always validate the entire safety function!

6.7.5.4 Firmware updates / Acknowledging updated firmware

Changes to safety-related parts of the firmware are distributed by B&R as firmware updates.
Safety-relevant firmware is only permitted to be updated by qualified personnel.
A firmware update is indicated on the SafeLOGIC controller and must be acknowledged accordingly.

Danger!

A complete functional test must be performed following any modification to the firmware.

Danger!

Check the installed firmware version of the SafeMOTION modules used against the version listed in the respective certificate.

6.7.5.5 Decommissioning a system

SafeMOTION modules have a mission time of maximum 20 years.
This means that all SafeMOTION modules must be taken out of service one week (at the latest) before the expiration of this 20 year time span (starting from B&R's delivery date).

Danger!

Operating SafeMOTION modules beyond the specified mission time is not permitted!

The user must ensure that all SafeMOTION modules are replaced by new SafeMOTION modules or removed from operation before their mission time expires.

7 PLCopen_Motion_SF_2

7.1 Overview

Overview of the function blocks in the PLCopen_Motion_SF_2 library

Function block	Description	Safety Release
SF_SafeMC_BR	Assignment of safety functions	Safety Release 1.3 or later
SF_SafeMC_Speed_BR	Links the safe speed of an axis and the associated status of the encoder error	
SF_SafeMC_BR_V2	Assignment of safety functions	Safety Release 1.4 or later
SF_SafeMC_Position_BR	Links the safe position of an axis and the associated status	
SF_SafeMC_SBT_BR	Safe brake test	Safety Release 1.7 or later
SF_SafeMC_BR_V3	Assignment of safety functions	Safety Release 1.9 or later
SF_SafeMC_Position_BR_V2	Links the safe position of an axis and the associated status	

Table 313: Overview of the function blocks in the PLCopen_Motion_SF_2 library

7.2 Term definitions

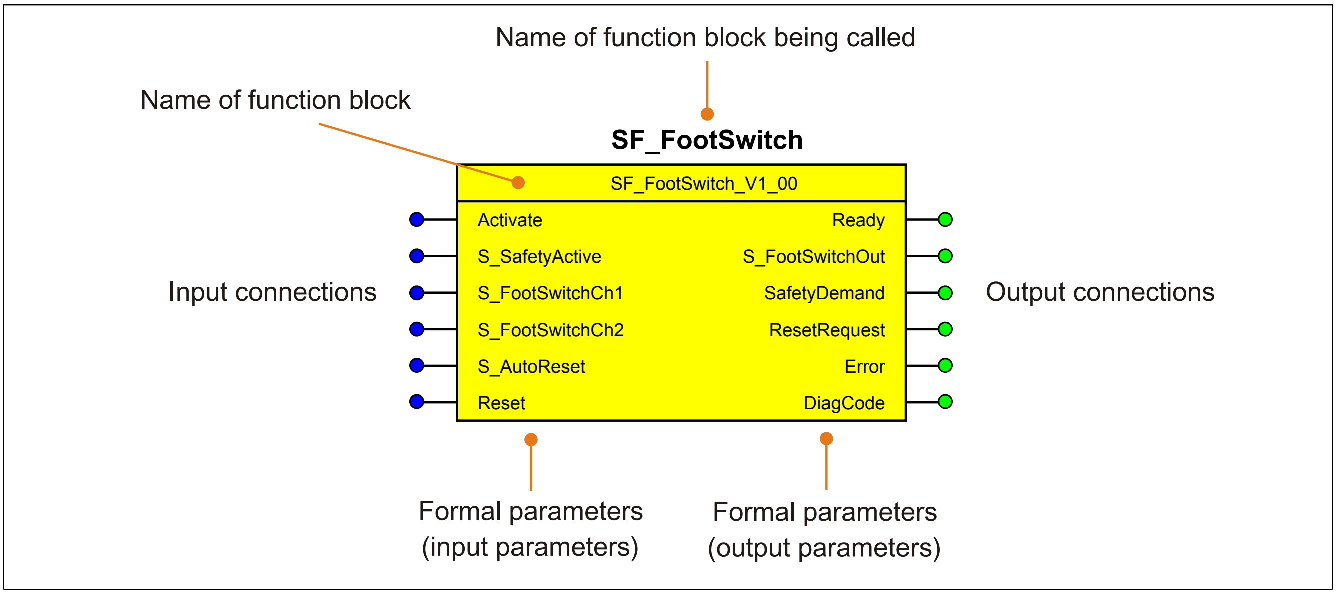


Figure 110: Components of a function block

When calling a function block, the inputs supply the input parameters with the current values of the variables or constants.
The output parameters supply the outputs with the associated values.

Inputs and outputs do not need to have the same name as the associated formal parameters, but they must be of the same data type. A difference in data type between formal parameters and inputs/outputs is reported as an error after compilation.

The name of a function block is composed of the function itself (e.g. "SF_FootSwitch", SF = safety function) and its version (Vx_yz). The format used to represent the version number in this document, Vx_yz, is a placeholder. For the actual version, see the function block being used.

7.3 SF_SafeMC_BR

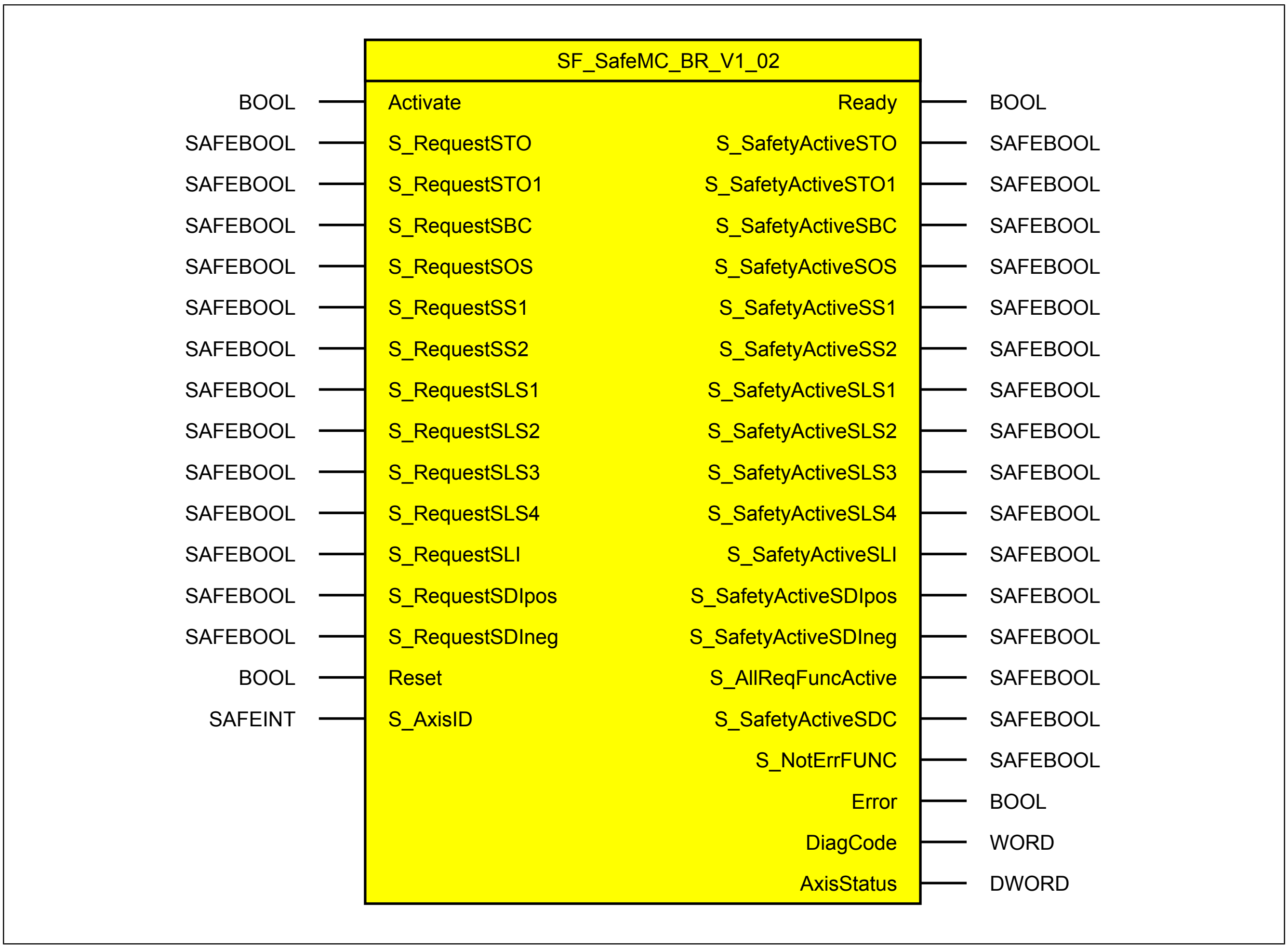


Figure 111: Function block SF_SafeMC_BR

7.3.1 Formal parameters of the function block

In the following, the term "variable" refers to both a variable as well as a graphic connection.

Name	Type	Connection	Signal type [1)]	Initial value	Description / General function
Activate	BOOL	Variable/ Constant	State	FALSE	Enables the function block (= TRUE)
S_RequestSTO	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	STO safety function request: SAFEFALSE: Safety function requested
S_RequestSTO1	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	STO1 safety function request: SAFEFALSE: Safety function requested
S_RequestSBC	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SBC safety function request: SAFEFALSE: Safety function requested
S_RequestSOS	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SOS safety function request: SAFEFALSE: Safety function requested
S_RequestSS1	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SS1 safety function request: SAFEFALSE: Safety function requested
S_RequestSS2	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SS2 safety function request: SAFEFALSE: Safety function requested
S_RequestSLS1	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLS1 safety function request: SAFEFALSE: Safety function requested
S_RequestSLS2	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLS2 safety function request: SAFEFALSE: Safety function requested
S_RequestSLS3	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLS3 safety function request: SAFEFALSE: Safety function requested
S_RequestSLS4	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLS4 safety function request: SAFEFALSE: Safety function requested
S_RequestSLI	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLI safety function request: SAFEFALSE: Safety function requested
S_RequestSDIpos	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SDIpos safety function request: SAFEFALSE: Safety function requested
S_RequestSDIneg	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SDIneg safety function request: SAFEFALSE: Safety function requested
Reset	BOOL	Variable	Edge	FALSE	Resets error messages and the SafeMOTION module after the cause of the error has been removed
S_AxisID	SAFEINT	Constant	State	-1	Assigns an axis to the function block

Table 314: SF_SafeMC_BR: Overview of input parameters

1) Evaluation of the input parameter signals in the function block. The signals must be controlled accordingly by the user.

Name	Type	Connection	Signal type [1)]	Initial value	Description / General function
Ready	BOOL	Variable	State	FALSE	Indicates that the function block is enabled
S_SafetyActiveSTO	SAFEBOOL	Variable	State	SAFEFALSE	STO safety function active (= SAFETRUE)
S_SafetyActiveSTO1	SAFEBOOL	Variable	State	SAFEFALSE	Safety function STO1 active (= SAFETRUE)
S_SafetyActiveSBC	SAFEBOOL	Variable	State	SAFEFALSE	SBC safety function active (= SAFETRUE)
S_SafetyActiveSOS	SAFEBOOL	Variable	State	SAFEFALSE	SOS safety function active, no violation of a monitored limit (= SAFETRUE)
S_SafetyActiveSS1	SAFEBOOL	Variable	State	SAFEFALSE	SS1 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSS2	SAFEBOOL	Variable	State	SAFEFALSE	SS2 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSLS1	SAFEBOOL	Variable	State	SAFEFALSE	SLS1 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSLS2	SAFEBOOL	Variable	State	SAFEFALSE	SLS2 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSLS3	SAFEBOOL	Variable	State	SAFEFALSE	SLS3 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSLS4	SAFEBOOL	Variable	State	SAFEFALSE	SLS4 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSLI	SAFEBOOL	Variable	State	SAFEFALSE	SLI safety function active, no violation of a monitored limit (= SAFETRUE)
S_SafetyActiveSDIpos	SAFEBOOL	Variable	State	SAFEFALSE	SDIpos safety function active (= SAFETRUE)

Table 315: SF_SafeMC_BR: Overview of output parameters

Name	Type	Connection	Signal type [1]	Initial value	Description / General function
S_SafetyActiveSDIneg	SAFEBOOL	Variable	State	SAFEFALSE	Safety function SDIneg active (= SAFETRUE)
S_AllReqFuncActive	SAFEBOOL	Variable	State	SAFEFALSE	All requested safety functions have achieved their safe state. (= SAFETRUE)
S_SafetyActiveSDC	SAFEBOOL	Variable	State	SAFEFALSE	Deceleration monitoring active (= SAFETRUE)
S_NotErrFUNC	SAFEBOOL	Variable	State	SAFEFALSE	SafeMOTION module not in the FUNCTIONAL FAIL SAFE state (= SAFETRUE)
Error	BOOL	Variable	State	FALSE	Function block error message
DiagCode	WORD	Variable	State	16#0000	Function block diagnostic message
AxisStatus	DWORD	Variable	State	32#00000000	Status information from axis

Table 315: SF_SafeMC_BR: Overview of output parameters

1) Output of the output parameter signals. The signals must be evaluated and/or further processed accordingly by the user.

Type	Description	Size in bits	Format option
BOOL	Bit	1	Bit string
WORD	Word	16	Bit string
DINT	Double integer	32	Binary number, hexadecimal number, signed decimal number
SAFEBOOL	Bit	1	Bit string (signal source: safe device)
SAFEDWORD	Double word	32	Bit string (signal source: safe device)
SAFEDINT	Double integer	32	Binary number, hexadecimal number, signed decimal number (signal source: safe device)
SAFEINT	Integer	16	Binary number, hexadecimal number, signed decimal number (signal source: safe device)

Table 316: Format description of the data types

You have the option of linking a safe signal with a non-safe input parameter. To do so, use a function block for type conversion.

Caution!

You are responsible for any conversion of a non-safe input parameter to a safe signal.

7.3.2 SafeMOTION module parameters

Group: General settings - Encoder Unit System (previously *Encoder Unit System*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>EUS - Count of physical reference system

(previously Count of physical reference system)</td><td>-</td><td>Rotary encoder unit scale: X revolutions
Linear encoder unit scale: X reference lengths (reference length = length of the physical reference system)

Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration).
For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.</td><td>1</td><td>R 1.4</td></tr>
<tr><td>EUS - Units per count of physical reference system

(previously Units per count of physical reference system [units])</td><td>[units]</td><td>Rotary encoder unit scale: Units per x revolutions
Linear encoder unit scale: Units per x reference lengths

Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration).
For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.</td><td>1000</td><td>R 1.4</td></tr>
<tr><td>EUS - Counting direction

(previously Counting direction)</td><td>Standard / Inverse</td><td>Counting direction of the position or speed<table><tr><th>Value</th><th>Description</th></tr><tr><td>Default</td><td>Encoder counting direction is equal to the counting direction of the unit system.</td></tr><tr><td>Inverse</td><td>Encoder counting direction is negative to the counting direction of the unit system.</td></tr></table></td><td>Default</td><td>R 1.3</td></tr>
<tr><td>EUS - Maximum speed to normalize speed range

(previously Maximum speed to normalize the speed range (units/s))</td><td>[units/s]</td><td>Maximum speed to which the displayed speed should be normalized</td><td>32767</td><td>R 1.3</td></tr>
</table>

Table 317: SafeMOTION parameter group: General settings - Encoder Unit System

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 318: SafeMOTION parameter group: General settings - Ramp monitoring

Group: Basic functions - SS1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS1 - Ramp monitoring - Enable

(previously Rampmonitoring for SS1)</td><td>Enabled/ Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SS1 function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When transitioning to the safe state of the SS1 function, a deceleration ramp is monitored in addition to the configurable time.</td></tr><tr><td>Disabled</td><td>When transitioning to the safe state of the SS1 function, only a configurable time is monitored.</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS1</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 319: SafeMOTION parameter group: Basic functions - SS1

Group: Speed functions - SS2 (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SS2 - Ramp monitoring - Enable (previously *Rampmonitoring for SS2*)	Enabled/ Disabled	Activates ramp monitoring (in addition to time-based monitoring) when the SS2 function is requested **Value** / **Description** Enabled: When changing to the safe state of the SS2 function, a deceleration ramp is also monitored, in addition to the configurable time Disabled: When changing to the safe state of the SS2 function, only a configurable time is monitored	Enabled	R 1.3
Ramp Monitoring Time for SS2 (us)	[µs]	Deceleration ramp monitoring time for SS2	0	R 1.3

Table 320: SafeMOTION parameter group: Speed functions - SS2

Group: General settings - Automatic reset on start (previously *General Settings*)

Parameter	Unit	Description	Default value	Used Starting in Safety Release
Automatic reset on start - Enable (previously *Automatic Reset at Startup*)	Enabled/ Disabled	Activates automatic reset of the function block at startup **Value** / **Description** Enabled: After startup, the module automatically changes to state OPERATIONAL (Startreset). The reset input does not have to be controlled! Disabled: After startup, the module remains in an Init state until a positive edge of the reset input is detected.	Disabled	R1.3

Table 321: SafeMOTION parameter group: General settings - Automatic reset on start

Group: Basic functions - STO1 (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
STO1 - Channel (previously *Channel selection for One Channel STO (STO1)*)	High-side/ Low-side	Selects the high-side or low-side IGBT in the STO1 function **Value** / **Description** High-side: The high-side IGBTs are actuated with the function STO1. Low-side: The low-side IGBTs are actuated with the function STO1.	High-side	R 1.3

Table 322: SafeMOTION parameter group: Basic functions - STO1

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SMS - Enable (previously *Safe Maximum Speed*)	Enabled/ Disabled	Activates the SMS safety function by configuration **Value** / **Description** Enabled: SMS activated Disabled: SMS deactivated	Enabled	R 1.3
SMS - Speed limit (previously *Maximum Speed for SMS (units/s)*)	[units/s]	Speed limit of the maximum speed (SMS)	0	R 1.3
SLS1 - Speed limit (previously *Safe Speedlimit 1 for SLS (units/s)*)	[units/s]	Speed limit 1 for SLS (SLS1)	0	R 1.3
SLS2 - Speed limit (previously *Safe Speedlimit 2 for SLS (units/s)*)	[units/s]	Speed limit 2 for SLS (SLS2)	0	R 1.3
SLS3 - Speed limit (previously *Safe Speedlimit 3 for SLS (units/s)*)	[units/s]	Speed limit 3 for SLS (SLS3)	0	R 1.3
SLS4 - Speed limit (previously *Safe Speedlimit 4 for SLS (units/s)*)	[units/s]	Speed limit 4 for SLS (SLS4)	0	R 1.3

Table 323: SafeMOTION parameter group: Speed functions - SMS/SLS

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SLS - Ramp monitoring - Enable

(previously Rampmonitoring for SLS)</td><td>Enabled/ Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr><tr><td>Disabled</td><td>When changing to the safe state of the SLS function, only a configurable time is monitored</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SLS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS1</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS2 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS2</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS3 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS3</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS4 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS4 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS4</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 323: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Encoder monitoring (previously *Encoder Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Encoder monitoring - Safe Encoder Mounting (Hardware upgrade 1.10.3.x and later)</td><td>From motor data record / Approved by user</td><td>Status of the proof of fatigue strength of the encoder mounting<table><tr><th>Value</th><th>Description</th></tr><tr><td>From motor data record</td><td>The status of the encoder mounting is determined using the motor data record.</td></tr><tr><td>Approved by user</td><td>The user confirms safe encoder mounting / no mounting information available in the motor data record.</td></tr></table></td><td>From motor data record</td><td>R1.10</td></tr>
<tr><td>Encoder monitoring - Position error monitoring - Enable

(previously Encoder Position monitoring)</td><td>Enabled/ Disabled</td><td>Enables/Disables monitoring of the position lag error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error monitoring - Enable

(previously Encoder Speed monitoring)</td><td>Enabled/ Disabled</td><td>Activates/Deactivates monitoring of the speed error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position setpoint alive testing (SPA) - Enable

(previously Set position alive testing)</td><td>Enabled/ Disabled</td><td>Activates/Deactivates the monitor that detects whether the position setpoint generated on the SafeMOTION module is frozen.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Disabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position error tolerance

(previously Encoder monitoring Position tolerance (units))</td><td>[units]</td><td>Position lag error tolerance for shaft breakage monitoring</td><td>0</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error tolerance

(previously Encoder monitoring Speed tolerance (units/s))</td><td>[units/s]</td><td>Speed error tolerance for encoder monitoring</td><td>0</td><td>R1.3</td></tr>
</table>

Table 324: SafeMOTION parameter group: General settings - Encoder monitoring

Group: General settings - Behavior of Functional Fail Safe (FFS) (previously *Behavior of Functional Fail Safe*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Used Starting in Safety Release</th></tr>
<tr><td>FFS - Mode

(previously Behavior of Functional Fail Safe)</td><td>STO /
STO1 and STO with time delay</td><td>In the FUNCTIONAL FAIL SAFE state, STO and SBC are activated immediately, or STO1 is activated and then STO after a delay.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>STO</td><td>In the FUNCTIONAL FAIL SAFE state, STO and SBC are activated immediately.</td></tr>
<tr><td>STO1 and STO with time delay</td><td>In the FUNCTIONAL FAIL SAFE state, STO1 and SBC are activated first, and then STO after a delay.</td></tr>
</table></td><td>STO</td><td>R 1.3</td></tr>
<tr><td>FFS - STO Enable delay time

(previously Delay for STO in Functional Fail Safe [µs])</td><td>[µs]</td><td>Delay time between STO1 and STO (and SBC) in the FUNCTIONAL FAIL SAFE state</td><td>0</td><td>R 1.3</td></tr>
<tr><td>FFS - Delay time until brake engages

(previously Delay time until the brake engages [µs])</td><td>[µs]</td><td>Delay time before the brake engages
The second enable channel is activated after this delay time if STO1 and time-delayed STO and SBC are configured for FUNCTIONAL FAIL SAFE.</td><td>0</td><td>R 1.3</td></tr>
<tr><td>FFS - Caused by encoder error
(1.10.1.x for ACOPOSmulti SafeMOTION and hardware upgrade 1.10.2.x or later for ACOPOS P3 SafeMOTION)</td><td>Always / Only if safety functions requiring an encoder are enabled</td><td>Enable FUNCTIONAL FAIL SAFE on encoder error:
Always:
FFS occurs if at least one safety function that requires an encoder is used and an encoder error is present.
Only if safety functions requiring an encoder are enabled:
FFS occurs if at least one safety function that requires an encoder is active and an encoder error is present.</td><td>Always</td><td>R 1.10.1</td></tr>
</table>

Table 325: SafeMOTION parameter group: General settings - Behavior of Functional Fail Safe (FFS)

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 326: SafeMOTION parameter group: General settings - Standstill monitoring

Group: Advanced functions - SLI (previously *Safely Limited Increment*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLI - Position limit (previously *Safe Increments (units)*)	[units]	Maximum movable increments when SLI is active	0	R 1.3
SLI - Disable delay time (previously *SLI Off Delay (µs)*)	[µs]	Switch off delay of SLI	0	R 1.3

Table 327: SafeMOTION parameter group: Advanced functions - SLI

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring*)	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** – **Description** Enabled – "Early Limit Monitoring" is active! Disabled – "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us)*)	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 328: SafeMOTION parameter group: General settings - Early limit monitoring

Group: Basic functions - SBC (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBC - Enable delay time (previously *Delay time to start SBC (us)*)	[µs]	Delay time between the SBC request and activation of the safety function	0	R 1.3

Table 329: SafeMOTION parameter group: Basic functions - SBC

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*)	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 330: SafeMOTION parameter group: Advanced functions - SDI

In a safety application, it is possible for multiple safety functions to be requested at the same time. In order to prevent this from turning into an unsafe situation, the individual safety functions are prioritized on the SafeMOTION module.

If several functions are active, then the lowest speed limit is always the value being monitored.

Information:

The following application rule must be observed:

$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS} \leq$ EUS - Maximum speed to normalize speed range

This is required for setting priority of the safety functions on the SafeMOTION module.

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

7.3.3 Integrated safety functions

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

7.3.4 Fault avoidance

> ## Danger!
> **Validation**
>
> **Each safety function that is used must be validated separately.**
> **It is also necessary to test the entire safety application, including the interactions between individual functions.**

7.3.4.1 Exceeding monitored limits

The SafeMOTION module monitors configurable limits. The drive itself, however, is controlled by the standard application on the standard PLC.

To prevent a violation of a monitored limit, the following points must be observed:

- The movement of the drive must be adapted to the requested safety function and initiated on time.
- The monitored limits must match the calculated limits and movement limitations. Make sure that the different configurations of the unit system match in the safety application and in the standard application!

> ## Danger!
> **Any violation of a monitored limit will cause the module to switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state.**
>
> **The "S_NotErrFUNC" output on the function block is reset, and the drive loses all torque/power and coasts to a stop!**
>
> **Depending on the configuration, the motor holding brake will also be switched to 0 V.**
>
> **In the event of an error, a synchronous axis will no longer be synchronous.**
>
> **Check the Safety Logger in Automation Studio for detailed information about monitoring.**

7.3.4.2 Plausibility error[10)]

Plausibility errors (limit values, data types, variables/constants) that occur when using the function block are detected and reported by either the function block or compiler.

This is not possible in the event of connection errors, however.

The function block does not check for the following errors:

- Actual parameter values or constants are within their valid range but incorrect for the safety function being executed.
- Actual parameters have been connected incorrectly.
- Formal input/output parameters that should have been connected have not been connected.

> ## Danger!
> **Ensuring proper safety function connections (sub-application) is your responsibility as the user!**
>
> **Check the connections when validating the sub-application!**

7.3.4.3 Sporadically changing/toggling signal levels or impermissible signals[11)]

Sporadically changing or toggling signal levels on edge-controlled formal input parameters cause the function block to interpret this signal as an edge, which results in an unintended corresponding action being triggered in the function block if fault avoidance measures are not taken.

Sporadically changing or toggling signal levels on status-controlled input formal parameters will cause the signal to trigger an undesired corresponding action if error prevention measures are not taken.

Impermissible signals on input formal parameters can lead to an unexpected initial movement, non-execution of a requested action or an error message.

Possible causes of these signals:

10) This section applies to all function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF:

11) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR, SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR

- Programming error in the application program (user error)
- Cross fault, short circuit or open circuit (user error, wiring error)
- Error on the standard controller

To prevent this, the following measures can be taken depending on the safety function:

- Using signals from safe devices
- Implementing additional measures for preventing a hazard if using a signal from a standard controller (e.g. executing an additional function start after a safety function has been triggered or an error has been corrected)
- Line control on the safe control system
- Suitable cabling when using non-safe signals from the standard controller
- Verifying the source code in the application program and final validation of the safety functionality

These measures can also be combined to prevent errors.

It is important to note that a signal change detected on a status-controlled formal parameter will be output as a diagnostic code.

7.3.4.4 Simultaneous edge change[12)]

Make sure that the "Reset" formal parameter is only connected to a signal from a manual resetting device to reduce the risk of an unexpected initial movement. This signal is based on your risk analysis.

7.3.4.5 Machine/System startup without performing functional testing of protective equipment[13)]

Faulty protective equipment is only detected following functional testing. Functional testing is not supported by this function block. If additional measures are not taken, faulty protective equipment can result in errors.

> ## Danger!
>
> **You are responsible for the functional testing of protective equipment.**
> **You must therefore validate the protective equipment!**

Possible causes of faulty protective equipment:

- Faulty devices (hardware error)
- Cross fault, short circuit and open circuit (user error, wiring error)

12) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR, SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR

13) This section applies to all function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF:

7.3.5 Input parameters

7.3.5.1 General information about the "S_Request" inputs

The "S_Request" inputs are used to request the respective safety functions.

If a safety function should not be used in the safety application, then the respective input should not be connected.

Information:

If a safety function is not used in the application, then the respective input must remain open.

Danger!

The safety functions that are used must be tested.
A function is considered to be used if the respective input variable is connected!

Information:

At a minimum, the "Activate" and "S_AxisID" inputs must be connected. Otherwise, the SafeMOTION module will not be operated by the SafeLOGIC controller. As a result, the pulse disabling and motor holding brake outputs will be permanently set to 0 V, which means that the controller cannot be turned on.

7.3.5.2 Activate

General function

- Enables the function block

Data type

- BOOL

Connection

- Constant or variable

Function description

This input parameter is used to activate the function block.

- When enabling or disabling safe devices, "Activate" must be linked to a variable that indicates the state (enabled or disabled) of the corresponding safe devices. This ensures that the function block does not output a triggered safety function as diagnostic information when a device is switched off.
- It is also possible to connect "Activate" to a constant (TRUE) in order to enable the function block.

TRUE

The function block is enabled.

FALSE

The function block is not enabled.
All binary output parameters are set to FALSE.
Sets the DiagCode diagnostic parameter to WORD#16#0000.

If you want to control function block diagnostics as needed in your diagnostic concept whenever error messages from safe devices and/or deactivated safe devices occur, connect "Activate" to a signal that indicates the status of the safe devices that are involved with the safety function supported by the function block. Form this signal using only safe devices whose I/O signals are connected to the function block via actual parameters. In this way, you prevent triggered safety functions from being reported by active safe devices. This measure is only used to control the diagnostic information from inactive safe devices in a defined manner.

7.3.5.3 S_RequestSTO

General function

- Selects/Deselects safety function Safe Torque Off, STO

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the STO safety function.

TRUE

The safety function is deselected. Safe pulse disabling is not active!

FALSE

The safety function is selected. Safe pulse disabling is active! Torque/Power are switched off on the drive.

Not connected

The safety function is deactivated.

Relevant configuration parameters

- None

7.3.5.4 S_RequestSTO1

General function

- Selects/Deselects safety function Safe Torque Off, One Channel, STO1

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the STO1 safety function.

TRUE

The safety function is deselected. Safe pulse disabling is not active!

FALSE

The safety function is selected. Depending on the configuration, the high-side or low-side of safe pulse disabling is active! Torque/Power are switched off on the drive.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Basic functions - STO1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>STO1 - Channel

(previously Channel selection for One Channel STO (STO1))</td><td>High-side/
Low-side</td><td>Selects the high-side or low-side IGBT in the STO1 function<table><tr><th>Value</th><th>Description</th></tr><tr><td>High-side</td><td>The high-side IGBTs are actuated with the function STO1.</td></tr><tr><td>Low-side</td><td>The low-side IGBTs are actuated with the function STO1.</td></tr></table></td><td>High-side</td><td>R 1.3</td></tr>
</table>

Table 331: SafeMOTION parameter group: Basic functions - STO1

7.3.5.5 S_RequestSBC

General function

- Selects/Deselects safety function Safe Brake Control, SBC

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SBC safety function.

TRUE

The safety function is deselected. The motor holding brake output is enabled and can be used by the standard application.

FALSE

The safety function is selected. The motor holding brake output is switched to 0 V!

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Basic functions - SBC (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBC - Enable delay time (previously *Delay time to start SBC (us)*)	[µs]	Delay time between the SBC request and activation of the safety function	0	R 1.3

Table 332: SafeMOTION parameter group: Basic functions - SBC

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

7.3.5.6 S_RequestSOS

General function

- Selects/Deselects safety function Safe Operating Stop, SOS

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SOS safety function.

TRUE

The safety function is deselected. Standstill tolerances are not being monitored.

FALSE

The safety function is selected. Standstill tolerances are being monitored.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 333: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ < EUS - Maximum speed to normalize speed range

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.3.5.7 S_RequestSS1

General function

- Selects/Deselects safety function Safe Stop 1, SS1

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SS1 safety function.

TRUE

The safety function is deselected. SS1 is not active!

FALSE

The safety function is selected. Safe pulse disabling is activated after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 334: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Basic functions - SS1 (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SS1 - Ramp monitoring - Enable (previously *Rampmonitoring for SS1*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SS1 function is requested **Value** / **Description** Enabled: When transitioning to the safe state of the SS1 function, a deceleration ramp is monitored in addition to the configurable time. Disabled: When transitioning to the safe state of the SS1 function, only a configurable time is monitored.	Enabled	R 1.3
SS1 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SS1 (us)*)	[µs]	Deceleration ramp monitoring time for SS1	0	R 1.3

Table 335: SafeMOTION parameter group: Basic functions - SS1

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** / **Description** Enabled: "Early Limit Monitoring" is active! Disabled: "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 336: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

To use this function without safe encoder evaluation, "Ramp monitoring for SS1" and "Early Limit Monitoring" must be disabled.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$\mathbf{LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.3.5.8 S_RequestSS2

General function

- Selects/Deselects safety function Safe Stop 2, SS2

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SS2 safety function.

TRUE

The safety function is deselected. SS2 is not active!

FALSE

The safety function is selected. Standstill monitoring is activated after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 337: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SS2 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS2 - Ramp monitoring - Enable

(previously Rampmonitoring for SS2)</td><td>Enabled/
Disabled</td><td>Activates ramp monitoring (in addition to time-based monitoring) when the SS2 function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When changing to the safe state of the SS2 function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr>
<tr><td>Disabled</td><td>When changing to the safe state of the SS2 function, only a configurable time is monitored</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>Ramp Monitoring Time for SS2 (us)</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS2</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 338: SafeMOTION parameter group: Speed functions - SS2

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 339: SafeMOTION parameter group: General settings - Standstill monitoring

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. <table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr><tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr></table>	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 340: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$\mathbf{LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.3.5.9 S_RequestSLS1

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 1

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS1 safety function.

TRUE

The safety function is deselected. SLS1 is not active!

FALSE

The safety function is selected. Speed limit 1 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 341: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLS - Ramp monitoring - Enable (previously *Rampmonitoring for SLS*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested **Value** – **Description** Enabled – When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time Disabled – When changing to the safe state of the SLS function, only a configurable time is monitored	Enabled	R 1.3
SLS1 - Speed limit (previously *Safe Speedlimit 1 for SLS (units/s)*)	[units/s]	Speed limit 1 for SLS (SLS1)	0	R 1.3
SLS1 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS1 (us)*)	[µs]	Deceleration ramp monitoring time for SLS1	0	R 1.3

Table 342: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** – **Description** Enabled – "Early Limit Monitoring" is active! Disabled – "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 343: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$\mathbf{LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.3.5.10 S_RequestSLS2

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 2

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS2 safety function.

TRUE

The safety function is deselected. SLS2 is not active!

FALSE

The safety function is selected. Speed limit 2 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 344: SafeMOTION parameter group: General settings - Ramp monitoring

> ## Danger!
> **The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!**

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLS - Ramp monitoring - Enable (previously *Rampmonitoring for SLS*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested **Value** – **Description** Enabled – When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time Disabled – When changing to the safe state of the SLS function, only a configurable time is monitored	Enabled	R 1.3
SLS2 - Speed limit (previously *Safe Speedlimit 2 for SLS (units/s)*)	[units/s]	Speed limit 2 for SLS (SLS2)	0	R 1.3
SLS2 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS2 (us)*)	[µs]	Deceleration ramp monitoring time for SLS2	0	R 1.3

Table 345: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** – **Description** Enabled – "Early Limit Monitoring" is active! Disabled – "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 346: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$\mathbf{LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.3.5.11 S_RequestSLS3

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 3

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS3 safety function.

TRUE

The safety function is deselected. SLS3 is not active!

FALSE

The safety function is selected. Speed limit 3 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 347: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLS - Ramp monitoring - Enable (previously *Rampmonitoring for SLS*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested **Value** – **Description** Enabled – When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time Disabled – When changing to the safe state of the SLS function, only a configurable time is monitored	Enabled	R 1.3
SLS3 - Speed limit (previously *Safe Speedlimit 3 for SLS (units/s)*)	[units/s]	Speed limit 3 for SLS (SLS3)	0	R 1.3
SLS3 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS3 (us)*)	[µs]	Deceleration ramp monitoring time for SLS3	0	R 1.3

Table 348: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** – **Description** Enabled – "Early Limit Monitoring" is active! Disabled – "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 349: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.3.5.12 S_RequestSLS4

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 4

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS4 safety function.

TRUE

The safety function is deselected. SLS4 is not active!

FALSE

The safety function is selected. Speed limit 4 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 350: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLS - Ramp monitoring - Enable (previously *Rampmonitoring for SLS*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested **Value** – **Description** Enabled – When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time Disabled – When changing to the safe state of the SLS function, only a configurable time is monitored	Enabled	R 1.3
SLS4 - Speed limit (previously *Safe Speedlimit 4 for SLS (units/s)*)	[units/s]	Speed limit 2 for SLS (SLS2)	0	R 1.3
SLS4 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS4 (us)*)	[µs]	Deceleration ramp monitoring time for SLS2	0	R 1.3

Table 351: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** – **Description** Enabled – "Early Limit Monitoring" is active! Disabled – "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 352: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.3.5.13 S_RequestSLI

General function

- Selects/Deselects safety function Safely Limited Increment, SLI

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLI safety function.

TRUE

The safety function is deselected. SLI is not active!

FALSE

The safety function is selected. A safe range of increments is monitored.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3

Table 353: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SLI (previously *Safely Limited Increment*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLI - Position limit (previously *Safe Increments (units)*)	[units]	Maximum movable increments when SLI is active	0	R 1.3
SLI - Disable delay time (previously *SLI Off Delay (µs)*)	[µs]	Switch off delay of SLI	0	R 1.3

Table 354: SafeMOTION parameter group: Advanced functions - SLI

Danger!

The maximum increment range must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

7.3.5.14 S_RequestSDIpos

General function

- Selects/Deselects safety function Safe Direction. Movement is allowed in the positive direction.

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the safety function SDI, movement is allowed in the positive direction of movement.

TRUE

The safety function is deselected. SDI is not active!

FALSE

The direction of movement is monitored after the delay time has expired. Movement is allowed in the positive direction.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 355: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*)	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 356: SafeMOTION parameter group: Advanced functions - SDI

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

7.3.5.15 S_RequestSDIneg

General function

- Selects/Deselects safety function Safe Direction. Movement is allowed in the negative direction.

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the safety function SDI, movement is allowed in the negative direction of movement.

TRUE

The safety function is deselected. SDI is not active!

FALSE

The direction of movement is monitored after the delay time has expired. Movement is allowed in the negative direction.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 357: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*)	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 358: SafeMOTION parameter group: Advanced functions - SDI

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

7.3.5.16 Reset

General function

- "Reset" input for acknowledging the FUNCTIONAL FAIL SAFE state or for putting the SafeMOTION module into OPERATIONAL state after STARTUP

Data type

- BOOL

Connection

- Variable

Function description

"Reset" input to acknowledge the FUNCTIONAL FAIL SAFE state

A positive edge triggers the reset function.

Depending on the configuration of parameter "Automatic Reset at Startup", a positive edge may be necessary to get the SafeMOTION module from state INIT to state OPERATIONAL after startup.

Relevant configuration parameters

Group: General settings - Automatic reset on start (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Used Starting in Safety Release</th></tr>
<tr><td>Automatic reset on start - Enable

(previously Automatic Reset at Startup)</td><td>Enabled/
Disabled</td><td>Activates automatic reset of the function block at startup<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>After startup, the module automatically changes to state OPERATIONAL (Startreset). The reset input does not have to be controlled!</td></tr><tr><td>Disabled</td><td>After startup, the module remains in an Init state until a positive edge of the reset input is detected.</td></tr></table></td><td>Disabled</td><td>R1.3</td></tr>
</table>

Table 359: SafeMOTION parameter group: General settings - Automatic reset on start

Danger!

Parameter "Automatic reset on start" enables/disables the restart interlock during startup or when a network failure occurs on a reestablished network connection.

If parameter "Automatic reset on start" is set to "Enabled", then the module automatically changes to state OPERATIONAL state (i.e. pulse disabling and the motor holding brake are enabled)!

Configuring an automatic restart can result in critical safety conditions. Take additional measures to ensure proper safety-related functionality.

7.3.5.17 S_AxisID

General function

- This input parameter assigns a real axis to the function block.

Data type

- SAFEINT

Connection

- Constant

Function description

The corresponding axis can be connected to the input in SafeDESIGNER using drag-and-drop.

> ## Information:
>
> **There is only permitted to be one combination of AxisID and the SF_SafeMC_BR or SF_SafeMC_BR_Vx function block in the safety application. Otherwise, it will not be possible to compile the safety application.**

7.3.6 Output parameters

Output parameters provide information about the state of the SafeMOTION module and the individual safety functions.

7.3.6.1 Ready

General function

- Message: Function block is enabled/disabled.

Data type

- BOOL

Connection

- Variable

Function description

This output parameter indicates whether the function block is enabled or not.

TRUE

The function block is enabled ("Activate" = TRUE). The output parameters indicate the current state of the safety function.

FALSE

The function block is not enabled ("Activate" = FALSE). The function block outputs are set to FALSE.

7.3.6.2 S_SafetyActiveSTO

General function

- Status information for safety function Safe Torque Off, STO

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the STO safety function

TRUE

The STO safety function is active and currently in its safe state.

FALSE

The STO safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.3.6.3 S_SafetyActiveSTO1

General function

- Status information for safety function Safe Torque Off, One Channel, STO1

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the STO1 safety function

TRUE

The STO1 safety function is active and currently in its safe state.

FALSE

The STO1 safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.3.6.4 S_SafetyActiveSBC

General function

- Status information for safety function Safe Brake Control, SBC

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SBC safety function

TRUE

The SBC safety function is active and currently in its safe state.

FALSE

The SBC safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.3.6.5 S_SafetyActiveSOS

General function

- Status information for safety function Safe Operating Stop, SOS

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SOS safety function

TRUE

The SOS safety function is active and currently in its safe state.

FALSE

The SOS safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.3.6.6 S_SafetyActiveSS1

General function

- Status information for safety function Safe Stop 1, SS1

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SS1 safety function

TRUE

The SS1 safety function is active and currently in its safe state.

FALSE

The SS1 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.3.6.7 S_SafetyActiveSS2

General function

- Status information for safety function Safe Stop 2, SS2

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SS2 safety function

TRUE

The SS2 safety function is active and currently in its safe state.

FALSE

The SS2 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.3.6.8 S_SafetyActiveSLS1

General function

- Status information for safety function Safely Limited Speed, Speed Limit 1

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS1 safety function

TRUE

The SLS1 safety function is active and currently in its safe state.

FALSE

The SLS1 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.3.6.9 S_SafetyActiveSLS2

General function

- Status information for safety function Safely Limited Speed, Speed Limit 2

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS2 safety function

TRUE

The SLS2 safety function is active and currently in its safe state.

FALSE

The SLS2 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.3.6.10 S_SafetyActiveSLS3

General function

- Status information for safety function Safely Limited Speed, Speed Limit 3

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS3 safety function

TRUE

The SLS3 safety function is active and currently in its safe state.

FALSE

The SLS3 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.3.6.11 S_SafetyActiveSLS4

General function

- Status information for safety function Safely Limited Speed, Speed Limit 4

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS4 safety function

TRUE

The SLS4 safety function is active and currently in its safe state.

FALSE

The SLS4 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.3.6.12 S_SafetyActiveSLI

General function

- Status information for safety function Safely Limited Increment

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLI safety function

TRUE

The SLI safety function is active and currently in its safe state.

FALSE

The SLI safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.3.6.13 S_SafetyActiveSDIpos

General function

- Status information for safety function Safe Direction. Movement is allowed in the positive direction.

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SDIpos safety function

TRUE

The SDIpos safety function is active and currently in its safe state.

FALSE

The SDIpos safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.3.6.14 S_SafetyActiveSDIneg

General function

- Status information for safety function Safe Direction. Movement is allowed in the negative direction.

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SDIneg safety function

TRUE

The SDIneg safety function is active and currently in its safe state.

FALSE

The SDIneg safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.3.6.15 S_SafetyActiveSDC

General function

- Information about the status of ramp monitoring

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the status of ramp monitoring.

TRUE

Ramp monitoring is active.

FALSE

Ramp monitoring is not active, the SafeMOTION module is currently in an error state or the function block has not been enabled.

> ## Danger!
> **This signal should only be used for status information.**

7.3.6.16 S_AllReqFuncActive

General function

- Information about the status of the requested safety functions

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies the status of the requested safety functions.

TRUE

All requested safety functions are currently in their functional safe state.

FALSE

One or more safety functions have not yet achieved their safe state, the SafeMOTION module is in an error state or the function block has not been enabled.

7.3.6.17 S_NotErrFUNC

General function

- Information about the error state of the safe SafeMOTION module

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies the error state of the SafeMOTION module.

TRUE

No error was found on the SafeMOTION module.

FALSE

An error was detected on the SafeMOTION module (e.g. a monitored limit was exceeded), or the function block has not been enabled.
In the event of an error, see the Safety Logger in Automation Studio for additional information about the error.
If the error is a functional error, then it can be acknowledged by changing the signal on input "Reset" from FALSE to TRUE (positive edge)!

Danger!

The purpose of this signal is only to provide additional information. It only provides information in connection with the requested safety functions.
"S_NotErrFUNC" does not represent the functional safe state of the SafeMOTION module!

Danger!

It is your responsibility to ensure that all necessary corrective measures are initiated after an error occurs since subsequent errors can result in a hazard!

7.3.6.18 Error

General function

- Function block error message

Data type

- BOOL

Connection

- Variable

Function description

This formal parameter indicates a pending function block error message.

TRUE

The enabled function block detected an error. "DiagCode" indicates the error code.

FALSE

The function block is not enabled, or the enabled function block did not detect an error. "DiagCode" indicates the status.

> ## Danger!
>
> **It is your responsibility to ensure that all necessary corrective measures are initiated after an error occurs since subsequent errors can result in a hazard!**

In order to exit an error state ("Error" = TRUE), the signal on the "Reset" input must change from FALSE to TRUE (positive edge).

7.3.6.19 DiagCode

General function

- Function block diagnostic message

Data type

- WORD

Connection

- Variable

Function description

This output parameter is used to output diagnostic and status messages specific to the function block and make them available automatically to diagnostic tools.

These diagnostic tools cannot acknowledge diagnostic messages from function blocks. This is done exclusively in the **safety** application.

The function block indicates the presence of an error message on the "DiagCode" output via the "Error" output parameter.

Diagnostic code

The diagnostic code is specified as data type WORD. The values and meanings of these diagnostic codes are listed below.

In the event of status messages ($0xxx_{hex}$, $8xxx_{hex}$), the function block sets "Error" to FALSE.

In the event of error messages ($Cxxx_{hex}$), the function block sets "Error" to TRUE.

7.3.6.20 Diagnostic codes

Code (hex)	State	Description	Possible workaround
0000	IDLE	The function block is not active.	Enable the function block by setting "Activate" to TRUE.
8001	INIT	The function block has been enabled and the SafeMOTION module is in the INIT state. The SafeMOTION module restart interlock is active.	Configure parameter "Startreset" accordingly or change to a positive edge on input "Reset".
8002	OPERATIONAL	The SafeMOTION module is in the OPERATIONAL state. No safety function is selected. The SMS speed limit is monitored according to the configuration.	No action required
8003	WAIT FOR CONFIRMATION	The SafeMOTION module is in the internal OPERATIONAL state. At least one safety function has been requested and at least one safety function has not yet achieved its functional safe state. None of the limits currently being monitored have been violated.	No action required
8000	SAFE STATE	All requested safety functions have achieved their functional safe state. None of the limits currently being monitored have been violated.	No action required
C000	FUNCTIONAL FAIL SAFE	An error occurred!	Check the Safety Logger in Automation Studio. It will provide detailed information about the current error. Depending on the type of error, check the standard and/or safety application. For functional errors, check the configuration of the SafeMOTION module or replace the faulty SafeMOTION module.

Table 360: SF_SafeMC_BR(_V2, _V3): Diagnostic codes

7.3.6.21 AxisStatus

General function

- Diagnostics message from the function block, representation of the axis status bits in a DWORD

Data type

- DWORD

Connection

- Variable

Function description

The "AxisStatus" output returns bit-coded information about the status of individual safety functions.
This information is equal to a summary of the "S_xxx" outputs in a DWORD.
The individual bits have the following meaning:

Bit 0	Bit 1	Bit 2	Bit 3	Bit 4	Bit 5	Bit 6	Bit 7
Status STO	Status SBC	Status SOS	Status SS1	Status SS2	Status SLS1	Status SLS2	Status SLS3
Bit 8	**Bit 9**	**Bit 10**	**Bit 11**	**Bit 12**	**Bit 13**	**Bit 14**	**Bit 15**
Status SLS4	Status STO1	Status SDI pos	Status SLI	Status SDI neg	-	-	-
Bit 16	**Bit 17**	**Bit 18**	**Bit 19**	**Bit 20**	**Bit 21**	**Bit 22**	**Bit 23**
-	Status Setposition Alive Test	Status SFR	Status All requested safety functions active	Status SDC	Status Operational	Status Not Encoder Error	Status Not Functional Error

Table 361: SF_SafeMC_BR: SafeMOTION module status bits

7.3.7 State machine

The state machine illustrated here is implemented on the SafeMOTION module.

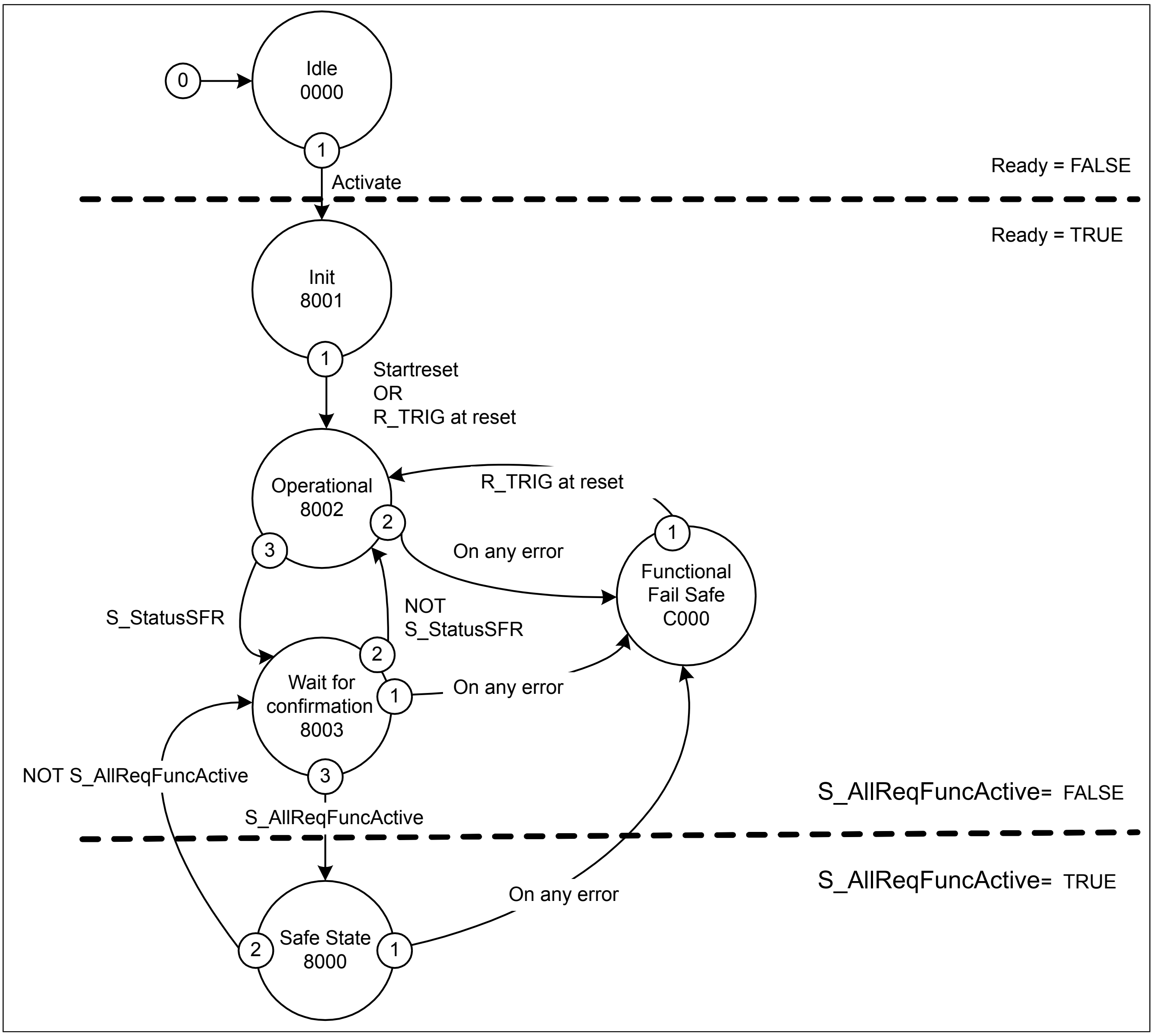


Figure 112: SF_SafeMC_BR(_V2): State machine

Individual states are reflected by the "DiagCode" output parameter. In this way, the function block provides a representation of the state machine on the SafeMOTION module.

7.3.8 Signal sequence diagram of the function block

A general signal sequence diagram of the function block cannot be specified since it depends on which safety functions are selected or deselected.

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

7.4 SF_SafeMC_BR_V2

Information:

The SF_SafeMC_BR_V2_00 function block can only be used with Safety Release 1.4.

If Safety Release 1.3 is being used, then SafeDESIGNER will return an error when compiling the safety application!

7.4.1 Formal parameters of the function block

In the following, the term "variable" refers to both a variable as well as a graphic connection.

Name	Type	Connection	Signal type [1)]	Initial value	Description / General function
Activate	BOOL	Variable/ Constant	State	FALSE	Enables the function block (= TRUE)
S_RequestSTO	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	STO safety function request: SAFEFALSE: Safety function requested
S_RequestSTO1	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	STO1 safety function request: SAFEFALSE: Safety function requested
S_RequestSBC	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SBC safety function request: SAFEFALSE: Safety function requested
S_RequestSOS	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SOS safety function request: SAFEFALSE: Safety function requested
S_RequestSS1	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SS1 safety function request: SAFEFALSE: Safety function requested
S_RequestSS2	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SS2 safety function request: SAFEFALSE: Safety function requested
S_RequestSLS1	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLS1 safety function request: SAFEFALSE: Safety function requested
S_RequestSLS2	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLS2 safety function request: SAFEFALSE: Safety function requested
S_RequestSLS3	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLS3 safety function request: SAFEFALSE: Safety function requested
S_RequestSLS4	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLS4 safety function request: SAFEFALSE: Safety function requested
S_RequestSLI	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLI safety function request: SAFEFALSE: Safety function requested
S_RequestSDIpos	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SDIpos safety function request: SAFEFALSE: Safety function requested
S_RequestSDIneg	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SDIneg safety function request: SAFEFALSE: Safety function requested
S_RequestSLP	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLP safety function request SAFEFALSE: Safety function requested
S_RequestHoming	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safe homing Request is made on a positive edge!
S_ReferenceSwitch	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Safe input for a reference switch
Reset	BOOL	Variable	Edge	FALSE	Resets error messages and the SafeMOTION module after the cause of the error has been removed
S_AxisID	SAFEINT	Constant	State	-1	Assigns an axis to the function block

Table 362: SF_SafeMC_BR_V2: Overview of input parameters

1) Evaluation of the input parameter signals in the function block. The signals must be controlled accordingly by the user.

Name	Type	Connection	Signal type [1)]	Initial value	Description / General function
Ready	BOOL	Variable	State	FALSE	Indicates that the function block is enabled
S_SafetyActiveSTO	SAFEBOOL	Variable	State	SAFEFALSE	STO safety function active (= SAFETRUE)
S_SafetyActiveSTO1	SAFEBOOL	Variable	State	SAFEFALSE	Safety function STO1 active (= SAFETRUE)
S_SafetyActiveSBC	SAFEBOOL	Variable	State	SAFEFALSE	SBC safety function active (= SAFETRUE)
S_SafetyActiveSOS	SAFEBOOL	Variable	State	SAFEFALSE	SOS safety function active, no violation of a monitored limit (= SAFETRUE)
S_SafetyActiveSS1	SAFEBOOL	Variable	State	SAFEFALSE	SS1 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSS2	SAFEBOOL	Variable	State	SAFEFALSE	SS2 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSLS1	SAFEBOOL	Variable	State	SAFEFALSE	SLS1 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSLS2	SAFEBOOL	Variable	State	SAFEFALSE	SLS2 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSLS3	SAFEBOOL	Variable	State	SAFEFALSE	SLS3 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)

Table 363: SF_SafeMC_BR_V2: Overview of output parameters

Name	Type	Connection	Signal type 1)	Initial value	Description / General function
S_SafetyActiveSLS4	SAFEBOOL	Variable	State	SAFEFALSE	SLS4 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSLI	SAFEBOOL	Variable	State	SAFEFALSE	SLI safety function active, no violation of a monitored limit (= SAFETRUE)
S_SafetyActiveSDIpos	SAFEBOOL	Variable	State	SAFEFALSE	SDIpos safety function active (= SAFETRUE)
S_SafetyActiveSDIneg	SAFEBOOL	Variable	State	SAFEFALSE	Safety function SDIneg active (= SAFETRUE)
S_SafetyActiveSLP	SAFEBOOL	Variable	State	SAFEFALSE	SLP safety function active (= SAFETRUE)
S_SafetyActiveSMP	SAFEBOOL	Variable	State	SAFEFALSE	SMP safety function active (= SAFETRUE)
S_SafePositionValid	SAFEBOOL	Variable	State	SAFEFALSE	Specifies whether the safe position is valid (=SAFETRUE, homing procedure has completed successfully and there are no encoder errors)
S_AllReqFuncActive	SAFEBOOL	Variable	State	SAFEFALSE	All requested safety functions have achieved their safe state. (= SAFETRUE)
S_SafetyActiveSDC	SAFEBOOL	Variable	State	SAFEFALSE	Deceleration monitoring active (= SAFETRUE)
S_NotErrFUNC	SAFEBOOL	Variable	State	SAFEFALSE	SafeMOTION module not in the FUNCTIONAL FAIL SAFE state (= SAFETRUE)
Error	BOOL	Variable	State	FALSE	Function block error message
DiagCode	WORD	Variable	State	16#0000	Function block diagnostic message
AxisStatus	DWORD	Variable	State	32#00000000	Status information from axis

Table 363: SF_SafeMC_BR_V2: Overview of output parameters

1) Output of the output parameter signals. The signals must be evaluated and/or further processed accordingly by the user.

Type	Description	Size in bits	Format option
BOOL	Bit	1	Bit string
WORD	Word	16	Bit string
DINT	Double integer	32	Binary number, hexadecimal number, signed decimal number
SAFEBOOL	Bit	1	Bit string (signal source: safe device)
SAFEDWORD	Double word	32	Bit string (signal source: safe device)
SAFEDINT	Double integer	32	Binary number, hexadecimal number, signed decimal number (signal source: safe device)
SAFEINT	Integer	16	Binary number, hexadecimal number, signed decimal number (signal source: safe device)

Table 364: Format description of the data types

You have the option of linking a safe signal with a non-safe input parameter. To do so, use a function block for type conversion.

Caution!

You are responsible for any conversion of a non-safe input parameter to a safe signal.

7.4.2 SafeMOTION module parameters

Group: General settings - Encoder Unit System (previously *Encoder Unit System*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>EUS - Count of physical reference system

(previously Count of physical reference system)</td><td>-</td><td>Rotary encoder unit scale: X revolutions
Linear encoder unit scale: X reference lengths (reference length = length of the physical reference system)

Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration).
For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.</td><td>1</td><td>R 1.4</td></tr>
<tr><td>EUS - Units per count of physical reference system

(previously Units per count of physical reference system [units])</td><td>[units]</td><td>Rotary encoder unit scale: Units per x revolutions
Linear encoder unit scale: Units per x reference lengths

Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration).
For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.</td><td>1000</td><td>R 1.4</td></tr>
<tr><td>EUS - Counting direction

(previously Counting direction)</td><td>Standard / Inverse</td><td>Counting direction of the position or speed
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Default</td><td>Encoder counting direction is equal to the counting direction of the unit system.</td></tr>
<tr><td>Inverse</td><td>Encoder counting direction is negative to the counting direction of the unit system.</td></tr>
</table></td><td>Default</td><td>R 1.3</td></tr>
<tr><td>EUS - Length of physical reference system for linear encoder

(previously Length of physical reference system for linear encoder (nm))</td><td>[nm]</td><td>For linear measurement systems, the length of a physical reference system is defined here.
This value is not used for rotary encoders, where the reference system is a single revolution.</td><td>1000000000</td><td>R 1.4</td></tr>
<tr><td>EUS - Maximum speed to normalize speed range

(previously Maximum speed to normalize the speed range (units/s))</td><td>[units/s]</td><td>Maximum speed to which the displayed speed should be normalized</td><td>32767</td><td>R 1.3</td></tr>
<tr><td>EUS - Encoder acceleration limit

(previously Maximum acceleration (rad/s² or mm/s²))</td><td>[rad/s²] or [mm/s²]</td><td>Maximum permissible encoder acceleration</td><td>100000</td><td>R 1.4</td></tr>
</table>

Table 365: SafeMOTION parameter group: General settings - Encoder Unit System

Group: Absolute position functions - Homing (previously *Homing*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Home position or home offset (previously *Home Position or Home Offset (units)*)	[units]	Home position or home offset	0	R 1.4
Homing - Maximum trigger speed (previously *Max. trigger speed (units/s)*)	[units/s]	Maximum permissible speed for evaluating the reference switch / reference pulse	0	R 1.4
Homing - Monitoring time (previously *Homing Monitoring Time (µs)*)	[µs]	Monitoring time for the homing procedure	0	R 1.4
Homing - Mode (previously *Mode*)	Direct / Reference switch / *Home Offset / Home offset with correction*	Selects the homing mode *Modes "Home offset" and "Home offset with correction" are only available for ACOPOSmulti SafeMOTION EnDat 2.2!*	Direct	R 1.4

Table 366: SafeMOTION parameter group: Absolute position functions - Homing

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Edge of reference switch (previously *Edge of reference switch*)	Positive / Negative	Selects the switching edge for the reference switch The switching edge for the reference switch input is positive if the logical state of the reference switch changes from SAFEFALSE to SAFETRUE in the positive direction of movement.	Positive	R 1.4
Homing - Trigger direction (previously *Trigger direction*)	Positive / Negative	Selects the trigger direction If the homing procedure requires a movement, then this parameter specifies the direction for evaluating the reference switch / reference pulse.	Positive	R 1.4
Homing - Enable reference pulse *(previously Reference pulse)*	*Enabled/ Disabled*	*Selects whether or not to use a reference pulse for homing* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2!*	*Disabled*	R 1.4
Homing - Blocking distance *(previously Blocking distance (% encoder reference system))*	*%*	*Distance within which evaluation of the reference pulse will be suppressed. This is calculated starting at the configured reference switch edge and indicated as a percentage of the encoder reference system.* *A single revolution is used as the encoder reference system for rotary encoders.* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2!*	*0*	R 1.4

Table 366: SafeMOTION parameter group: Absolute position functions - Homing

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 367: SafeMOTION parameter group: General settings - Ramp monitoring

Group: Basic functions - SS1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS1 - Ramp monitoring - Enable

(previously Rampmonitoring for SS1)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SS1 function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When transitioning to the safe state of the SS1 function, a deceleration ramp is monitored in addition to the configurable time.</td></tr>
<tr><td>Disabled</td><td>When transitioning to the safe state of the SS1 function, only a configurable time is monitored.</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS1</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 368: SafeMOTION parameter group: Basic functions - SS1

Group: Speed functions - SS2 (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SS2 - Ramp monitoring - Enable (previously *Rampmonitoring for SS2*)	Enabled/ Disabled	Activates ramp monitoring (in addition to time-based monitoring) when the SS2 function is requested **Value** / **Description** Enabled: When changing to the safe state of the SS2 function, a deceleration ramp is also monitored, in addition to the configurable time Disabled: When changing to the safe state of the SS2 function, only a configurable time is monitored	Enabled	R 1.3
Ramp Monitoring Time for SS2 (us)	[µs]	Deceleration ramp monitoring time for SS2	0	R 1.3

Table 369: SafeMOTION parameter group: Speed functions - SS2

Group: General settings - Automatic reset on start (previously *General Settings*)

Parameter	Unit	Description	Default value	Used Starting in Safety Release
Automatic reset on start - Enable (previously *Automatic Reset at Startup*)	Enabled/ Disabled	Activates automatic reset of the function block at startup **Value** / **Description** Enabled: After startup, the module automatically changes to state OPERATIONAL (Startreset). The reset input does not have to be controlled! Disabled: After startup, the module remains in an Init state until a positive edge of the reset input is detected.	Disabled	R1.3

Table 370: SafeMOTION parameter group: General settings - Automatic reset on start

Group: Basic functions - STO1 (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
STO1 - Channel (previously *Channel selection for One Channel STO (STO1)*)	High-side/ Low-side	Selects the high-side or low-side IGBT in the STO1 function **Value** / **Description** High-side: The high-side IGBTs are actuated with the function STO1. Low-side: The low-side IGBTs are actuated with the function STO1.	High-side	R 1.3

Table 371: SafeMOTION parameter group: Basic functions - STO1

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SMS - Enable (previously *Safe Maximum Speed*)	Enabled/ Disabled	Activates the SMS safety function by configuration **Value** / **Description** Enabled: SMS activated Disabled: SMS deactivated	Enabled	R 1.3
SMS - Speed limit (previously *Maximum Speed for SMS (units/s)*)	[units/s]	Speed limit of the maximum speed (SMS)	0	R 1.3
SLS1 - Speed limit (previously *Safe Speedlimit 1 for SLS (units/s)*)	[units/s]	Speed limit 1 for SLS (SLS1)	0	R 1.3
SLS2 - Speed limit (previously *Safe Speedlimit 2 for SLS (units/s)*)	[units/s]	Speed limit 2 for SLS (SLS2)	0	R 1.3
SLS3 - Speed limit (previously *Safe Speedlimit 3 for SLS (units/s)*)	[units/s]	Speed limit 3 for SLS (SLS3)	0	R 1.3
SLS4 - Speed limit (previously *Safe Speedlimit 4 for SLS (units/s)*)	[units/s]	Speed limit 4 for SLS (SLS4)	0	R 1.3

Table 372: SafeMOTION parameter group: Speed functions - SMS/SLS

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SLS - Ramp monitoring - Enable

(previously Rampmonitoring for SLS)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr><tr><td>Disabled</td><td>When changing to the safe state of the SLS function, only a configurable time is monitored</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SLS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS1</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS2 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS2</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS3 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS3</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS4 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS4 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS4</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 372: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: Absolute position functions - SMP/SLP (previously *Safety Position Limits*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SMP - Enable

(previously Safe Maximum Position)</td><td>Enabled/
Disabled</td><td>Activates the SMP safety function from the configuration<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>SMP is activated</td></tr><tr><td>Disabled</td><td>SMP is deactivated</td></tr></table></td><td>Disabled</td><td>R 1.4</td></tr>
<tr><td>SMP - Lower position limit

(previously Safe Lower Position Limit for SMP (units))</td><td>[units]</td><td>Lower position limit for the machine's full travel range</td><td>0</td><td>R 1.4</td></tr>
<tr><td>SMP - Upper position limit

(previously Safe Upper Position Limit for SMP (units))</td><td>[units]</td><td>Upper position limit for the machine's full travel range</td><td>0</td><td>R 1.4</td></tr>
<tr><td>SLP - Lower position limit

(previously Safe Lower Position Limit for SLP (units))</td><td>[units]</td><td>Lower position limit for the monitoring range</td><td>0</td><td>R 1.4</td></tr>
<tr><td>SLP - Upper position limit

(previously Safe Upper Position Limit for SLP (units))</td><td>[units]</td><td>Upper position limit for the monitoring range</td><td>0</td><td>R 1.4</td></tr>
<tr><td>SLP - Enable delay time

(previously Delay time to start SLP (us))</td><td>[µs]</td><td>Delay time between the SLP request and start of monitoring</td><td>0</td><td>R 1.4</td></tr>
</table>

Table 373: SafeMOTION parameter group: Absolute position functions - SMP/SLP

Group: General settings - Encoder monitoring (previously *Encoder Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Encoder monitoring - Safe Encoder Mounting (Hardware upgrade 1.10.3.x and later)	From motor data record / Approved by user	Status of the proof of fatigue strength of the encoder mounting **Value** – **Description** From motor data record – The status of the encoder mounting is determined using the motor data record. Approved by user – The user confirms safe encoder mounting / no mounting information available in the motor data record.	From motor data record	R1.10
Encoder monitoring - Position error monitoring - Enable *(previously Encoder Position monitoring)*	Enabled/ Disabled	Enables/Disables monitoring of the position lag error generated on the SafeMOTION module **Value** – **Description** Enabled – Monitoring active Disabled – Monitoring not active	Enabled	R1.3
Encoder monitoring - Speed error monitoring - Enable (previously *Encoder Speed monitoring*)	Enabled/ Disabled	Activates/Deactivates monitoring of the speed error generated on the SafeMOTION module **Value** – **Description** Enabled – Monitoring active Disabled – Monitoring not active	Enabled	R1.3
Encoder monitoring - Position setpoint alive testing (SPA) - Enable (previously *Set position alive testing*)	Enabled/ Disabled	Activates/Deactivates the monitor that detects whether the position setpoint generated on the SafeMOTION module is frozen. **Value** – **Description** Enabled – Monitoring active Disabled – Monitoring not active	Disabled	R1.3
Encoder monitoring - Position error tolerance (previously *Encoder monitoring Position tolerance (units)*)	[units]	Position lag error tolerance for shaft breakage monitoring	0	R1.3
Encoder monitoring - Speed error tolerance (previously *Encoder monitoring Speed tolerance (units/s)*)	[units/s]	Speed error tolerance for encoder monitoring	0	R1.3

Table 374: SafeMOTION parameter group: General settings - Encoder monitoring

Group: General settings - Behavior of Functional Fail Safe (FFS) (previously *Behavior of Functional Fail Safe*)

Parameter	Unit	Description	Default value	Used Starting in Safety Release
FFS - Mode (previously *Behavior of Functional Fail Safe*)	STO / STO1 and STO with time delay	In the FUNCTIONAL FAIL SAFE state, STO and SBC are activated immediately, or STO1 is activated and then STO after a delay. **Value** – **Description** STO – In the FUNCTIONAL FAIL SAFE state, STO and SBC are activated immediately. STO1 and STO with time delay – In the FUNCTIONAL FAIL SAFE state, STO1 and SBC are activated first, and then STO after a delay.	STO	R 1.3
FFS - STO Enable delay time (previously *Delay for STO in Functional Fail Safe [µs]*)	[µs]	Delay time between STO1 and STO (and SBC) in the FUNCTIONAL FAIL SAFE state	0	R 1.3
FFS - Delay time until brake engages (previously *Delay time until the brake engages [µs]*)	[µs]	**Delay time before the brake engages** The second enable channel is activated after this delay time if STO1 and time-delayed STO and SBC are configured for FUNCTIONAL FAIL SAFE.	0	R 1.3
FFS - Caused by encoder error *(1.10.1.x for ACOPOSmulti SafeMOTION and hardware upgrade 1.10.2.x or later for ACOPOS P3 SafeMOTION)*	Always / Only if safety functions requiring an encoder are enabled	Enable FUNCTIONAL FAIL SAFE on encoder error: Always: FFS occurs if at least one safety function that requires an encoder is used and an encoder error is present. Only if safety functions requiring an encoder are enabled: FFS occurs if at least one safety function that requires an encoder is active and an encoder error is present.	Always	R 1.10.1

Table 375: SafeMOTION parameter group: General settings - Behavior of Functional Fail Safe (FFS)

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 376: SafeMOTION parameter group: General settings - Standstill monitoring

Group: Advanced functions - SLI (previously *Safely Limited Increment*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLI - Position limit (previously *Safe Increments (units)*)	[units]	Maximum movable increments when SLI is active	0	R 1.3
SLI - Disable delay time (previously *SLI Off Delay (µs)*)	[µs]	Switch off delay of SLI	0	R 1.3

Table 377: SafeMOTION parameter group: Advanced functions - SLI

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** – **Description** Enabled – "Early Limit Monitoring" is active! Disabled – "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 378: SafeMOTION parameter group: General settings - Early limit monitoring

Group: Basic functions - SBC (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBC - Enable delay time (previously *Delay time to start SBC (us)*	[µs]	Delay time between the SBC request and activation of the safety function	0	R 1.3

Table 379: SafeMOTION parameter group: Basic functions - SBC

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 380: SafeMOTION parameter group: Advanced functions - SDI

In a safety application, it is possible for multiple safety functions to be requested at the same time. In order to prevent this from turning into an unsafe situation, the individual safety functions are prioritized on the SafeMOTION module.

If several functions are active, then the lowest speed limit is always the value being monitored.

Information:

The following application rule must be observed:

$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS} \leq$ EUS - Maximum speed to normalize speed range

This is required for setting priority of the safety functions on the SafeMOTION module.

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

7.4.3 Integrated safety functions

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

7.4.4 Safe encoder connection monitoring

7.4.4.1 Encoder mounting with proof of fatigue strength[14)]

To prevent errors caused by encoder slippage or shaft breakage, the mechanical mounting of the encoder requires proof of fatigue strength.

This proof and the corresponding mounting guidelines can be provided either by the manufacturer of the measuring instrument or by the manufacturer of the machine.

Danger!

To ensure safe operation up to and including the motor shaft, any errors in the connection between the motor shaft and encoder must be identified and prevented.

Danger!

Proof of fatigue strength for the encoder's mechanical mounting is to be dimensioned to the maximum rotor acceleration. This acceleration value is not permitted to be exceeded in the worst case. The maximum acceleration is monitored on the SafeMOTION module and can be configured using parameter "EUS - Encoder acceleration limit".

Danger!

Mechanical tolerances in the encoder mounting must be taken into account when calculating the residual distance. This residual movement must be taken into account by the safety functions.

Danger!

To ensure safe operation up to and including the motor shaft, any errors in the connection between the motor shaft and encoder must be identified and prevented.
There are specific guidelines that must be followed when installing a functional safety encoder.
The motor manufacturer must ensure that these specifications are adhered to.

Danger!

The frictional connection between the cone-shaped shaft of the rotor and measuring instrument can be dimensioned for maximum rotor acceleration in accordance with the mounting instructions provided by the encoder manufacturer. This acceleration value is not permitted to be exceeded in the worst case. The maximum acceleration is monitored on the SafeMOTION module and can be configured using parameter "EUS - Encoder acceleration limit".

Danger!

If the terminal screw for the coupling ring becomes loose on installed measuring instruments, then the form-fit pin will be the only thing holding the encoder to the motor housing. A movement in accordance with the mounting tolerances is possible. The encoder is not able to register this movement. This residual movement must be taken into account by the safety functions.

7.4.4.2 Encoder mounting without proof of fatigue strength - Safe lag error monitoring[15)]

If "General settings - Encoder monitoring" is activated in the SafeMOTION module, in some applications the proof of fatigue strength for the mechanical mounting of the encoder is not required.

The following safety-related restrictions must be taken into account!

Danger!

Only safety functions in which no safe absolute position is monitored are permitted to be used (STO, SBC, SOS, SS1, SS2, SLS, SMS, SLI, SDI, SLA, SBT (only available for ACOPOSmulti SafeMOTION SinCos and ACOPOS P3 SafeMOTION), SLT (only available for ACOPOS P3 SafeMOTION) and Safe Speed).

14) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR, SF_oS_MOTION_ScaledSpeed_BR, SF_oS_MOTION_Position_BR.

15) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR, SF_oS_MOTION_ScaledSpeed_BR, SF_oS_MOTION_Position_BR.

Danger!

The application must meet the following requirements for safety-related monitoring of the encoder-motor connection:

- **Encoder connection monitoring is only permitted to be used for encoders that are integrated in position control.**
- **Encoder connection monitoring is only permitted to be used for drive systems with synchronous motors.**
- **The encoder must be protected against shearing in standstill (e.g. with encasement in the motor housing)!**
- **Monitoring for position lag errors, speed errors and position setpoints change (Alive Testing) must be enabled in the safety application, and sufficiently strict limits must be monitored!**
- **Safety functions Safe Position, SLP and/or SMP are not permitted to be not be used!**
- **Safe monitoring can only be guaranteed when closed-loop control is enabled.**

Danger!

- **An electrical offset of <90° will not be detected sufficiently.**
- **There is no way to monitor the encoder connection if the setpoint remains constant.**
- **An encoder connection error or an error in encoder evaluation is always assumed as the cause for the lag error.**
- **The error reaction in the standard application to a position lag error or speed error is disabled by the SafeMOTION module (overridden). When lag errors occur, only the error responses STO or STO1 with an induction stop are possible.**

Danger!

Note that an error can result in a forward movement. The maximum angle of rotation φ of the motor shaft during this forward movement depends on the motor being used.

For permanent magnet synchronous motors, φ = 360°/2p. For three-phase induction motors, there is a relatively small angle of rotation between 5° and 15°.

The maximum speed of the forward movement can be calculated as follows:

$$n_{Jolt} = \frac{1}{2\pi}\sqrt{\frac{6a_{max}}{p_z}}\left[\frac{U}{s}\right]$$

With the maximum acceleration $a_{max} = \frac{M_{max}}{J}\left[\frac{rad}{s^2}\right]$ **And number of motor pole pairs** p_z

Danger!

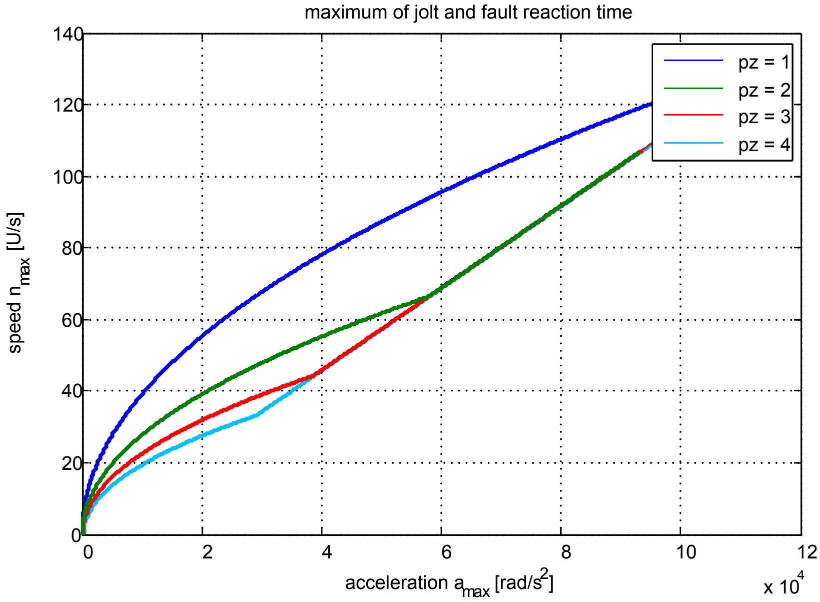
In the worst-case consideration of a safety function, the maximum achievable speed must be the maximum of maximum actuation speed n_{Jolt} **and the speed due to the maximum error response time** $n_{T_{worstcase}}$.

$$n_{max} = max(n_{Jolt}, n_{T_{worstcase}}) = max\left(\frac{1}{2\pi}\sqrt{\frac{6a_{max}}{p_z}}, \frac{T_{worstcase}}{2\pi}\cdot a_{max}\right)$$

With the maximum error response time $T_{worstcase} = 7.2[ms]$

The maximum speed n_{max} **resulting from this must be considered together with the speed when the safety function** n_{LIM} **is violated in order to determine the maximum possible speed** $n_{worstcase}$ **at the time of coasting to a stop.**

$$n_{worstcase} = n_{LIM} + n_{max}$$



Information:

In order to check the plausibility of setpoint selection after each power on, the axis must be moved by at least twice the configured lag error limit before the first request of a safety function, which requires a safe encoder evaluation, or at least within 15 min.
If this is not done, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state. The "S_NotErrFUNC" output on the function block is reset, and the drive loses all torque/power and coasts to a stop!
In the event of an error, a synchronous axis will no longer be synchronous.

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

Information:

A 24-hour timeout begins after successfully checking the plausibility of the setpoint.
The timeout is reset any time the position setpoint changes by more than twice the position lag error tolerance.
If the position setpoint does not change during 24 hours of continuous controller operation, then the SafeMOTION module will switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state. The "S_NotErrFUNC" output on the function block is reset, and the drive loses all torque/power and coasts to a stop! In the event of an error, a synchronous axis will no longer be synchronous.

The following parameters are relevant for safe monitoring of the encoder-motor shaft connection (Encoder Monitoring):

Group: General settings - Encoder monitoring (previously *Encoder Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Encoder monitoring - Safe Encoder Mounting (Hardware upgrade 1.10.3.x and later)</td><td>From motor data record / Approved by user</td><td>Status of the proof of fatigue strength of the encoder mounting<table><tr><th>Value</th><th>Description</th></tr><tr><td>From motor data record</td><td>The status of the encoder mounting is determined using the motor data record.</td></tr><tr><td>Approved by user</td><td>The user confirms safe encoder mounting / no mounting information available in the motor data record.</td></tr></table></td><td>From motor data record</td><td>R1.10</td></tr>
<tr><td>Encoder monitoring - Position error monitoring - Enable

(previously Encoder Position monitoring)</td><td>Enabled/
Disabled</td><td>Enables/Disables monitoring of the position lag error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error monitoring - Enable

(previously Encoder Speed monitoring)</td><td>Enabled/
Disabled</td><td>Activates/Deactivates monitoring of the speed error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position setpoint alive testing (SPA) - Enable

(previously Set position alive testing)</td><td>Enabled/
Disabled</td><td>Activates/Deactivates the monitor that detects whether the position setpoint generated on the SafeMOTION module is frozen.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Disabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position error tolerance

(previously Encoder monitoring Position tolerance (units))</td><td>[units]</td><td>Position lag error tolerance for shaft breakage monitoring</td><td>0</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error tolerance

(previously Encoder monitoring Speed tolerance (units/s))</td><td>[units/s]</td><td>Speed error tolerance for encoder monitoring</td><td>0</td><td>R1.3</td></tr>
</table>

Table 381: SafeMOTION parameter group: General settings - Encoder monitoring

Group: General settings - Encoder Unit System (previously *Encoder Unit System*)

Parameter	Unit	Description	Default value	Starting in Safety Release
EUS - Encoder acceleration limit (previously *Maximum acceleration (rad/s² or mm/s²)*)	[rad/s²] or [mm/s²]	Maximum permissible encoder acceleration	100000	R 1.4

Table 382: SafeMOTION parameter group: General settings - Encoder Unit System

Information:

The physical drive speed is not permitted to exceed the value set for parameter "EUS - Maximum speed to normalize speed range"; otherwise, the SafeMOTION module will switch to the error state!

Danger!

If the manufacturer of the measuring instrument specifies a limitation of the maximum acceleration, this must be monitored by the SafeMOTION module. The acceleration to be monitored can be configured using parameter "EUS - Encoder acceleration limit".

Danger!

Incorrectly configuring the unit system can result in dangerous situations.
When validating the application, the monitored speed limits must be intentionally violated and their physical values tested! The same must also be done for the monitored direction of rotation!

Danger!

The machine manufacturer is responsible for determining whether or not the application is suited for safe encoder connection monitoring if there is no mechanical mechanism for detecting encoder shaft breakage.
The machine manufacturer is responsible for ensuring that the safe encoder monitoring has been configured correctly!

Danger!

Encoder connection monitoring is only permitted to be used in a safety-related capacity if the aforementioned requirements for the application have been fulfilled!

7.4.4.2.1 Activating monitoring[16)]

The following parameters must be set to "Enabled" in SafeDESIGNER in order to enable safe encoder connection monitoring:

- "Encoder monitoring - Position error monitoring - Enable" = Enabled
- "Encoder monitoring - Speed error monitoring - Enable" = Enabled
- "Encoder monitoring - Position setpoint alive testing (SPA) - Enable" = Enabled

Danger!

In order to ensure safety-related monitoring of the encoder/motor connection, all three parameters "Encoder monitoring - Position error monitoring - Enable", "Encoder monitoring - Speed error monitoring - Enable" and "Encoder monitoring - Position setpoint alive testing (SPA) - Enable" must be set to "Enabled"!
If this is not the case, then the monitoring system cannot be used for safety purposes and a mechanical solution for detecting errors must be implemented!

7.4.4.2.2 Configuration rule for position lag error tolerance[17)]

The position lag error tolerance must be set large enough to ensure availability. This can be done by first measuring the position lag error under the highest influence of disturbance variables and at maximum acceleration and then setting the position lag error tolerance accordingly higher.

Danger!

The position lag error tolerance is not permitted to be higher than half of one pole length!

If the safety function is activated, the size of the position lag error tolerance value affects how long it will take to look for errors and therefore also the error response time and estimation of the residual distance.

This must be taken into account by the machine manufacturer in the risk analysis!

Information:

Due to rounding errors, a reserve of 1 unit should be taken into account with the parameter "Encoder monitoring - Position error tolerance".

16) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR, SF_oS_MOTION_ScaledSpeed_BR, SF_oS_MOTION_Position_BR.

17) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR, SF_oS_MOTION_ScaledSpeed_BR, SF_oS_MOTION_Position_BR.

7.4.4.2.3 Configuration rule for speed error tolerance[18)]

The speed error tolerance must be set large enough to ensure availability.
This can be done by first measuring the speed error under the highest influence of disturbance variables and reference variables (e.g. at maximum acceleration) and then setting the speed error tolerance accordingly higher.

Danger!

When the safety function is enabled, the size of the speed error tolerance value affects how long it will take to look for errors and therefore also the error response time and estimation of the residual distance.

This must be taken into account by the machine manufacturer in the risk analysis!

Information:

Due to rounding errors, a reserve of 1 unit/s should be taken into account with the parameter "Encoder monitoring - Speed error tolerance".

18) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR, SF_oS_MOTION_ScaledSpeed_BR, SF_oS_MOTION_Position_BR.

7.4.5 Fault avoidance

> ## Danger!
> **Validation**
>
> **Each safety function that is used must be validated separately.**
> **It is also necessary to test the entire safety application, including the interactions between individual functions.**

7.4.5.1 Exceeding monitored limits

The SafeMOTION module monitors configurable limits. The drive itself, however, is controlled by the standard application on the standard PLC.

To prevent a violation of a monitored limit, the following points must be observed:

- The movement of the drive must be adapted to the requested safety function and initiated on time.
- The monitored limits must match the calculated limits and movement limitations. Make sure that the different configurations of the unit system match in the safety application and in the standard application!

> ## Danger!
> **Any violation of a monitored limit will cause the module to switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state.**
>
> **The "S_NotErrFUNC" output on the function block is reset, and the drive loses all torque/power and coasts to a stop!**
>
> **Depending on the configuration, the motor holding brake will also be switched to 0 V.**
>
> **In the event of an error, a synchronous axis will no longer be synchronous.**
>
> **Check the Safety Logger in Automation Studio for detailed information about monitoring.**

7.4.5.2 Plausibility error[19)]

Plausibility errors (limit values, data types, variables/constants) that occur when using the function block are detected and reported by either the function block or compiler.

This is not possible in the event of connection errors, however.

The function block does not check for the following errors:

- Actual parameter values or constants are within their valid range but incorrect for the safety function being executed.
- Actual parameters have been connected incorrectly.
- Formal input/output parameters that should have been connected have not been connected.

> ## Danger!
> **Ensuring proper safety function connections (sub-application) is your responsibility as the user!**
>
> **Check the connections when validating the sub-application!**

7.4.5.3 Sporadically changing/toggling signal levels or impermissible signals[20)]

Sporadically changing or toggling signal levels on edge-controlled formal input parameters cause the function block to interpret this signal as an edge, which results in an unintended corresponding action being triggered in the function block if fault avoidance measures are not taken.

Sporadically changing or toggling signal levels on status-controlled input formal parameters will cause the signal to trigger an undesired corresponding action if error prevention measures are not taken.

Impermissible signals on input formal parameters can lead to an unexpected initial movement, non-execution of a requested action or an error message.

Possible causes of these signals:

19) This section applies to all function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF:

20) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR, SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR

- Programming error in the application program (user error)
- Cross fault, short circuit or open circuit (user error, wiring error)
- Error on the standard controller

To prevent this, the following measures can be taken depending on the safety function:

- Using signals from safe devices
- Implementing additional measures for preventing a hazard if using a signal from a standard controller (e.g. executing an additional function start after a safety function has been triggered or an error has been corrected)
- Line control on the safe control system
- Suitable cabling when using non-safe signals from the standard controller
- Verifying the source code in the application program and final validation of the safety functionality

These measures can also be combined to prevent errors.

It is important to note that a signal change detected on a status-controlled formal parameter will be output as a diagnostic code.

7.4.5.4 Simultaneous edge change[21)]

Make sure that the "Reset" formal parameter is only connected to a signal from a manual resetting device to reduce the risk of an unexpected initial movement. This signal is based on your risk analysis.

7.4.5.5 Machine/System startup without performing functional testing of protective equipment[22)]

Faulty protective equipment is only detected following functional testing. Functional testing is not supported by this function block. If additional measures are not taken, faulty protective equipment can result in errors.

Danger!

You are responsible for the functional testing of protective equipment.
You must therefore validate the protective equipment!

Possible causes of faulty protective equipment:

- Faulty devices (hardware error)
- Cross fault, short circuit and open circuit (user error, wiring error)

21) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR, SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR

22) This section applies to all function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF:

7.4.6 Input parameters

Information:

For detailed information about individual safety functions, see "SafeMOTION user's manual / chapter "Safety technology" / Integrated safety functions"!

7.4.6.1 General information about the "S_Request" inputs

The "S_Request" inputs are used to request the respective safety functions.

If a safety function should not be used in the safety application, then the respective input should not be connected.

Information:

If a safety function is not used in the application, then the respective input must remain open.

Danger!

The safety functions that are used must be tested.
A function is considered to be used if the respective input variable is connected!

Information:

At a minimum, the "Activate" and "S_AxisID" inputs must be connected. Otherwise, the SafeMOTION module will not be operated by the SafeLOGIC controller. As a result, the pulse disabling and motor holding brake outputs will be permanently set to 0 V, which means that the controller cannot be turned on.

7.4.6.2 Activate

General function

- Enables the function block

Data type

- BOOL

Connection

- Constant or variable

Function description

This input parameter is used to activate the function block.

- When enabling or disabling safe devices, "Activate" must be linked to a variable that indicates the state (enabled or disabled) of the corresponding safe devices. This ensures that the function block does not output a triggered safety function as diagnostic information when a device is switched off.
- It is also possible to connect "Activate" to a constant (TRUE) in order to enable the function block.

TRUE

The function block is enabled.

FALSE

The function block is not enabled.
All binary output parameters are set to FALSE.
Sets the DiagCode diagnostic parameter to WORD#16#0000.

If you want to control function block diagnostics as needed in your diagnostic concept whenever error messages from safe devices and/or deactivated safe devices occur, connect "Activate" to a signal that indicates the status of the safe devices that are involved with the safety function supported by the function block. Form this signal using only safe devices whose I/O signals are connected to the function block via actual parameters. In this way, you prevent triggered safety functions from being reported by active safe devices. This measure is only used to control the diagnostic information from inactive safe devices in a defined manner.

7.4.6.3 S_RequestSTO

General function

- Selects/Deselects safety function Safe Torque Off, STO

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the STO safety function.

TRUE

The safety function is deselected. Safe pulse disabling is not active!

FALSE

The safety function is selected. Safe pulse disabling is active! Torque/Power are switched off on the drive.

Not connected

The safety function is deactivated.

Relevant configuration parameters

- None

7.4.6.4 S_RequestSTO1

General function

- Selects/Deselects safety function Safe Torque Off, One Channel, STO1

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the STO1 safety function.

TRUE

The safety function is deselected. Safe pulse disabling is not active!

FALSE

The safety function is selected. Depending on the configuration, the high-side or low-side of safe pulse disabling is active! Torque/Power are switched off on the drive.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Basic functions - STO1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>STO1 - Channel

(previously Channel selection for One Channel STO (STO1))</td><td>High-side/
Low-side</td><td>Selects the high-side or low-side IGBT in the STO1 function<table><tr><th>Value</th><th>Description</th></tr><tr><td>High-side</td><td>The high-side IGBTs are actuated with the function STO1.</td></tr><tr><td>Low-side</td><td>The low-side IGBTs are actuated with the function STO1.</td></tr></table></td><td>High-side</td><td>R 1.3</td></tr>
</table>

Table 383: SafeMOTION parameter group: Basic functions - STO1

7.4.6.5 S_RequestSBC

General function

- Selects/Deselects safety function Safe Brake Control, SBC

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SBC safety function.

TRUE

The safety function is deselected. The motor holding brake output is enabled and can be used by the standard application.

FALSE

The safety function is selected. The motor holding brake output is switched to 0 V!

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Basic functions - SBC (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBC - Enable delay time (previously *Delay time to start SBC (us)*)	[µs]	Delay time between the SBC request and activation of the safety function	0	R 1.3

Table 384: SafeMOTION parameter group: Basic functions - SBC

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

7.4.6.6 S_RequestSOS

General function

- Selects/Deselects safety function Safe Operating Stop, SOS

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SOS safety function.

TRUE

The safety function is deselected. Standstill tolerances are not being monitored.

FALSE

The safety function is selected. Standstill tolerances are being monitored.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 385: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ < EUS - Maximum speed to normalize speed range

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.4.6.7 S_RequestSS1

General function

- Selects/Deselects safety function Safe Stop 1, SS1

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SS1 safety function.

TRUE

The safety function is deselected. SS1 is not active!

FALSE

The safety function is selected. Safe pulse disabling is activated after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 386: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Basic functions - SS1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS1 - Ramp monitoring - Enable

(previously Rampmonitoring for SS1)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SS1 function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When transitioning to the safe state of the SS1 function, a deceleration ramp is monitored in addition to the configurable time.</td></tr>
<tr><td>Disabled</td><td>When transitioning to the safe state of the SS1 function, only a configurable time is monitored.</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS1</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 387: SafeMOTION parameter group: Basic functions - SS1

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr>
<tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr>
</table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 388: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

To use this function without safe encoder evaluation, "Ramp monitoring for SS1" and "Early Limit Monitoring" must be disabled.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \le LIM_{SLS4} \le LIM_{SLS3} \le LIM_{SLS2} \le LIM_{SLS1} \le LIM_{SMS} <$ **EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.4.6.8 S_RequestSS2

General function

- Selects/Deselects safety function Safe Stop 2, SS2

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SS2 safety function.

TRUE

The safety function is deselected. SS2 is not active!

FALSE

The safety function is selected. Standstill monitoring is activated after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 389: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SS2 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS2 - Ramp monitoring - Enable

(previously Rampmonitoring for SS2)</td><td>Enabled/
Disabled</td><td>Activates ramp monitoring (in addition to time-based monitoring) when the SS2 function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When changing to the safe state of the SS2 function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr>
<tr><td>Disabled</td><td>When changing to the safe state of the SS2 function, only a configurable time is monitored</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>Ramp Monitoring Time for SS2 (us)</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS2</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 390: SafeMOTION parameter group: Speed functions - SS2

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 391: SafeMOTION parameter group: General settings - Standstill monitoring

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** / **Description** Enabled: "Early Limit Monitoring" is active! Disabled: "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 392: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ < EUS - Maximum speed to normalize speed range

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.4.6.9 S_RequestSLS1

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 1

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS1 safety function.

TRUE

The safety function is deselected. SLS1 is not active!

FALSE

The safety function is selected. Speed limit 1 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 393: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SLS - Ramp monitoring - Enable

(previously Rampmonitoring for SLS)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr>
<tr><td>Disabled</td><td>When changing to the safe state of the SLS function, only a configurable time is monitored</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SLS1 - Speed limit

(previously Safe Speedlimit 1 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 1 for SLS (SLS1)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS1</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 394: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr>
<tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr>
</table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 395: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.4.6.10 S_RequestSLS2

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 2

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS2 safety function.

TRUE

The safety function is deselected. SLS2 is not active!

FALSE

The safety function is selected. Speed limit 2 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 396: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLS - Ramp monitoring - Enable (previously *Rampmonitoring for SLS*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested **Value** / **Description** Enabled: When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time Disabled: When changing to the safe state of the SLS function, only a configurable time is monitored	Enabled	R 1.3
SLS2 - Speed limit (previously *Safe Speedlimit 2 for SLS (units/s)*)	[units/s]	Speed limit 2 for SLS (SLS2)	0	R 1.3
SLS2 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS2 (us)*)	[µs]	Deceleration ramp monitoring time for SLS2	0	R 1.3

Table 397: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** / **Description** Enabled: "Early Limit Monitoring" is active! Disabled: "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 398: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$\mathbf{LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.4.6.11 S_RequestSLS3

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 3

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS3 safety function.

TRUE

The safety function is deselected. SLS3 is not active!

FALSE

The safety function is selected. Speed limit 3 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 399: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SLS - Ramp monitoring - Enable

(previously Rampmonitoring for SLS)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr>
<tr><td>Disabled</td><td>When changing to the safe state of the SLS function, only a configurable time is monitored</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SLS3 - Speed limit

(previously Safe Speedlimit 3 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 3 for SLS (SLS3)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS3 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS3 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS3</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 400: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr>
<tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr>
</table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 401: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.4.6.12 S_RequestSLS4

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 4

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS4 safety function.

TRUE

The safety function is deselected. SLS4 is not active!

FALSE

The safety function is selected. Speed limit 4 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 402: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLS - Ramp monitoring - Enable (previously *Rampmonitoring for SLS*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested **Value** / **Description** Enabled: When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time Disabled: When changing to the safe state of the SLS function, only a configurable time is monitored	Enabled	R 1.3
SLS4 - Speed limit (previously *Safe Speedlimit 4 for SLS (units/s)*)	[units/s]	Speed limit 2 for SLS (SLS2)	0	R 1.3
SLS4 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS4 (us)*)	[µs]	Deceleration ramp monitoring time for SLS2	0	R 1.3

Table 403: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** / **Description** Enabled: "Early Limit Monitoring" is active! Disabled: "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 404: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.4.6.13 S_RequestSLI

General function

- Selects/Deselects safety function Safely Limited Increment, SLI

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLI safety function.

TRUE

The safety function is deselected. SLI is not active!

FALSE

The safety function is selected. A safe range of increments is monitored.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3

Table 405: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SLI (previously *Safely Limited Increment*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLI - Position limit (previously *Safe Increments (units)*)	[units]	Maximum movable increments when SLI is active	0	R 1.3
SLI - Disable delay time (previously *SLI Off Delay (µs)*)	[µs]	Switch off delay of SLI	0	R 1.3

Table 406: SafeMOTION parameter group: Advanced functions - SLI

Danger!

The maximum increment range must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

7.4.6.14 S_RequestSDIpos

General function

- Selects/Deselects safety function Safe Direction. Movement is allowed in the positive direction.

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the safety function SDI, movement is allowed in the positive direction of movement.

TRUE

The safety function is deselected. SDI is not active!

FALSE

The direction of movement is monitored after the delay time has expired. Movement is allowed in the positive direction.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 407: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*)	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 408: SafeMOTION parameter group: Advanced functions - SDI

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

7.4.6.15 S_RequestSDIneg

General function

- Selects/Deselects safety function Safe Direction. Movement is allowed in the negative direction.

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the safety function SDI, movement is allowed in the negative direction of movement.

TRUE

The safety function is deselected. SDI is not active!

FALSE

The direction of movement is monitored after the delay time has expired. Movement is allowed in the negative direction.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 409: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*)	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 410: SafeMOTION parameter group: Advanced functions - SDI

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

7.4.6.16 S_RequestSLP

General function

- Selects/Deselects safety function Safely Limited Position, SLP

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLP safety function.

TRUE

The safety function is deselected. SLP is not active!

FALSE

The configured position window will be safety-monitored after "Delay time to start SLP (us)".

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 411: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Absolute position functions - SMP/SLP (previously *Safety Position Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLP - Lower position limit (previously *Safe Lower Position Limit for SLP (units)*)	[units]	Lower position limit for the monitoring range	0	R 1.4
SLP - Upper position limit (previously *Safe Upper Position Limit for SLP (units)*)	[units]	Upper position limit for the monitoring range	0	R 1.4
SLP - Enable delay time (previously *Delay time to start SLP (us)*)	[µs]	Delay time between the SLP request and start of monitoring	0	R 1.4

Table 412: SafeMOTION parameter group: Absolute position functions - SMP/SLP

Danger!

The position limits being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement, a dangerous movement cannot occur in the event of a worst case scenario.

The dangerous movement must be determined by a risk analysis.

Information:

The following application rule must be observed:

$LIM_{SMP,NEG} \leq LIM_{SLP,NEG} \leq LIM_{SLP,POS} \leq LIM_{SMP,POS}$

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 413: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

The following application rule must be observed:
$LIM_{SMP,NEG} \leq LIM_{SLP,NEG} \leq LIM_{SLP,POS} \leq LIM_{SMP,POS}$
Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

Information:

Safe homing of the axis must be completed prior to using this safety function.
If a homing procedure is not completed successfully or the "S_SafePositionValid" status changes, then the request for the SLP safety function causes the module to switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state.
The drive loses all torque/power and coasts to a stop! In the event of an error, a synchronous axis will no longer be synchronous. The output of function block "S_NotErrFUNC" is reset.

7.4.6.17 S_RequestHoming

General function

- Selects/Deselects the "Safe Homing" safety function

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to start a "Safe Homing" procedure. A positive edge of the input starts the safety function.

Positive edge: Change from FALSE to TRUE

Starts "Safe Homing".

Negative edge: Change from TRUE to FALSE

If still active, the homing procedure will be terminated by the negative edge. This state transition has no effect if the homing procedure has already been completed.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Absolute position functions - Homing (previously *Homing*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Mode (previously *Mode*)	Direct / Reference switch / *Home Offset /* *Home offset with correction*	Selects the homing mode *Modes "Home offset" and "Home offset with correction" are only available for ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	Direct	R 1.4
Homing - Home position or home offset (previously *Home Position or Home Offset (units)*)	[units]	Home position or home offset	0	R 1.4
Homing - Enable RSP (Remanent safe position) *(previously Remanent safe position)*	*Enabled/* *Disabled*	*Selects whether or not to use the remanent safe position* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*Disabled*	R 1.9
Homing - Edge of reference switch (previously *Edge of reference switch*)	Positive / Negative	Selects the switching edge for the reference switch The switching edge for the reference switch input is positive if the logical state of the reference switch changes from SAFEFALSE to SAFETRUE in the positive direction of movement.	Positive	R 1.4
Homing - Trigger direction (previously *Trigger direction*)	Positive / Negative	Selects the trigger direction If the homing procedure requires a movement, then this parameter specifies the direction for evaluating the reference switch / reference pulse.	Positive	R 1.4

Table 414: SafeMOTION parameter group: Absolute position functions - Homing

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Enable reference pulse *(previously Reference pulse)*	*Enabled/ Disabled*	*Selects whether or not to use a reference pulse for homing* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*Disabled*	R 1.4
Homing - Blocking distance *(previously Blocking distance (% encoder reference system))*	*%*	*Distance within which evaluation of the reference pulse will be suppressed.* *This is calculated starting at the configured reference switch edge and indicated as a percentage of the encoder reference system.* *A single revolution is used as the encoder reference system for rotary encoders.* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*0*	R 1.4
Homing - Maximum trigger speed (previously *Max. trigger speed (units/s)*)	[units/s]	Maximum permissible speed for evaluating the reference switch / reference pulse	0	R 1.4
Homing - Monitoring time (previously *Homing Monitoring Time (µs)*)	[µs]	Monitoring time for the homing procedure	0	R 1.4

Table 414: SafeMOTION parameter group: Absolute position functions - Homing

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

The Safe Homing function is needed in order to implement the safety functions SLP and SMP and for using the safe position.
The SafePositionValid status bit will remain set to SAFEFALSE until safe homing has been performed!

7.4.6.18 S_ReferenceSwitch

General function

- Reference switch input for the "Safe Homing" safety function

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter serves as a reference switch input for the "Safe Homing" safety function and is only evaluated in the "Reference Switch" homing mode.
The status of a safe reference switch that was read into the safety application via a safe input module (X20SIxxxx), for example, should be linked to the input.

Not connected

The reference switch is not being used!

Information:

If "Reference Switch" homing mode is configured and the reference switch input "S_ReferenceSwitch" is not wired on the function block, then the SafeMOTION module will switch to the FAIL SAFE state.
The only way to exit the FAIL SAFE state is to complete a power off/on cycle and modify the safety application!

Information:

The "S_ReferenceSwitch" input is only evaluated in "Reference Switch" homing mode.
The input is ignored in other homing modes!

7.4.6.19 Reset

General function

- "Reset" input for acknowledging the FUNCTIONAL FAIL SAFE state or for putting the SafeMOTION module into OPERATIONAL state after STARTUP

Data type

- BOOL

Connection

- Variable

Function description

"Reset" input to acknowledge the FUNCTIONAL FAIL SAFE state

A positive edge triggers the reset function.

Depending on the configuration of parameter "Automatic Reset at Startup", a positive edge may be necessary to get the SafeMOTION module from state INIT to state OPERATIONAL after startup.

Relevant configuration parameters

Group: General settings - Automatic reset on start (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Used Starting in Safety Release</th></tr>
<tr><td>Automatic reset on start - Enable

(previously Automatic Reset at Startup)</td><td>Enabled/
Disabled</td><td>Activates automatic reset of the function block at startup<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>After startup, the module automatically changes to state OPERATIONAL (Startreset). The reset input does not have to be controlled!</td></tr><tr><td>Disabled</td><td>After startup, the module remains in an Init state until a positive edge of the reset input is detected.</td></tr></table></td><td>Disabled</td><td>R1.3</td></tr>
</table>

Table 415: SafeMOTION parameter group: General settings - Automatic reset on start

Danger!

Parameter "Automatic reset on start" enables/disables the restart interlock during startup or when a network failure occurs on a reestablished network connection.

If parameter "Automatic reset on start" is set to "Enabled", then the module automatically changes to state OPERATIONAL state (i.e. pulse disabling and the motor holding brake are enabled)!

Configuring an automatic restart can result in critical safety conditions. Take additional measures to ensure proper safety-related functionality.

7.4.6.20 S_AxisID

General function

- This input parameter assigns a real axis to the function block.

Data type

- SAFEINT

Connection

- Constant

Function description

The corresponding axis can be connected to the input in SafeDESIGNER using drag-and-drop.

Information:

There is only permitted to be one combination of AxisID and the SF_SafeMC_BR or SF_SafeMC_BR_Vx function block in the safety application. Otherwise, it will not be possible to compile the safety application.

7.4.7 Output parameters

Output parameters provide information about the state of the SafeMOTION module and the individual safety functions.

7.4.7.1 Ready

General function

- Message: Function block is enabled/disabled.

Data type

- BOOL

Connection

- Variable

Function description

This output parameter indicates whether the function block is enabled or not.

TRUE

The function block is enabled ("Activate" = TRUE). The output parameters indicate the current state of the safety function.

FALSE

The function block is not enabled ("Activate" = FALSE). The function block outputs are set to FALSE.

7.4.7.2 S_SafetyActiveSTO

General function

- Status information for safety function Safe Torque Off, STO

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the STO safety function

TRUE

The STO safety function is active and currently in its safe state.

FALSE

The STO safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.4.7.3 S_SafetyActiveSTO1

General function

- Status information for safety function Safe Torque Off, One Channel, STO1

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the STO1 safety function

TRUE

The STO1 safety function is active and currently in its safe state.

FALSE

The STO1 safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.4.7.4 S_SafetyActiveSBC

General function

- Status information for safety function Safe Brake Control, SBC

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SBC safety function

TRUE

The SBC safety function is active and currently in its safe state.

FALSE

The SBC safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.4.7.5 S_SafetyActiveSOS

General function

- Status information for safety function Safe Operating Stop, SOS

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SOS safety function

TRUE

The SOS safety function is active and currently in its safe state.

FALSE

The SOS safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.4.7.6 S_SafetyActiveSS1

General function

- Status information for safety function Safe Stop 1, SS1

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SS1 safety function

TRUE

The SS1 safety function is active and currently in its safe state.

FALSE

The SS1 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.4.7.7 S_SafetyActiveSS2

General function

- Status information for safety function Safe Stop 2, SS2

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SS2 safety function

TRUE

The SS2 safety function is active and currently in its safe state.

FALSE

The SS2 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.4.7.8 S_SafetyActiveSLS1

General function

- Status information for safety function Safely Limited Speed, Speed Limit 1

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS1 safety function

TRUE

The SLS1 safety function is active and currently in its safe state.

FALSE

The SLS1 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.4.7.9 S_SafetyActiveSLS2

General function

- Status information for safety function Safely Limited Speed, Speed Limit 2

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS2 safety function

TRUE

The SLS2 safety function is active and currently in its safe state.

FALSE

The SLS2 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.4.7.10 S_SafetyActiveSLS3

General function

- Status information for safety function Safely Limited Speed, Speed Limit 3

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS3 safety function

TRUE

The SLS3 safety function is active and currently in its safe state.

FALSE

The SLS3 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.4.7.11 S_SafetyActiveSLS4

General function

- Status information for safety function Safely Limited Speed, Speed Limit 4

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS4 safety function

TRUE

The SLS4 safety function is active and currently in its safe state.

FALSE

The SLS4 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.4.7.12 S_SafetyActiveSLI

General function

- Status information for safety function Safely Limited Increment

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLI safety function

TRUE

The SLI safety function is active and currently in its safe state.

FALSE

The SLI safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.4.7.13 S_SafetyActiveSDIpos

General function

- Status information for safety function Safe Direction. Movement is allowed in the positive direction.

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SDIpos safety function

TRUE

The SDIpos safety function is active and currently in its safe state.

FALSE

The SDIpos safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.4.7.14 S_SafetyActiveSDIneg

General function

- Status information for safety function Safe Direction. Movement is allowed in the negative direction.

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SDIneg safety function

TRUE

The SDIneg safety function is active and currently in its safe state.

FALSE

The SDIneg safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.4.7.15 S_SafetyActiveSLP

General function

- Status information for safety function Safely Limited Position, SLP

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLP safety function

TRUE

The SLP safety function is active and currently in its safe state.

FALSE

The SLP safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.4.7.16 S_SafetyActiveSMP

General function

- Status information for safety function Safe Maximum Position, SMP

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SMP safety function

TRUE

The SMP safety function is active and currently in its safe state.

FALSE

Monitoring of the SMP position limits is not active. Monitoring is not active because the SafeMOTION module has not yet been homed, the function or the SafeMOTION module is in an error state or the function block has not been enabled.

7.4.7.17 S_SafePositionValid

General function

- Status information for the "Safe Homing" safety function and the safe position

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies whether or not safe homing of the axis has been completed and whether or not the position signal is valid.

TRUE

The axis has been safely homed, and the safe position is valid.

FALSE

The axis has not yet been safely homed, the axis encoder signal contains errors, the SafeMOTION module is in an error state or the function block has not been enabled.
The safe position is invalid!

> **Danger!**
>
> **The purpose of this signal is only to provide additional information.**
>
> **"S_SafePositionValid" does not represent the functional safe state of the SafeMOTION module!**

> **Danger!**
>
> **The value of the output parameter "S_SafePosition" is only valid if the output parameter "S_SafePositionValid" is SAFETRUE. Otherwise, it is invalid and is not permitted to be used further.**

7.4.7.18 S_SafetyActiveSDC

General function

- Information about the status of ramp monitoring

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the status of ramp monitoring.

TRUE

Ramp monitoring is active.

FALSE

Ramp monitoring is not active, the SafeMOTION module is currently in an error state or the function block has not been enabled.

> **Danger!**
>
> **This signal should only be used for status information.**

7.4.7.19 S_AllReqFuncActive

General function

- Information about the status of the requested safety functions

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies the status of the requested safety functions.

TRUE

All requested safety functions are currently in their functional safe state.

FALSE

One or more safety functions have not yet achieved their safe state, the SafeMOTION module is in an error state or the function block has not been enabled.

7.4.7.20 S_NotErrFUNC

General function

- Information about the error state of the safe SafeMOTION module

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies the error state of the SafeMOTION module.

TRUE

No error was found on the SafeMOTION module.

FALSE

An error was detected on the SafeMOTION module (e.g. a monitored limit was exceeded), or the function block has not been enabled.
In the event of an error, see the Safety Logger in Automation Studio for additional information about the error.
If the error is a functional error, then it can be acknowledged by changing the signal on input "Reset" from FALSE to TRUE (positive edge)!

> **Danger!**
>
> **The purpose of this signal is only to provide additional information. It only provides information in connection with the requested safety functions.**
> **"S_NotErrFUNC" does not represent the functional safe state of the SafeMOTION module!**

> **Danger!**
>
> **It is your responsibility to ensure that all necessary corrective measures are initiated after an error occurs since subsequent errors can result in a hazard!**

7.4.7.21 Error

General function

- Function block error message

Data type

- BOOL

Connection

- Variable

Function description

This formal parameter indicates a pending function block error message.

TRUE

The enabled function block detected an error. "DiagCode" indicates the error code.

FALSE

The function block is not enabled, or the enabled function block did not detect an error. "DiagCode" indicates the status.

> **Danger!**
>
> **It is your responsibility to ensure that all necessary corrective measures are initiated after an error occurs since subsequent errors can result in a hazard!**

In order to exit an error state ("Error" = TRUE), the signal on the "Reset" input must change from FALSE to TRUE (positive edge).

7.4.7.22 DiagCode

General function

- Function block diagnostic message

Data type

- WORD

Connection

- Variable

Function description

This output parameter is used to output diagnostic and status messages specific to the function block and make them available automatically to diagnostic tools.

These diagnostic tools cannot acknowledge diagnostic messages from function blocks. This is done exclusively in the **safety** application.

The function block indicates the presence of an error message on the "DiagCode" output via the "Error" output parameter.

Diagnostic code

The diagnostic code is specified as data type WORD. The values and meanings of these diagnostic codes are listed below.

In the event of status messages (0xxx$_{hex}$, 8xxx$_{hex}$), the function block sets "Error" to FALSE.

In the event of error messages (Cxxx$_{hex}$), the function block sets "Error" to TRUE.

7.4.7.23 Diagnostic codes

Code (hex)	State	Description	Possible workaround
0000	IDLE	The function block is not active.	Enable the function block by setting "Activate" to TRUE.
8001	INIT	The function block has been enabled and the SafeMOTION module is in the INIT state. The SafeMOTION module restart interlock is active.	Configure parameter "Startreset" accordingly or change to a positive edge on input "Reset".
8002	OPERATIONAL	The SafeMOTION module is in the OPERATIONAL state. No safety function is selected. The SMS speed limit is monitored according to the configuration.	No action required
8003	WAIT FOR CONFIRMATION	The SafeMOTION module is in the internal OPERATIONAL state. At least one safety function has been requested and at least one safety function has not yet achieved its functional safe state. None of the limits currently being monitored have been violated.	No action required
8000	SAFE STATE	All requested safety functions have achieved their functional safe state. None of the limits currently being monitored have been violated.	No action required
C000	FUNCTIONAL FAIL SAFE	An error occurred!	Check the Safety Logger in Automation Studio. It will provide detailed information about the current error. Depending on the type of error, check the standard and/or safety application. For functional errors, check the configuration of the SafeMOTION module or replace the faulty SafeMOTION module.

Table 416: SF_SafeMC_BR(_V2, _V3): Diagnostic codes

7.4.7.24 AxisStatus

General function

- Diagnostics message from the function block, representation of the axis status bits in a DWORD

Data type

- DWORD

Connection

- Variable

Function description

The "AxisStatus" output returns bit-coded information about the status of individual safety functions.
This information is equal to a summary of the S_xxx outputs in a DWORD.
The individual bits have the following meaning:

Bit 0	**Bit 1**	**Bit 2**	**Bit 3**	**Bit 4**	**Bit 5**	**Bit 6**	**Bit 7**
Status STO	Status SBC	Status SOS	Status SS1	Status SS2	Status SLS1	Status SLS2	Status SLS3
Bit 8	**Bit 9**	**Bit 10**	**Bit 11**	**Bit 12**	**Bit 13**	**Bit 14**	**Bit 15**
Status SLS4	Status STO1	Status SDI pos	Status SLI	Status SDI neg	Status SLP	Status SMP	Status PositionValid
Bit 16	**Bit 17**	**Bit 18**	**Bit 19**	**Bit 20**	**Bit 21**	**Bit 22**	**Bit 23**
-	Status Setposition Alive Test	Status SFR	Status All requested safety functions active	Status SDC	Status Operational	Status Not Encoder Error	Status Not Functional Error

Table 417: SF_SafeMC_BR_V2: SafeMOTION module status bits

7.4.8 State machine

The state machine illustrated here is implemented on the SafeMOTION module.

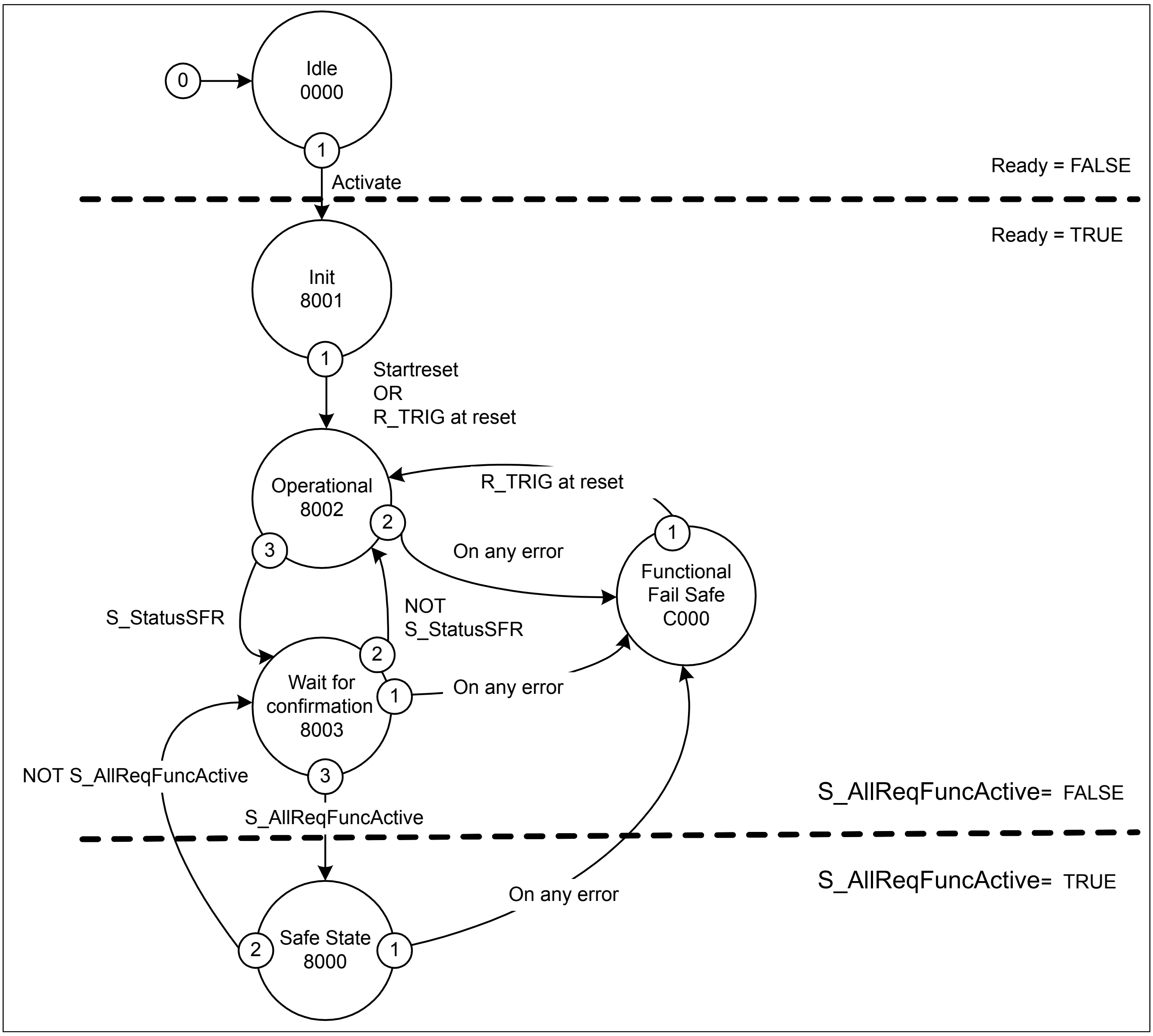


Figure 113: SF_SafeMC_BR(_V2): State machine

Individual states are reflected by the "DiagCode" output parameter. In this way, the function block provides a representation of the state machine on the SafeMOTION module.

7.4.9 Signal sequence diagram of the function block

A general signal sequence diagram of the function block cannot be specified since it depends on which safety functions are selected or deselected.

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

7.5 SF_SafeMC_BR_V3

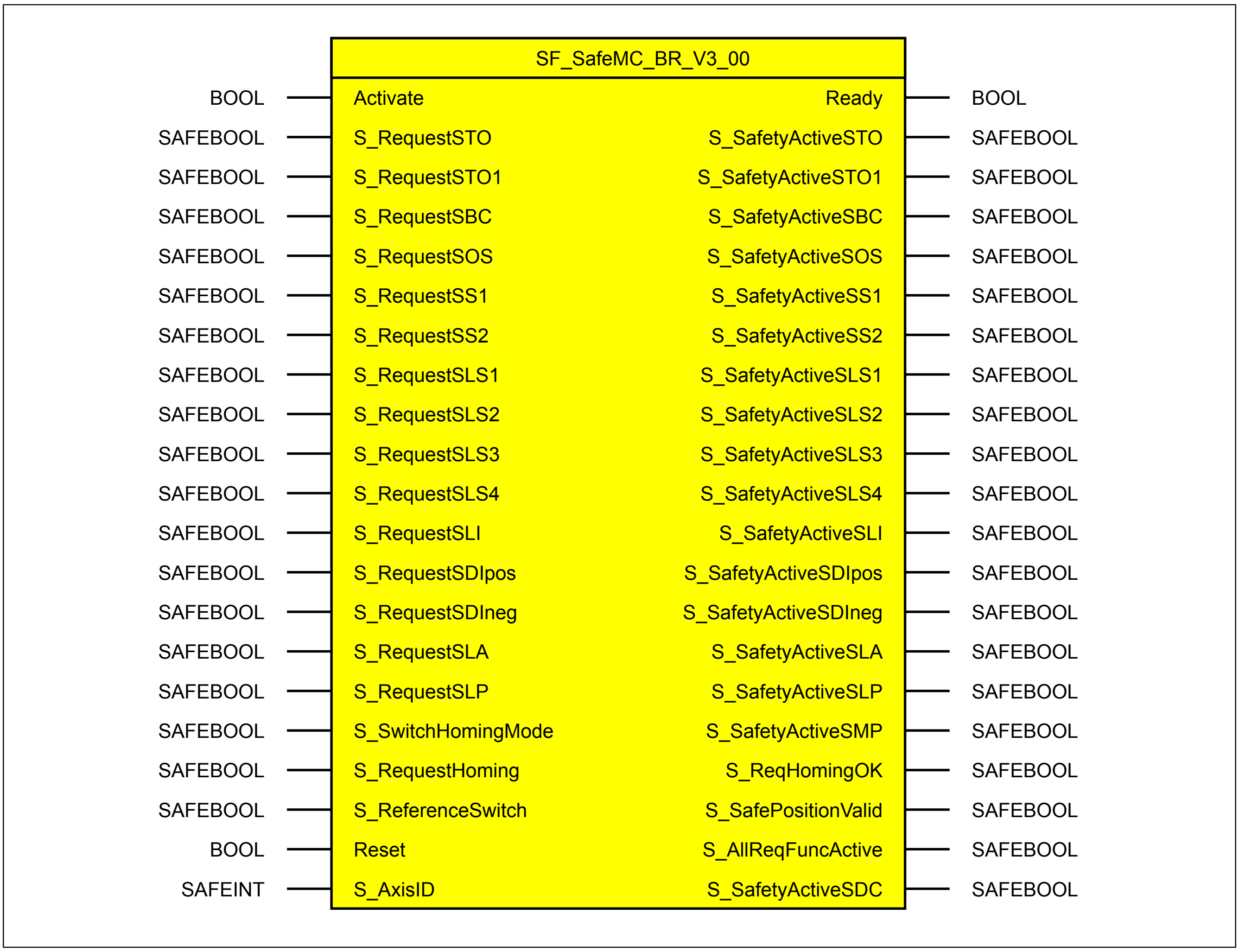


Figure 114: SF_SafeMC_BR_V3 function block

Information:

The SF_SafeMC_BR_V3_00 function block can only be used with Safety Release 1.9.

If a previous Safety Release is being used, then SafeDESIGNER will return an error when compiling the safety application!

7.5.1 Formal parameters of the function block

In the following, the term "variable" refers to both a variable as well as a graphic connection.

Name	Type	Connection	Signal type [1]	Initial value	Description / General function
Activate	BOOL	Variable/ Constant	State	FALSE	Enables the function block (= TRUE)
S_RequestSTO	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	STO safety function request: SAFEFALSE: Safety function requested
S_RequestSTO1	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	STO1 safety function request: SAFEFALSE: Safety function requested
S_RequestSBC	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SBC safety function request: SAFEFALSE: Safety function requested
S_RequestSOS	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SOS safety function request: SAFEFALSE: Safety function requested
S_RequestSS1	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SS1 safety function request: SAFEFALSE: Safety function requested
S_RequestSS2	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SS2 safety function request: SAFEFALSE: Safety function requested
S_RequestSLS1	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLS1 safety function request: SAFEFALSE: Safety function requested
S_RequestSLS2	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLS2 safety function request: SAFEFALSE: Safety function requested
S_RequestSLS3	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLS3 safety function request: SAFEFALSE: Safety function requested
S_RequestSLS4	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLS4 safety function request: SAFEFALSE: Safety function requested
S_RequestSLI	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLI safety function request: SAFEFALSE: Safety function requested
S_RequestSDIpos	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SDIpos safety function request: SAFEFALSE: Safety function requested
S_RequestSDIneg	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SDIneg safety function request: SAFEFALSE: Safety function requested
S_RequestSLA	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLA safety function request SAFEFALSE: Safety function requested
S_RequestSLP	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SLP safety function request SAFEFALSE: Safety function requested
S_SwitchHomingMode	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Homing with RSP enabled. SAFEFALSE: Homing with RSP disabled.
S_RequestHoming	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safe homing Request is made on a positive edge!
S_ReferenceSwitch	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Safe input for a reference switch
Reset	BOOL	Variable	Edge	FALSE	Resets error messages and the SafeMOTION module after the cause of the error has been removed
S_AxisID	SAFEINT	Constant	State	-1	Assigns an axis to the function block

Table 418: SF_SafeMC_BR_V3: Overview of input parameters

1) Evaluation of the input parameter signals in the function block. The signals must be controlled accordingly by the user.

Name	Type	Connection	Signal type [1]	Initial value	Description / General function
Ready	BOOL	Variable	State	FALSE	Indicates that the function block is enabled
S_SafetyActiveSTO	SAFEBOOL	Variable	State	SAFEFALSE	STO safety function active (= SAFETRUE)
S_SafetyActiveSTO1	SAFEBOOL	Variable	State	SAFEFALSE	Safety function STO1 active (= SAFETRUE)
S_SafetyActiveSBC	SAFEBOOL	Variable	State	SAFEFALSE	SBC safety function active (= SAFETRUE)
S_SafetyActiveSOS	SAFEBOOL	Variable	State	SAFEFALSE	SOS safety function active, no violation of a monitored limit (= SAFETRUE)
S_SafetyActiveSS1	SAFEBOOL	Variable	State	SAFEFALSE	SS1 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSS2	SAFEBOOL	Variable	State	SAFEFALSE	SS2 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSLS1	SAFEBOOL	Variable	State	SAFEFALSE	SLS1 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSLS2	SAFEBOOL	Variable	State	SAFEFALSE	SLS2 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)

Table 419: SF_SafeMC_BR_V3: Overview of output parameters

Name	Type	Connection	Signal type 1)	Initial value	Description / General function
S_SafetyActiveSLS3	SAFEBOOL	Variable	State	SAFEFALSE	SLS3 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSLS4	SAFEBOOL	Variable	State	SAFEFALSE	SLS4 safety function active, deceleration monitoring completed, no violation of a monitored limit detected (= SAFETRUE)
S_SafetyActiveSLI	SAFEBOOL	Variable	State	SAFEFALSE	SLI safety function active, no violation of a monitored limit (= SAFETRUE)
S_SafetyActiveSDIpos	SAFEBOOL	Variable	State	SAFEFALSE	SDIpos safety function active (= SAFETRUE)
S_SafetyActiveSDIneg	SAFEBOOL	Variable	State	SAFEFALSE	Safety function SDIneg active (= SAFETRUE)
S_SafetyActiveSLA	SAFEBOOL	Variable	State	SAFEFALSE	SLA safety function is active, no violation of a monitored limit (= SAFETRUE)
S_SafetyActiveSLP	SAFEBOOL	Variable	State	SAFEFALSE	SLP safety function active (= SAFETRUE)
S_SafetyActiveSMP	SAFEBOOL	Variable	State	SAFEFALSE	SMP safety function active (= SAFETRUE)
S_ReqHomingOK	SAFEBOOL	Variable	State	SAFEFALSE	Feedback for homing in SafeDESIGNER (=SAFETRUE, safe position is valid and request for safe homing is SAFETRUE)
S_SafePositionValid	SAFEBOOL	Variable	State	SAFEFALSE	Specifies whether the safe position is valid (=SAFETRUE, homing procedure has completed successfully and there are no encoder errors)
S_AllReqFuncActive	SAFEBOOL	Variable	State	SAFEFALSE	All requested safety functions have achieved their safe state. (= SAFETRUE)
S_SafetyActiveSDC	SAFEBOOL	Variable	State	SAFEFALSE	Deceleration monitoring active (= SAFETRUE)
S_NotErrFUNC	SAFEBOOL	Variable	State	SAFEFALSE	SafeMOTION module not in the FUNCTIONAL FAIL SAFE state (= SAFETRUE)
Error	BOOL	Variable	State	FALSE	Function block error message
DiagCode	WORD	Variable	State	16#0000	Function block diagnostic message
AxisStatus	DWORD	Variable	State	32#00000000	Status information from axis

Table 419: SF_SafeMC_BR_V3: Overview of output parameters

1) Output of the output parameter signals. The signals must be evaluated and/or further processed accordingly by the user.

Type	Description	Size in bits	Format option
BOOL	Bit	1	Bit string
WORD	Word	16	Bit string
DINT	Double integer	32	Binary number, hexadecimal number, signed decimal number
SAFEBOOL	Bit	1	Bit string (signal source: safe device)
SAFEDWORD	Double word	32	Bit string (signal source: safe device)
SAFEDINT	Double integer	32	Binary number, hexadecimal number, signed decimal number (signal source: safe device)
SAFEINT	Integer	16	Binary number, hexadecimal number, signed decimal number (signal source: safe device)

Table 420: Format description of the data types

You have the option of linking a safe signal with a non-safe input parameter. To do so, use a function block for type conversion.

Caution!

You are responsible for any conversion of a non-safe input parameter to a safe signal.

7.5.2 SafeMOTION module parameters

Group: Safe machine options (previously *Additional Parameter*)

Parameter	Unit	Description	Default value	Used starting in Safety Release
Safe machine options - Enable (previously *Activate Safe Machine Options*)	Enabled/ Disabled	Activates/Deactivates the "Safe machine options" safety function	Disabled	R 1.9

Table 421: SafeMOTION parameter group: Safe machine options

Group: General settings - Encoder Unit System (previously *Encoder Unit System*)

Parameter	Unit	Description	Default value	Starting in Safety Release
EUS - Count of physical reference system (previously *Count of physical reference system*)	-	Rotary encoder unit scale: X revolutions Linear encoder unit scale: X reference lengths (reference length = length of the physical reference system) Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration). For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.	1	R 1.4
EUS - Units per count of physical reference system (previously *Units per count of physical reference system [units]*)	[units]	Rotary encoder unit scale: Units per x revolutions Linear encoder unit scale: Units per x reference lengths Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration). For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.	1000	R 1.4
EUS - Counting direction (previously *Counting direction*)	Standard / Inverse	Counting direction of the position or speed **Value** / **Description**: Default: Encoder counting direction is equal to the counting direction of the unit system. Inverse: Encoder counting direction is negative to the counting direction of the unit system.	Default	R 1.3
EUS - Length of physical reference system for linear encoder (previously *Length of physical reference system for linear encoder (nm)*)	[nm]	For linear measurement systems, the length of a physical reference system is defined here. This value is not used for rotary encoders, where the reference system is a single revolution.	1000000000	R 1.4
EUS - Maximum speed to normalize speed range (previously *Maximum speed to normalize the speed range (units/s)*)	[units/s]	Maximum speed to which the displayed speed should be normalized	32767	R 1.3
EUS - Encoder acceleration limit (previously *Maximum acceleration (rad/s² or mm/s²)*)	[rad/s²] or [mm/s²]	Maximum permissible encoder acceleration	100000	R 1.4

Table 422: SafeMOTION parameter group: General settings - Encoder Unit System

Group: Absolute position functions - Homing (previously *Homing*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Home position or home offset (previously *Home Position or Home Offset (units)*)	[units]	Home position or home offset	0	R 1.4
Homing - Maximum trigger speed (previously *Max. trigger speed (units/s)*)	[units/s]	Maximum permissible speed for evaluating the reference switch / reference pulse	0	R 1.4
Homing - Monitoring time (previously *Homing Monitoring Time (µs)*)	[µs]	Monitoring time for the homing procedure	0	R 1.4

Table 423: SafeMOTION parameter group: Absolute position functions - Homing

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Mode (previously *Mode*)	Direct / Reference switch / *Home Offset / Home offset with correction*	Selects the homing mode *Modes "Home offset" and "Home offset with correction" are only available for ACOPOSmulti SafeMOTION EnDat 2.2!*	Direct	R 1.4
Homing - Edge of reference switch (previously *Edge of reference switch*)	Positive / Negative	Selects the switching edge for the reference switch The switching edge for the reference switch input is positive if the logical state of the reference switch changes from SAFEFALSE to SAFETRUE in the positive direction of movement.	Positive	R 1.4
Homing - Trigger direction (previously *Trigger direction*)	Positive / Negative	Selects the trigger direction If the homing procedure requires a movement, then this parameter specifies the direction for evaluating the reference switch / reference pulse.	Positive	R 1.4
Homing - Enable reference pulse *(previously Reference pulse)*	*Enabled/ Disabled*	*Selects whether or not to use a reference pulse for homing* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2!*	*Disabled*	R 1.4
Homing - Blocking distance *(previously Blocking distance (% encoder reference system))*	*%*	*Distance within which evaluation of the reference pulse will be suppressed. This is calculated starting at the configured reference switch edge and indicated as a percentage of the encoder reference system.* *A single revolution is used as the encoder reference system for rotary encoders.* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2!*	*0*	R 1.4

Table 423: SafeMOTION parameter group: Absolute position functions - Homing

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 424: SafeMOTION parameter group: General settings - Ramp monitoring

Group: Basic functions - SS1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS1 - Ramp monitoring - Enable

(previously Rampmonitoring for SS1)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SS1 function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When transitioning to the safe state of the SS1 function, a deceleration ramp is monitored in addition to the configurable time.</td></tr>
<tr><td>Disabled</td><td>When transitioning to the safe state of the SS1 function, only a configurable time is monitored.</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS1</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 425: SafeMOTION parameter group: Basic functions - SS1

Group: Speed functions - SS2 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS2 - Ramp monitoring - Enable

(previously Rampmonitoring for SS2)</td><td>Enabled/
Disabled</td><td>Activates ramp monitoring (in addition to time-based monitoring) when the SS2 function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When changing to the safe state of the SS2 function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr><tr><td>Disabled</td><td>When changing to the safe state of the SS2 function, only a configurable time is monitored</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>Ramp Monitoring Time for SS2 (us)</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS2</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 426: SafeMOTION parameter group: Speed functions - SS2

Group: General settings - Automatic reset on start (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Used Starting in Safety Release</th></tr>
<tr><td>Automatic reset on start - Enable

(previously Automatic Reset at Startup)</td><td>Enabled/
Disabled</td><td>Activates automatic reset of the function block at startup<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>After startup, the module automatically changes to state OPERATIONAL (Startreset). The reset input does not have to be controlled!</td></tr><tr><td>Disabled</td><td>After startup, the module remains in an Init state until a positive edge of the reset input is detected.</td></tr></table></td><td>Disabled</td><td>R1.3</td></tr>
</table>

Table 427: SafeMOTION parameter group: General settings - Automatic reset on start

Group: Basic functions - STO1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>STO1 - Channel

(previously Channel selection for One Channel STO (STO1))</td><td>High-side/
Low-side</td><td>Selects the high-side or low-side IGBT in the STO1 function<table><tr><th>Value</th><th>Description</th></tr><tr><td>High-side</td><td>The high-side IGBTs are actuated with the function STO1.</td></tr><tr><td>Low-side</td><td>The low-side IGBTs are actuated with the function STO1.</td></tr></table></td><td>High-side</td><td>R 1.3</td></tr>
</table>

Table 428: SafeMOTION parameter group: Basic functions - STO1

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SMS - Enable

(previously Safe Maximum Speed)</td><td>Enabled/
Disabled</td><td>Activates the SMS safety function by configuration<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>SMS activated</td></tr><tr><td>Disabled</td><td>SMS deactivated</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SMS - Speed limit

(previously Maximum Speed for SMS (units/s))</td><td>[units/s]</td><td>Speed limit of the maximum speed (SMS)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS1 - Speed limit

(previously Safe Speedlimit 1 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 1 for SLS (SLS1)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Speed limit

(previously Safe Speedlimit 2 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 2 for SLS (SLS2)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS3 - Speed limit

(previously Safe Speedlimit 3 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 3 for SLS (SLS3)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS4 - Speed limit

(previously Safe Speedlimit 4 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 4 for SLS (SLS4)</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 429: SafeMOTION parameter group: Speed functions - SMS/SLS

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SLS - Ramp monitoring - Enable

(previously Rampmonitoring for SLS)</td><td>Enabled/ Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr><tr><td>Disabled</td><td>When changing to the safe state of the SLS function, only a configurable time is monitored</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SLS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS1</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS2 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS2</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS3 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS3</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS4 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS4 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS4</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 429: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: Speed functions - SLA (previously *Safely Limited Acceleration*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLA - Acceleration limit in positive direction (previously *Safe acceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for acceleration in the positive direction of movement	0	R 1.9
SLA - Deceleration limit in positive direction (previously *Safe deceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for deceleration in the positive direction of movement	0	R 1.9
SLA - Acceleration limit in negative direction (previously *Safe acceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for acceleration in the negative direction of movement	0	R 1.9
SLA - Deceleration limit in negative direction (previously *Safe deceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for deceleration in the negative direction of movement	0	R 1.9
SLA - Enable delay time (previously *Delay time to start SLA (us)*)	[µs]	Delay time between the SLA request and activation of the safety function	0	R 1.9

Table 430: SafeMOTION parameter group: Speed functions - SLA

Group: Absolute position functions - SMP/SLP (previously *Safety Position Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SMP - Enable (previously *Safe Maximum Position*)	Enabled/ Disabled	Activates the SMP safety function from the configuration **Value** – **Description** Enabled – SMP is activated Disabled – SMP is deactivated	Disabled	R 1.4
SMP - Lower position limit (previously *Safe Lower Position Limit for SMP (units)*)	[units]	Lower position limit for the machine's full travel range	0	R 1.4
SMP - Upper position limit (previously *Safe Upper Position Limit for SMP (units)*)	[units]	Upper position limit for the machine's full travel range	0	R 1.4
SLP - Lower position limit (previously *Safe Lower Position Limit for SLP (units)*)	[units]	Lower position limit for the monitoring range	0	R 1.4
SLP - Upper position limit (previously *Safe Upper Position Limit for SLP (units)*)	[units]	Upper position limit for the monitoring range	0	R 1.4
SLP - Enable delay time (previously *Delay time to start SLP (us)*)	[µs]	Delay time between the SLP request and start of monitoring	0	R 1.4

Table 431: SafeMOTION parameter group: Absolute position functions - SMP/SLP

Group: General settings - Encoder monitoring (previously *Encoder Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Encoder monitoring - Safe Encoder Mounting (Hardware upgrade 1.10.3.x and later)	From motor data record / Approved by user	Status of the proof of fatigue strength of the encoder mounting **Value** – **Description** From motor data record – The status of the encoder mounting is determined using the motor data record. Approved by user – The user confirms safe encoder mounting / no mounting information available in the motor data record.	From motor data record	R1.10
Encoder monitoring - Position error monitoring - Enable *(previously Encoder Position monitoring)*	Enabled/ Disabled	Enables/Disables monitoring of the position lag error generated on the SafeMOTION module **Value** – **Description** Enabled – Monitoring active Disabled – Monitoring not active	Enabled	R1.3
Encoder monitoring - Speed error monitoring - Enable (previously *Encoder Speed monitoring*)	Enabled/ Disabled	Activates/Deactivates monitoring of the speed error generated on the SafeMOTION module **Value** – **Description** Enabled – Monitoring active Disabled – Monitoring not active	Enabled	R1.3
Encoder monitoring - Position setpoint alive testing (SPA) - Enable (previously *Set position alive testing*)	Enabled/ Disabled	Activates/Deactivates the monitor that detects whether the position setpoint generated on the SafeMOTION module is frozen. **Value** – **Description** Enabled – Monitoring active Disabled – Monitoring not active	Disabled	R1.3
Encoder monitoring - Position error tolerance (previously *Encoder monitoring Position tolerance (units)*)	[units]	Position lag error tolerance for shaft breakage monitoring	0	R1.3
Encoder monitoring - Speed error tolerance (previously *Encoder monitoring Speed tolerance (units/s)*)	[units/s]	Speed error tolerance for encoder monitoring	0	R1.3

Table 432: SafeMOTION parameter group: General settings - Encoder monitoring

Group: General settings - Behavior of Functional Fail Safe (FFS) (previously *Behavior of Functional Fail Safe*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Used Starting in Safety Release</th></tr>
<tr><td>FFS - Mode

(previously Behavior of Functional Fail Safe)</td><td>STO /
STO1 and STO with time delay</td><td>In the FUNCTIONAL FAIL SAFE state, STO and SBC are activated immediately, or STO1 is activated and then STO after a delay.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>STO</td><td>In the FUNCTIONAL FAIL SAFE state, STO and SBC are activated immediately.</td></tr>
<tr><td>STO1 and STO with time delay</td><td>In the FUNCTIONAL FAIL SAFE state, STO1 and SBC are activated first, and then STO after a delay.</td></tr>
</table></td><td>STO</td><td>R 1.3</td></tr>
<tr><td>FFS - STO Enable delay time

(previously Delay for STO in Functional Fail Safe [µs])</td><td>[µs]</td><td>Delay time between STO1 and STO (and SBC) in the FUNCTIONAL FAIL SAFE state</td><td>0</td><td>R 1.3</td></tr>
<tr><td>FFS - Delay time until brake engages

(previously Delay time until the brake engages [µs])</td><td>[µs]</td><td>Delay time before the brake engages
The second enable channel is activated after this delay time if STO1 and time-delayed STO and SBC are configured for FUNCTIONAL FAIL SAFE.</td><td>0</td><td>R 1.3</td></tr>
<tr><td>FFS - Caused by encoder error
(1.10.1.x for ACOPOSmulti SafeMOTION and hardware upgrade 1.10.2.x or later for ACOPOS P3 SafeMOTION)</td><td>Always / Only if safety functions requiring an encoder are enabled</td><td>Enable FUNCTIONAL FAIL SAFE on encoder error:
Always:
FFS occurs if at least one safety function that requires an encoder is used and an encoder error is present.
Only if safety functions requiring an encoder are enabled:
FFS occurs if at least one safety function that requires an encoder is active and an encoder error is present.</td><td>Always</td><td>R 1.10.1</td></tr>
</table>

Table 433: SafeMOTION parameter group: General settings - Behavior of Functional Fail Safe (FFS)

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 434: SafeMOTION parameter group: General settings - Standstill monitoring

Group: Advanced functions - SLI (previously *Safely Limited Increment*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLI - Position limit (previously *Safe Increments (units)*)	[units]	Maximum movable increments when SLI is active	0	R 1.3
SLI - Disable delay time (previously *SLI Off Delay (µs)*)	[µs]	Switch off delay of SLI	0	R 1.3

Table 435: SafeMOTION parameter group: Advanced functions - SLI

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring*)	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** / **Description** Enabled / "Early Limit Monitoring" is active! Disabled / "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us)*)	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 436: SafeMOTION parameter group: General settings - Early limit monitoring

Group: Basic functions - SBC (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBC - Enable delay time (previously *Delay time to start SBC (us)*)	[µs]	Delay time between the SBC request and activation of the safety function	0	R 1.3

Table 437: SafeMOTION parameter group: Basic functions - SBC

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*)	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 438: SafeMOTION parameter group: Advanced functions - SDI

In a safety application, it is possible for multiple safety functions to be requested at the same time. In order to prevent this from turning into an unsafe situation, the individual safety functions are prioritized on the SafeMOTION module.

If several functions are active, then the lowest speed limit is always the value being monitored.

Information:

The following application rule must be observed:

$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS} \leq$ EUS - Maximum speed to normalize speed range

This is required for setting priority of the safety functions on the SafeMOTION module.

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

7.5.3 Integrated safety functions

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

7.5.4 Safe encoder connection monitoring

7.5.4.1 Encoder mounting with proof of fatigue strength[23)]

To prevent errors caused by encoder slippage or shaft breakage, the mechanical mounting of the encoder requires proof of fatigue strength.

This proof and the corresponding mounting guidelines can be provided either by the manufacturer of the measuring instrument or by the manufacturer of the machine.

Danger!

To ensure safe operation up to and including the motor shaft, any errors in the connection between the motor shaft and encoder must be identified and prevented.

Danger!

Proof of fatigue strength for the encoder's mechanical mounting is to be dimensioned to the maximum rotor acceleration. This acceleration value is not permitted to be exceeded in the worst case. The maximum acceleration is monitored on the SafeMOTION module and can be configured using parameter "EUS - Encoder acceleration limit".

Danger!

Mechanical tolerances in the encoder mounting must be taken into account when calculating the residual distance. This residual movement must be taken into account by the safety functions.

Danger!

To ensure safe operation up to and including the motor shaft, any errors in the connection between the motor shaft and encoder must be identified and prevented.
There are specific guidelines that must be followed when installing a functional safety encoder.
The motor manufacturer must ensure that these specifications are adhered to.

Danger!

The frictional connection between the cone-shaped shaft of the rotor and measuring instrument can be dimensioned for maximum rotor acceleration in accordance with the mounting instructions provided by the encoder manufacturer. This acceleration value is not permitted to be exceeded in the worst case. The maximum acceleration is monitored on the SafeMOTION module and can be configured using parameter "EUS - Encoder acceleration limit".

Danger!

If the terminal screw for the coupling ring becomes loose on installed measuring instruments, then the form-fit pin will be the only thing holding the encoder to the motor housing. A movement in accordance with the mounting tolerances is possible. The encoder is not able to register this movement. This residual movement must be taken into account by the safety functions.

7.5.4.2 Encoder mounting without proof of fatigue strength - Safe lag error monitoring[24)]

If "General settings - Encoder monitoring" is activated in the SafeMOTION module, in some applications the proof of fatigue strength for the mechanical mounting of the encoder is not required.

The following safety-related restrictions must be taken into account!

Danger!

Only safety functions in which no safe absolute position is monitored are permitted to be used (STO, SBC, SOS, SS1, SS2, SLS, SMS, SLI, SDI, SLA, SBT (only available for ACOPOSmulti SafeMOTION SinCos and ACOPOS P3 SafeMOTION), SLT (only available for ACOPOS P3 SafeMOTION) and Safe Speed).

23) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR, SF_oS_MOTION_ScaledSpeed_BR, SF_oS_MOTION_Position_BR.

24) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR, SF_oS_MOTION_ScaledSpeed_BR, SF_oS_MOTION_Position_BR.

Danger!

The application must meet the following requirements for safety-related monitoring of the encoder-motor connection:

- **Encoder connection monitoring is only permitted to be used for encoders that are integrated in position control.**
- **Encoder connection monitoring is only permitted to be used for drive systems with synchronous motors.**
- **The encoder must be protected against shearing in standstill (e.g. with encasement in the motor housing)!**
- **Monitoring for position lag errors, speed errors and position setpoints change (Alive Testing) must be enabled in the safety application, and sufficiently strict limits must be monitored!**
- **Safety functions Safe Position, SLP and/or SMP are not permitted to be not be used!**
- **Safe monitoring can only be guaranteed when closed-loop control is enabled.**

Danger!

- **An electrical offset of <90° will not be detected sufficiently.**
- **There is no way to monitor the encoder connection if the setpoint remains constant.**
- **An encoder connection error or an error in encoder evaluation is always assumed as the cause for the lag error.**
- **The error reaction in the standard application to a position lag error or speed error is disabled by the SafeMOTION module (overridden). When lag errors occur, only the error responses STO or STO1 with an induction stop are possible.**

Danger!

Note that an error can result in a forward movement. The maximum angle of rotation φ of the motor shaft during this forward movement depends on the motor being used.

For permanent magnet synchronous motors, φ = 360°/2p. For three-phase induction motors, there is a relatively small angle of rotation between 5° and 15°.

The maximum speed of the forward movement can be calculated as follows:

$$n_{Jolt} = \frac{1}{2\pi}\sqrt{\frac{6a_{max}}{p_z}}\left[\frac{U}{s}\right]$$

With the maximum acceleration $a_{max} = \frac{M_{max}}{J}\left[\frac{rad}{s^2}\right]$ **And number of motor pole pairs** p_z

Danger!

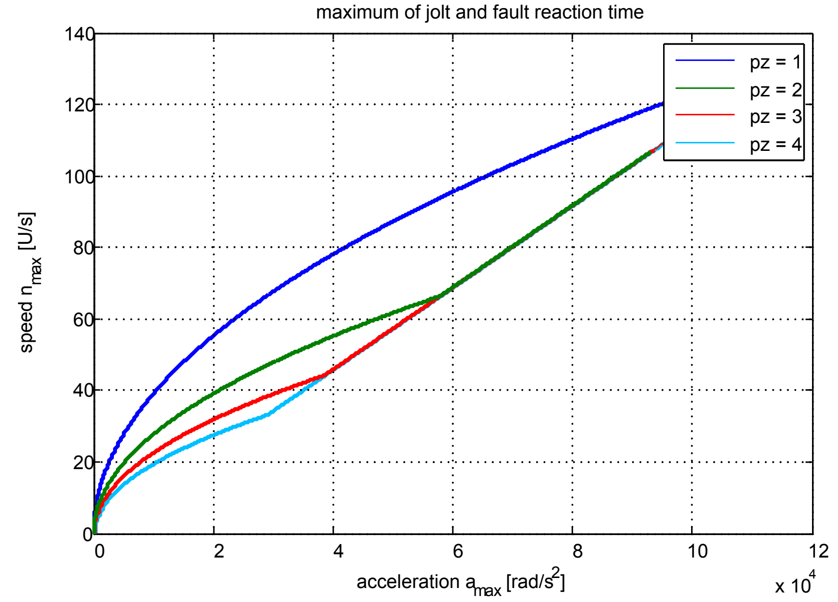
In the worst-case consideration of a safety function, the maximum achievable speed must be the maximum of maximum actuation speed n_{Jolt} **and the speed due to the maximum error response time** $n_{T_{worstcase}}$.

$$n_{max} = max(n_{Jolt}, n_{T_{worstcase}}) = max\left(\frac{1}{2\pi}\sqrt{\frac{6a_{max}}{p_z}}, \frac{T_{worstcase}}{2\pi}\cdot a_{max}\right)$$

With the maximum error response time $T_{worstcase} = 7.2[ms]$

The maximum speed n_{max} **resulting from this must be considered together with the speed when the safety function** n_{LIM} **is violated in order to determine the maximum possible speed** $n_{worstcase}$ **at the time of coasting to a stop.**

$$n_{worstcase} = n_{LIM} + n_{max}$$



Information:

In order to check the plausibility of setpoint selection after each power on, the axis must be moved by at least twice the configured lag error limit before the first request of a safety function, which requires a safe encoder evaluation, or at least within 15 min.
If this is not done, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state. The "S_NotErrFUNC" output on the function block is reset, and the drive loses all torque/power and coasts to a stop!
In the event of an error, a synchronous axis will no longer be synchronous.

Danger!

Situations involving external forces (e.g. hanging loads) can result in dangerous movements!
If this poses a safety risk, then the user must implement the necessary equipment to eliminate the risk (e.g. mechanical brakes)! This equipment must correspond to the required safety level!

Information:

A 24-hour timeout begins after successfully checking the plausibility of the setpoint.
The timeout is reset any time the position setpoint changes by more than twice the position lag error tolerance.
If the position setpoint does not change during 24 hours of continuous controller operation, then the SafeMOTION module will switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state. The "S_NotErrFUNC" output on the function block is reset, and the drive loses all torque/power and coasts to a stop! In the event of an error, a synchronous axis will no longer be synchronous.

The following parameters are relevant for safe monitoring of the encoder-motor shaft connection (Encoder Monitoring):

Group: General settings - Encoder monitoring (previously *Encoder Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Encoder monitoring - Safe Encoder Mounting (Hardware upgrade 1.10.3.x and later)</td><td>From motor data record / Approved by user</td><td>Status of the proof of fatigue strength of the encoder mounting<table><tr><th>Value</th><th>Description</th></tr><tr><td>From motor data record</td><td>The status of the encoder mounting is determined using the motor data record.</td></tr><tr><td>Approved by user</td><td>The user confirms safe encoder mounting / no mounting information available in the motor data record.</td></tr></table></td><td>From motor data record</td><td>R1.10</td></tr>
<tr><td>Encoder monitoring - Position error monitoring - Enable

(previously Encoder Position monitoring)</td><td>Enabled/ Disabled</td><td>Enables/Disables monitoring of the position lag error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error monitoring - Enable

(previously Encoder Speed monitoring)</td><td>Enabled/ Disabled</td><td>Activates/Deactivates monitoring of the speed error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position setpoint alive testing (SPA) - Enable

(previously Set position alive testing)</td><td>Enabled/ Disabled</td><td>Activates/Deactivates the monitor that detects whether the position setpoint generated on the SafeMOTION module is frozen.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Disabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position error tolerance

(previously Encoder monitoring Position tolerance (units))</td><td>[units]</td><td>Position lag error tolerance for shaft breakage monitoring</td><td>0</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error tolerance

(previously Encoder monitoring Speed tolerance (units/s))</td><td>[units/s]</td><td>Speed error tolerance for encoder monitoring</td><td>0</td><td>R1.3</td></tr>
</table>

Table 439: SafeMOTION parameter group: General settings - Encoder monitoring

Group: General settings - Encoder Unit System (previously *Encoder Unit System*)

Parameter	Unit	Description	Default value	Starting in Safety Release
EUS - Encoder acceleration limit (previously *Maximum acceleration (rad/s² or mm/s²)*)	[rad/s²] or [mm/s²]	Maximum permissible encoder acceleration	100000	R 1.4

Table 440: SafeMOTION parameter group: General settings - Encoder Unit System

Information:

The physical drive speed is not permitted to exceed the value set for parameter "EUS - Maximum speed to normalize speed range"; otherwise, the SafeMOTION module will switch to the error state!

Danger!

If the manufacturer of the measuring instrument specifies a limitation of the maximum acceleration, this must be monitored by the SafeMOTION module. The acceleration to be monitored can be configured using parameter "EUS - Encoder acceleration limit".

Danger!

Incorrectly configuring the unit system can result in dangerous situations.
When validating the application, the monitored speed limits must be intentionally violated and their physical values tested! The same must also be done for the monitored direction of rotation!

Danger!

The machine manufacturer is responsible for determining whether or not the application is suited for safe encoder connection monitoring if there is no mechanical mechanism for detecting encoder shaft breakage.
The machine manufacturer is responsible for ensuring that the safe encoder monitoring has been configured correctly!

Danger!

Encoder connection monitoring is only permitted to be used in a safety-related capacity if the aforementioned requirements for the application have been fulfilled!

7.5.4.2.1 Activating monitoring[25)]

The following parameters must be set to "Enabled" in SafeDESIGNER in order to enable safe encoder connection monitoring:

- "Encoder monitoring - Position error monitoring - Enable" = Enabled
- "Encoder monitoring - Speed error monitoring - Enable" = Enabled
- "Encoder monitoring - Position setpoint alive testing (SPA) - Enable" = Enabled

Danger!

In order to ensure safety-related monitoring of the encoder/motor connection, all three parameters "Encoder monitoring - Position error monitoring - Enable", "Encoder monitoring - Speed error monitoring - Enable" and "Encoder monitoring - Position setpoint alive testing (SPA) - Enable" must be set to "Enabled"!
If this is not the case, then the monitoring system cannot be used for safety purposes and a mechanical solution for detecting errors must be implemented!

7.5.4.2.2 Configuration rule for position lag error tolerance[26)]

The position lag error tolerance must be set large enough to ensure availability. This can be done by first measuring the position lag error under the highest influence of disturbance variables and at maximum acceleration and then setting the position lag error tolerance accordingly higher.

Danger!

The position lag error tolerance is not permitted to be higher than half of one pole length!

If the safety function is activated, the size of the position lag error tolerance value affects how long it will take to look for errors and therefore also the error response time and estimation of the residual distance.

This must be taken into account by the machine manufacturer in the risk analysis!

Information:

Due to rounding errors, a reserve of 1 unit should be taken into account with the parameter "Encoder monitoring - Position error tolerance".

25) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR, SF_oS_MOTION_ScaledSpeed_BR, SF_oS_MOTION_Position_BR.

26) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR, SF_oS_MOTION_ScaledSpeed_BR, SF_oS_MOTION_Position_BR.

7.5.4.2.3 Configuration rule for speed error tolerance[27)]

The speed error tolerance must be set large enough to ensure availability.
This can be done by first measuring the speed error under the highest influence of disturbance variables and reference variables (e.g. at maximum acceleration) and then setting the speed error tolerance accordingly higher.

Danger!

When the safety function is enabled, the size of the speed error tolerance value affects how long it will take to look for errors and therefore also the error response time and estimation of the residual distance.

This must be taken into account by the machine manufacturer in the risk analysis!

Information:

Due to rounding errors, a reserve of 1 unit/s should be taken into account with the parameter "Encoder monitoring - Speed error tolerance".

27) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR, SF_oS_MOTION_ScaledSpeed_BR, SF_oS_MOTION_Position_BR.

7.5.5 Fault avoidance

> ## Danger!
> **Validation**
>
> **Each safety function that is used must be validated separately.**
> **It is also necessary to test the entire safety application, including the interactions between individual functions.**

7.5.5.1 Exceeding monitored limits

The SafeMOTION module monitors configurable limits. The drive itself, however, is controlled by the standard application on the standard PLC.

To prevent a violation of a monitored limit, the following points must be observed:

- The movement of the drive must be adapted to the requested safety function and initiated on time.
- The monitored limits must match the calculated limits and movement limitations. Make sure that the different configurations of the unit system match in the safety application and in the standard application!

> ## Danger!
> **Any violation of a monitored limit will cause the module to switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state.**
>
> **The "S_NotErrFUNC" output on the function block is reset, and the drive loses all torque/power and coasts to a stop!**
>
> **Depending on the configuration, the motor holding brake will also be switched to 0 V.**
>
> **In the event of an error, a synchronous axis will no longer be synchronous.**
>
> **Check the Safety Logger in Automation Studio for detailed information about monitoring.**

7.5.5.2 Plausibility error[28)]

Plausibility errors (limit values, data types, variables/constants) that occur when using the function block are detected and reported by either the function block or compiler.

This is not possible in the event of connection errors, however.

The function block does not check for the following errors:

- Actual parameter values or constants are within their valid range but incorrect for the safety function being executed.
- Actual parameters have been connected incorrectly.
- Formal input/output parameters that should have been connected have not been connected.

> ## Danger!
> **Ensuring proper safety function connections (sub-application) is your responsibility as the user!**
>
> **Check the connections when validating the sub-application!**

7.5.5.3 Sporadically changing/toggling signal levels or impermissible signals[29)]

Sporadically changing or toggling signal levels on edge-controlled formal input parameters cause the function block to interpret this signal as an edge, which results in an unintended corresponding action being triggered in the function block if fault avoidance measures are not taken.

Sporadically changing or toggling signal levels on status-controlled input formal parameters will cause the signal to trigger an undesired corresponding action if error prevention measures are not taken.

Impermissible signals on input formal parameters can lead to an unexpected initial movement, non-execution of a requested action or an error message.

Possible causes of these signals:

28) This section applies to all function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF:
29) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR, SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR

- Programming error in the application program (user error)
- Cross fault, short circuit or open circuit (user error, wiring error)
- Error on the standard controller

To prevent this, the following measures can be taken depending on the safety function:

- Using signals from safe devices
- Implementing additional measures for preventing a hazard if using a signal from a standard controller (e.g. executing an additional function start after a safety function has been triggered or an error has been corrected)
- Line control on the safe control system
- Suitable cabling when using non-safe signals from the standard controller
- Verifying the source code in the application program and final validation of the safety functionality

These measures can also be combined to prevent errors.

It is important to note that a signal change detected on a status-controlled formal parameter will be output as a diagnostic code.

7.5.5.4 Simultaneous edge change[30)]

Make sure that the "Reset" formal parameter is only connected to a signal from a manual resetting device to reduce the risk of an unexpected initial movement. This signal is based on your risk analysis.

7.5.5.5 Machine/System startup without performing functional testing of protective equipment[31)]

Faulty protective equipment is only detected following functional testing. Functional testing is not supported by this function block. If additional measures are not taken, faulty protective equipment can result in errors.

> **Danger!**
>
> **You are responsible for the functional testing of protective equipment.**
> **You must therefore validate the protective equipment!**

Possible causes of faulty protective equipment:

- Faulty devices (hardware error)
- Cross fault, short circuit and open circuit (user error, wiring error)

30) This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_SafeMC_BR, SF_SafeMC_BR_V2, SF_SafeMC_BR_V3, SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR

31) This section applies to all function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF:

7.5.6 Input parameters

> **Information:**
>
> **For detailed information about individual safety functions, see "SafeMOTION user's manual / chapter "Safety technology" / Integrated safety functions"!**

7.5.6.1 General information about the "S_Request" inputs

The "S_Request" inputs are used to request the respective safety functions.

If a safety function should not be used in the safety application, then the respective input should not be connected.

> **Information:**
>
> **If a safety function is not used in the application, then the respective input must remain open.**

> **Danger!**
>
> **The safety functions that are used must be tested.**
> **A function is considered to be used if the respective input variable is connected!**

> **Information:**
>
> **At a minimum, the "Activate" and "S_AxisID" inputs must be connected. Otherwise, the SafeMOTION module will not be operated by the SafeLOGIC controller. As a result, the pulse disabling and motor holding brake outputs will be permanently set to 0 V, which means that the controller cannot be turned on.**

7.5.6.2 Activate

General function

- Enables the function block

Data type

- BOOL

Connection

- Constant or variable

Function description

This input parameter is used to activate the function block.

- When enabling or disabling safe devices, "Activate" must be linked to a variable that indicates the state (enabled or disabled) of the corresponding safe devices. This ensures that the function block does not output a triggered safety function as diagnostic information when a device is switched off.
- It is also possible to connect "Activate" to a constant (TRUE) in order to enable the function block.

TRUE

The function block is enabled.

FALSE

The function block is not enabled.
All binary output parameters are set to FALSE.
Sets the DiagCode diagnostic parameter to WORD#16#0000.

If you want to control function block diagnostics as needed in your diagnostic concept whenever error messages from safe devices and/or deactivated safe devices occur, connect "Activate" to a signal that indicates the status of the safe devices that are involved with the safety function supported by the function block. Form this signal using only safe devices whose I/O signals are connected to the function block via actual parameters. In this way, you prevent triggered safety functions from being reported by active safe devices. This measure is only used to control the diagnostic information from inactive safe devices in a defined manner.

7.5.6.3 S_RequestSTO

General function

- Selects/Deselects safety function Safe Torque Off, STO

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the STO safety function.

TRUE

The safety function is deselected. Safe pulse disabling is not active!

FALSE

The safety function is selected. Safe pulse disabling is active! Torque/Power are switched off on the drive.

Not connected

The safety function is deactivated.

Relevant configuration parameters

- None

7.5.6.4 S_RequestSTO1

General function

- Selects/Deselects safety function Safe Torque Off, One Channel, STO1

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the STO1 safety function.

TRUE

The safety function is deselected. Safe pulse disabling is not active!

FALSE

The safety function is selected. Depending on the configuration, the high-side or low-side of safe pulse disabling is active! Torque/Power are switched off on the drive.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Basic functions - STO1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>STO1 - Channel

(previously Channel selection for One Channel STO (STO1))</td><td>High-side/
Low-side</td><td>Selects the high-side or low-side IGBT in the STO1 function<table><tr><th>Value</th><th>Description</th></tr><tr><td>High-side</td><td>The high-side IGBTs are actuated with the function STO1.</td></tr><tr><td>Low-side</td><td>The low-side IGBTs are actuated with the function STO1.</td></tr></table></td><td>High-side</td><td>R 1.3</td></tr>
</table>

Table 441: SafeMOTION parameter group: Basic functions - STO1

7.5.6.5 S_RequestSBC

General function

- Selects/Deselects safety function Safe Brake Control, SBC

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SBC safety function.

TRUE

The safety function is deselected. The motor holding brake output is enabled and can be used by the standard application.

FALSE

The safety function is selected. The motor holding brake output is switched to 0 V!

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Basic functions - SBC (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBC - Enable delay time (previously *Delay time to start SBC (us)*)	[µs]	Delay time between the SBC request and activation of the safety function	0	R 1.3

Table 442: SafeMOTION parameter group: Basic functions - SBC

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

7.5.6.6 S_RequestSOS

General function

- Selects/Deselects safety function Safe Operating Stop, SOS

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SOS safety function.

TRUE

The safety function is deselected. Standstill tolerances are not being monitored.

FALSE

The safety function is selected. Standstill tolerances are being monitored.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 443: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ < EUS - Maximum speed to normalize speed range

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.5.6.7 S_RequestSS1

General function

- Selects/Deselects safety function Safe Stop 1, SS1

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SS1 safety function.

TRUE

The safety function is deselected. SS1 is not active!

FALSE

The safety function is selected. Safe pulse disabling is activated after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 444: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Basic functions - SS1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS1 - Ramp monitoring - Enable

(previously Rampmonitoring for SS1)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SS1 function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When transitioning to the safe state of the SS1 function, a deceleration ramp is monitored in addition to the configurable time.</td></tr>
<tr><td>Disabled</td><td>When transitioning to the safe state of the SS1 function, only a configurable time is monitored.</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS1</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 445: SafeMOTION parameter group: Basic functions - SS1

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr>
<tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr>
</table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 446: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

To use this function without safe encoder evaluation, "Ramp monitoring for SS1" and "Early Limit Monitoring" must be disabled.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.5.6.8 S_RequestSS2

General function

- Selects/Deselects safety function Safe Stop 2, SS2

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SS2 safety function.

TRUE

The safety function is deselected. SS2 is not active!

FALSE

The safety function is selected. Standstill monitoring is activated after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 447: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SS2 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS2 - Ramp monitoring - Enable

(previously Rampmonitoring for SS2)</td><td>Enabled/
Disabled</td><td>Activates ramp monitoring (in addition to time-based monitoring) when the SS2 function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When changing to the safe state of the SS2 function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr>
<tr><td>Disabled</td><td>When changing to the safe state of the SS2 function, only a configurable time is monitored</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>Ramp Monitoring Time for SS2 (us)</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS2</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 448: SafeMOTION parameter group: Speed functions - SS2

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 449: SafeMOTION parameter group: General settings - Standstill monitoring

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr>
<tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr>
</table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 450: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \le LIM_{SLS4} \le LIM_{SLS3} \le LIM_{SLS2} \le LIM_{SLS1} \le LIM_{SMS} <$ **EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.5.6.9 S_RequestSLS1

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 1

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS1 safety function.

TRUE

The safety function is deselected. SLS1 is not active!

FALSE

The safety function is selected. Speed limit 1 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 451: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLS - Ramp monitoring - Enable (previously *Rampmonitoring for SLS*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested **Value** / **Description** Enabled: When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time Disabled: When changing to the safe state of the SLS function, only a configurable time is monitored	Enabled	R 1.3
SLS1 - Speed limit (previously *Safe Speedlimit 1 for SLS (units/s)*)	[units/s]	Speed limit 1 for SLS (SLS1)	0	R 1.3
SLS1 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS1 (us)*)	[µs]	Deceleration ramp monitoring time for SLS1	0	R 1.3

Table 452: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** / **Description** Enabled: "Early Limit Monitoring" is active! Disabled: "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 453: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.5.6.10 S_RequestSLS2

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 2

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS2 safety function.

TRUE

The safety function is deselected. SLS2 is not active!

FALSE

The safety function is selected. Speed limit 2 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 454: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLS - Ramp monitoring - Enable (previously *Rampmonitoring for SLS*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested **Value** / **Description** Enabled: When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time Disabled: When changing to the safe state of the SLS function, only a configurable time is monitored	Enabled	R 1.3
SLS2 - Speed limit (previously *Safe Speedlimit 2 for SLS (units/s)*)	[units/s]	Speed limit 2 for SLS (SLS2)	0	R 1.3
SLS2 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS2 (us)*)	[µs]	Deceleration ramp monitoring time for SLS2	0	R 1.3

Table 455: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** / **Description** Enabled: "Early Limit Monitoring" is active! Disabled: "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 456: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$\mathbf{LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.5.6.11 S_RequestSLS3

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 3

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS3 safety function.

TRUE

The safety function is deselected. SLS3 is not active!

FALSE

The safety function is selected. Speed limit 3 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 457: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLS - Ramp monitoring - Enable (previously *Rampmonitoring for SLS*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested **Value** / **Description** Enabled: When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time Disabled: When changing to the safe state of the SLS function, only a configurable time is monitored	Enabled	R 1.3
SLS3 - Speed limit (previously *Safe Speedlimit 3 for SLS (units/s)*)	[units/s]	Speed limit 3 for SLS (SLS3)	0	R 1.3
SLS3 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS3 (us)*)	[µs]	Deceleration ramp monitoring time for SLS3	0	R 1.3

Table 458: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** / **Description** Enabled: "Early Limit Monitoring" is active! Disabled: "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 459: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.5.6.12 S_RequestSLS4

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 4

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS4 safety function.

TRUE

The safety function is deselected. SLS4 is not active!

FALSE

The safety function is selected. Speed limit 4 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 460: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SLS - Ramp monitoring - Enable

(previously Rampmonitoring for SLS)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr><tr><td>Disabled</td><td>When changing to the safe state of the SLS function, only a configurable time is monitored</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SLS4 - Speed limit

(previously Safe Speedlimit 4 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 2 for SLS (SLS2)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS4 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS4 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS2</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 461: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr><tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr></table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 462: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ < EUS - Maximum speed to normalize speed range

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

7.5.6.13 S_RequestSLI

General function

- Selects/Deselects safety function Safely Limited Increment, SLI

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLI safety function.

TRUE

The safety function is deselected. SLI is not active!

FALSE

The safety function is selected. A safe range of increments is monitored.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3

Table 463: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SLI (previously *Safely Limited Increment*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLI - Position limit (previously *Safe Increments (units)*)	[units]	Maximum movable increments when SLI is active	0	R 1.3
SLI - Disable delay time (previously *SLI Off Delay (µs)*)	[µs]	Switch off delay of SLI	0	R 1.3

Table 464: SafeMOTION parameter group: Advanced functions - SLI

Danger!

The maximum increment range must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

7.5.6.14 S_RequestSDIpos

General function

- Selects/Deselects safety function Safe Direction. Movement is allowed in the positive direction.

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the safety function SDI, movement is allowed in the positive direction of movement.

TRUE

The safety function is deselected. SDI is not active!

FALSE

The direction of movement is monitored after the delay time has expired. Movement is allowed in the positive direction.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 465: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*)	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 466: SafeMOTION parameter group: Advanced functions - SDI

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

7.5.6.15 S_RequestSDIneg

General function

- Selects/Deselects safety function Safe Direction. Movement is allowed in the negative direction.

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the safety function SDI, movement is allowed in the negative direction of movement.

TRUE

The safety function is deselected. SDI is not active!

FALSE

The direction of movement is monitored after the delay time has expired. Movement is allowed in the negative direction.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 467: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*)	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 468: SafeMOTION parameter group: Advanced functions - SDI

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

7.5.6.16 S_RequestSLA

General function

- Selects/Deselects safety function Safely Limited Acceleration, SLA

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLA safety function.

TRUE

The safety function is deselected. SLA is not active!

FALSE

The safety function is selected. A safe limit value for acceleration/deceleration is monitored with respect to the direction of movement.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 469: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with considera-tion for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Speed functions - SLA (previously *Safely Limited Acceleration*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLA - Acceleration limit in positive direction (previously *Safe acceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for acceleration in the positive direction of movement	0	R 1.9
SLA - Deceleration limit in positive direction (previously *Safe deceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for deceleration in the positive direction of movement	0	R 1.9
SLA - Acceleration limit in negative direction (previously *Safe acceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for acceleration in the negative direction of movement	0	R 1.9
SLA - Deceleration limit in negative direction (previously *Safe deceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for deceleration in the negative direction of movement	0	R 1.9
SLA - Enable delay time (previously *Delay time to start SLA (us)*)	[μs]	Delay time between the SLA request and activation of the safety function	0	R 1.9

Table 470: SafeMOTION parameter group: Speed functions - SLA

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

7.5.6.17 S_RequestSLP

General function

- Selects/Deselects safety function Safely Limited Position, SLP

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLP safety function.

TRUE

The safety function is deselected. SLP is not active!

FALSE

The configured position window will be safety-monitored after "Delay time to start SLP (us)".

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 471: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Absolute position functions - SMP/SLP (previously *Safety Position Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLP - Lower position limit (previously *Safe Lower Position Limit for SLP (units)*)	[units]	Lower position limit for the monitoring range	0	R 1.4
SLP - Upper position limit (previously *Safe Upper Position Limit for SLP (units)*)	[units]	Upper position limit for the monitoring range	0	R 1.4
SLP - Enable delay time (previously *Delay time to start SLP (us)*)	[µs]	Delay time between the SLP request and start of monitoring	0	R 1.4

Table 472: SafeMOTION parameter group: Absolute position functions - SMP/SLP

Danger!

The position limits being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement, a dangerous movement cannot occur in the event of a worst case scenario.

The dangerous movement must be determined by a risk analysis.

Information:

The following application rule must be observed:

$LIM_{SMP,NEG} \leq LIM_{SLP,NEG} \leq LIM_{SLP,POS} \leq LIM_{SMP,POS}$

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 473: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

The following application rule must be observed:
$LIM_{SMP,NEG} \leq LIM_{SLP,NEG} \leq LIM_{SLP,POS} \leq LIM_{SMP,POS}$
Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

Information:

Safe homing of the axis must be completed prior to using this safety function.
If a homing procedure is not completed successfully or the "S_SafePositionValid" status changes, then the request for the SLP safety function causes the module to switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state.
The drive loses all torque/power and coasts to a stop! In the event of an error, a synchronous axis will no longer be synchronous. The output of function block "S_NotErrFUNC" is reset.

7.5.6.18 S_SwitchHomingMode

General function

- This input is used by safety function "Remanent Safe Position" and enables a homing procedure that confirms the remanent safe position.

Data type

- SAFEBOOL

Connection

- Variable

Function description

This input parameter is used to switch between homing with RSP and the configured homing mode.

TRUE

When a homing command is given (i.e. positive edge of the "S_RequestHoming" input), then homing mode "Homing with RSP" is used.

FALSE

When a homing command is given (i.e. positive edge of the "S_RequestHoming" input), then the configured homing mode is used.

Relevant configuration parameters

Parameter	Unit	Description	Default value
Homing			
Remanent Safe Position	*Enabled/ Disabled*	*Selects whether or not to use the remanent safe position* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2!*	*Disabled*
Safety Standstill and Direction Tolerances			
Speed Tolerance	[units/s]	Speed tolerance for standstill monitoring	0
Position Tolerance	[units]	Position tolerance for standstill and direction monitoring	0

Table 474: RSP safety function - Parameters

7.5.6.19 S_RequestHoming

General function

- Selects/Deselects the "Safe Homing" safety function

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to start a "Safe Homing" procedure. A positive edge of the input starts the safety function.

Positive edge: Change from FALSE to TRUE

Starts "Safe Homing".

Negative edge: Change from TRUE to FALSE

If still active, the homing procedure will be terminated by the negative edge. This state transition has no effect if the homing procedure has already been completed.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Absolute position functions - Homing (previously *Homing*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Mode (previously *Mode*)	Direct / Reference switch / *Home Offset /* *Home offset with correction*	Selects the homing mode *Modes "Home offset" and "Home offset with correction" are only available for ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	Direct	R 1.4
Homing - Home position or home offset (previously *Home Position or Home Offset (units)*)	[units]	Home position or home offset	0	R 1.4
Homing - Enable RSP (Remanent safe position) *(previously Remanent safe position)*	*Enabled/* *Disabled*	*Selects whether or not to use the remanent safe position* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*Disabled*	R 1.9
Homing - Edge of reference switch (previously *Edge of reference switch*)	Positive / Negative	Selects the switching edge for the reference switch The switching edge for the reference switch input is positive if the logical state of the reference switch changes from SAFEFALSE to SAFETRUE in the positive direction of movement.	Positive	R 1.4
Homing - Trigger direction (previously *Trigger direction*)	Positive / Negative	Selects the trigger direction If the homing procedure requires a movement, then this parameter specifies the direction for evaluating the reference switch / reference pulse.	Positive	R 1.4

Table 475: SafeMOTION parameter group: Absolute position functions - Homing

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Enable reference pulse *(previously Reference pulse)*	*Enabled/ Disabled*	*Selects whether or not to use a reference pulse for homing* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*Disabled*	R 1.4
Homing - Blocking distance *(previously Blocking distance (% encoder reference system))*	*%*	*Distance within which evaluation of the reference pulse will be suppressed.* *This is calculated starting at the configured reference switch edge and indicated as a percentage of the encoder reference system.* *A single revolution is used as the encoder reference system for rotary encoders.* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*0*	R 1.4
Homing - Maximum trigger speed (previously *Max. trigger speed (units/s)*)	[units/s]	Maximum permissible speed for evaluating the reference switch / reference pulse	0	R 1.4
Homing - Monitoring time (previously *Homing Monitoring Time (µs)*)	[µs]	Monitoring time for the homing procedure	0	R 1.4

Table 475: SafeMOTION parameter group: Absolute position functions - Homing

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

The Safe Homing function is needed in order to implement the safety functions SLP and SMP and for using the safe position.
The SafePositionValid status bit will remain set to SAFEFALSE until safe homing has been performed!

7.5.6.20 S_ReferenceSwitch

General function

- Reference switch input for the "Safe Homing" safety function

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter serves as a reference switch input for the "Safe Homing" safety function and is only evaluated in the "Reference Switch" homing mode.
The status of a safe reference switch that was read into the safety application via a safe input module (X20SIxxxx), for example, should be linked to the input.

Not connected

The reference switch is not being used!

> **Information:**
>
> **If "Reference Switch" homing mode is configured and the reference switch input "S_ReferenceSwitch" is not wired on the function block, then the SafeMOTION module will switch to the FAIL SAFE state.**
> **The only way to exit the FAIL SAFE state is to complete a power off/on cycle and modify the safety application!**

> **Information:**
>
> **The "S_ReferenceSwitch" input is only evaluated in "Reference Switch" homing mode.**
> **The input is ignored in other homing modes!**

7.5.6.21 Reset

General function

- "Reset" input for acknowledging the FUNCTIONAL FAIL SAFE state or for putting the SafeMOTION module into OPERATIONAL state after STARTUP

Data type

- BOOL

Connection

- Variable

Function description

"Reset" input to acknowledge the FUNCTIONAL FAIL SAFE state

A positive edge triggers the reset function.

Depending on the configuration of parameter "Automatic Reset at Startup", a positive edge may be necessary to get the SafeMOTION module from state INIT to state OPERATIONAL after startup.

Relevant configuration parameters

Group: General settings - Automatic reset on start (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Used Starting in Safety Release</th></tr>
<tr><td>Automatic reset on start - Enable

(previously Automatic Reset at Startup)</td><td>Enabled/
Disabled</td><td>Activates automatic reset of the function block at startup<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>After startup, the module automatically changes to state OPERATIONAL (Startreset). The reset input does not have to be controlled!</td></tr><tr><td>Disabled</td><td>After startup, the module remains in an Init state until a positive edge of the reset input is detected.</td></tr></table></td><td>Disabled</td><td>R1.3</td></tr>
</table>

Table 476: SafeMOTION parameter group: General settings - Automatic reset on start

Danger!

Parameter "Automatic reset on start" enables/disables the restart interlock during startup or when a network failure occurs on a reestablished network connection.

If parameter "Automatic reset on start" is set to "Enabled", then the module automatically changes to state OPERATIONAL state (i.e. pulse disabling and the motor holding brake are enabled)!

Configuring an automatic restart can result in critical safety conditions. Take additional measures to ensure proper safety-related functionality.

7.5.6.22 S_AxisID

General function

- This input parameter assigns a real axis to the function block.

Data type

- SAFEINT

Connection

- Constant

Function description

The corresponding axis can be connected to the input in SafeDESIGNER using drag-and-drop.

> **Information:**
>
> **There is only permitted to be one combination of AxisID and the SF_SafeMC_BR or SF_SafeMC_BR_Vx function block in the safety application. Otherwise, it will not be possible to compile the safety application.**

7.5.7 Output parameters

Output parameters provide information about the state of the SafeMOTION module and the individual safety functions.

7.5.7.1 Ready

General function

- Message: Function block is enabled/disabled.

Data type

- BOOL

Connection

- Variable

Function description

This output parameter indicates whether the function block is enabled or not.

TRUE

The function block is enabled ("Activate" = TRUE). The output parameters indicate the current state of the safety function.

FALSE

The function block is not enabled ("Activate" = FALSE). The function block outputs are set to FALSE.

7.5.7.2 S_SafetyActiveSTO

General function

- Status information for safety function Safe Torque Off, STO

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the STO safety function

TRUE

The STO safety function is active and currently in its safe state.

FALSE

The STO safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.5.7.3 S_SafetyActiveSTO1

General function

- Status information for safety function Safe Torque Off, One Channel, STO1

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the STO1 safety function

TRUE

The STO1 safety function is active and currently in its safe state.

FALSE

The STO1 safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.5.7.4 S_SafetyActiveSBC

General function

- Status information for safety function Safe Brake Control, SBC

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SBC safety function

TRUE

The SBC safety function is active and currently in its safe state.

FALSE

The SBC safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.5.7.5 S_SafetyActiveSOS

General function

- Status information for safety function Safe Operating Stop, SOS

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SOS safety function

TRUE

The SOS safety function is active and currently in its safe state.

FALSE

The SOS safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.5.7.6 S_SafetyActiveSS1

General function

- Status information for safety function Safe Stop 1, SS1

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SS1 safety function

TRUE

The SS1 safety function is active and currently in its safe state.

FALSE

The SS1 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.5.7.7 S_SafetyActiveSS2

General function

- Status information for safety function Safe Stop 2, SS2

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SS2 safety function

TRUE

The SS2 safety function is active and currently in its safe state.

FALSE

The SS2 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.5.7.8 S_SafetyActiveSLS1

General function

- Status information for safety function Safely Limited Speed, Speed Limit 1

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS1 safety function

TRUE

The SLS1 safety function is active and currently in its safe state.

FALSE

The SLS1 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.5.7.9 S_SafetyActiveSLS2

General function

- Status information for safety function Safely Limited Speed, Speed Limit 2

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS2 safety function

TRUE

The SLS2 safety function is active and currently in its safe state.

FALSE

The SLS2 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.5.7.10 S_SafetyActiveSLS3

General function

- Status information for safety function Safely Limited Speed, Speed Limit 3

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS3 safety function

TRUE

The SLS3 safety function is active and currently in its safe state.

FALSE

The SLS3 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.5.7.11 S_SafetyActiveSLS4

General function

- Status information for safety function Safely Limited Speed, Speed Limit 4

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS4 safety function

TRUE

The SLS4 safety function is active and currently in its safe state.

FALSE

The SLS4 safety function is not requested, has not yet achieved its safe state, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.5.7.12 S_SafetyActiveSLI

General function

- Status information for safety function Safely Limited Increment

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLI safety function

TRUE

The SLI safety function is active and currently in its safe state.

FALSE

The SLI safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.5.7.13 S_SafetyActiveSDIpos

General function

- Status information for safety function Safe Direction. Movement is allowed in the positive direction.

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SDIpos safety function

TRUE

The SDIpos safety function is active and currently in its safe state.

FALSE

The SDIpos safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.5.7.14 S_SafetyActiveSDIneg

General function

- Status information for safety function Safe Direction. Movement is allowed in the negative direction.

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SDIneg safety function

TRUE

The SDIneg safety function is active and currently in its safe state.

FALSE

The SDIneg safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.5.7.15 S_SafetyActiveSLA

General function

- Status information for the "Safely Limited Acceleration" (SLA) safety function

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLA safety function

TRUE

The SLA safety function is active and currently in its safe state.

FALSE

The SLA safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.5.7.16 S_SafetyActiveSLP

General function

- Status information for safety function Safely Limited Position, SLP

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLP safety function

TRUE

The SLP safety function is active and currently in its safe state.

FALSE

The SLP safety function is not requested, the function or the SafeMOTION module is currently in an error state or the function block has not been enabled.

7.5.7.17 S_SafetyActiveSMP

General function

- Status information for safety function Safe Maximum Position, SMP

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SMP safety function

TRUE

The SMP safety function is active and currently in its safe state.

FALSE

Monitoring of the SMP position limits is not active. Monitoring is not active because the SafeMOTION module has not yet been homed, the function or the SafeMOTION module is in an error state or the function block has not been enabled.

7.5.7.18 S_ReqHominOK

General function

- Feedback for homing in SafeDESIGNER

Data type

- SAFEBOOL

Connection

- Variable

Function description

This status is set to provide feedback in the event that homing is requested when already in a homed state (**S_RequestHoming** and **S_SafePositionValid** are set).

TRUE

The input for homing is set (**S_RequestHoming** = SAFETRUE), and the safe position is valid (**S_SafePositionValid** = SAFETRUE).

FALSE

The input for homing is not set or the safe position is not valid.

7.5.7.19 S_SafePositionValid

General function

- Status information for the "Safe Homing" safety function and the safe position

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies whether or not safe homing of the axis has been completed and whether or not the position signal is valid.

TRUE

The axis has been safely homed, and the safe position is valid.

FALSE

The axis has not yet been safely homed, the axis encoder signal contains errors, the SafeMOTION module is in an error state or the function block has not been enabled.
The safe position is invalid!

> ## Danger!
>
> **The purpose of this signal is only to provide additional information.**
>
> **"S_SafePositionValid" does not represent the functional safe state of the SafeMOTION module!**

> ## Danger!
>
> **The value of the output parameter "S_SafePosition" is only valid if the output parameter "S_SafePositionValid" is SAFETRUE. Otherwise, it is invalid and is not permitted to be used further.**

7.5.7.20 S_SafetyActiveSDC

General function

- Information about the status of ramp monitoring

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the status of ramp monitoring.

TRUE

Ramp monitoring is active.

FALSE

Ramp monitoring is not active, the SafeMOTION module is currently in an error state or the function block has not been enabled.

> ## Danger!
> **This signal should only be used for status information.**

7.5.7.21 S_AllReqFuncActive

General function

- Information about the status of the requested safety functions

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies the status of the requested safety functions.

TRUE

All requested safety functions are currently in their functional safe state.

FALSE

One or more safety functions have not yet achieved their safe state, the SafeMOTION module is in an error state or the function block has not been enabled.

7.5.7.22 S_NotErrFUNC

General function

- Information about the error state of the safe SafeMOTION module

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies the error state of the SafeMOTION module.

TRUE

No error was found on the SafeMOTION module.

FALSE

An error was detected on the SafeMOTION module (e.g. a monitored limit was exceeded), or the function block has not been enabled.
In the event of an error, see the Safety Logger in Automation Studio for additional information about the error.
If the error is a functional error, then it can be acknowledged by changing the signal on input "Reset" from FALSE to TRUE (positive edge)!

> **Danger!**
>
> **The purpose of this signal is only to provide additional information. It only provides information in connection with the requested safety functions.**
> **"S_NotErrFUNC" does not represent the functional safe state of the SafeMOTION module!**

> **Danger!**
>
> **It is your responsibility to ensure that all necessary corrective measures are initiated after an error occurs since subsequent errors can result in a hazard!**

7.5.7.23 Error

General function

- Function block error message

Data type

- BOOL

Connection

- Variable

Function description

This formal parameter indicates a pending function block error message.

TRUE

The enabled function block detected an error. "DiagCode" indicates the error code.

FALSE

The function block is not enabled, or the enabled function block did not detect an error. "DiagCode" indicates the status.

> **Danger!**
>
> **It is your responsibility to ensure that all necessary corrective measures are initiated after an error occurs since subsequent errors can result in a hazard!**

In order to exit an error state ("Error" = TRUE), the signal on the "Reset" input must change from FALSE to TRUE (positive edge).

7.5.7.24 DiagCode

General function

- Function block diagnostic message

Data type

- WORD

Connection

- Variable

Function description

This output parameter is used to output diagnostic and status messages specific to the function block and make them available automatically to diagnostic tools.

These diagnostic tools cannot acknowledge diagnostic messages from function blocks. This is done exclusively in the **safety** application.

The function block indicates the presence of an error message on the "DiagCode" output via the "Error" output parameter.

Diagnostic code

The diagnostic code is specified as data type WORD. The values and meanings of these diagnostic codes are listed below.

In the event of status messages (0xxx$_{hex}$, 8xxx$_{hex}$), the function block sets "Error" to FALSE.

In the event of error messages (Cxxx$_{hex}$), the function block sets "Error" to TRUE.

7.5.7.25 Diagnostic codes

Code (hex)	State	Description	Possible workaround
0000	IDLE	The function block is not active.	Enable the function block by setting "Activate" to TRUE.
8001	INIT	The function block has been enabled and the SafeMOTION module is in the INIT state. The SafeMOTION module restart interlock is active.	Configure parameter "Startreset" accordingly or change to a positive edge on input "Reset".
8002	OPERATIONAL	The SafeMOTION module is in the OPERATIONAL state. No safety function is selected. The SMS speed limit is monitored according to the configuration.	No action required
8003	WAIT FOR CONFIRMATION	The SafeMOTION module is in the internal OPERATIONAL state. At least one safety function has been requested and at least one safety function has not yet achieved its functional safe state. None of the limits currently being monitored have been violated.	No action required
8000	SAFE STATE	All requested safety functions have achieved their functional safe state. None of the limits currently being monitored have been violated.	No action required
C000	FUNCTIONAL FAIL SAFE	An error occurred!	Check the Safety Logger in Automation Studio. It will provide detailed information about the current error. Depending on the type of error, check the standard and/or safety application. For functional errors, check the configuration of the SafeMOTION module or replace the faulty SafeMOTION module.

Table 477: SF_SafeMC_BR(_V2, _V3): Diagnostic codes

7.5.7.26 AxisStatus

General function

- Diagnostics message from the function block, representation of the axis status bits in a DWORD

Data type

- DWORD

Connection

- Variable

Function description

The **AxisStatus** output returns bit-coded information about the status of individual safety functions.
This information corresponds to a summary of the **S_xxx** outputs in a DWORD.
The individual bits have the following meaning:

Bit 0	**Bit 1**	**Bit 2**	**Bit 3**	**Bit 4**	**Bit 5**	**Bit 6**	**Bit 7**
Status STO	Status SBC	Status SOS	Status SS1	Status SS2	Status SLS1	Status SLS2	Status SLS3
Bit 8	**Bit 9**	**Bit 10**	**Bit 11**	**Bit 12**	**Bit 13**	**Bit 14**	**Bit 15**
Status SLS4	Status STO1	Status SDI pos	Status SLI	Status SDI neg	Status SLP	Status SMP	Status PositionValid
Bit 16	**Bit 17**	**Bit 18**	**Bit 19**	**Bit 20**	**Bit 21**	**Bit 22**	**Bit 23**
Status SLA	Status Setposition Alive Test	Status SFR	Status "All requested safety functions active"	Status SDC	Status Operational	Status Not Encoder Error	Status Not Functional Error

Table 478: SF_SafeMC_BR_V3: SafeMOTION module status bits

7.5.8 State machine

The state machine illustrated here is implemented on the SafeMOTION module.

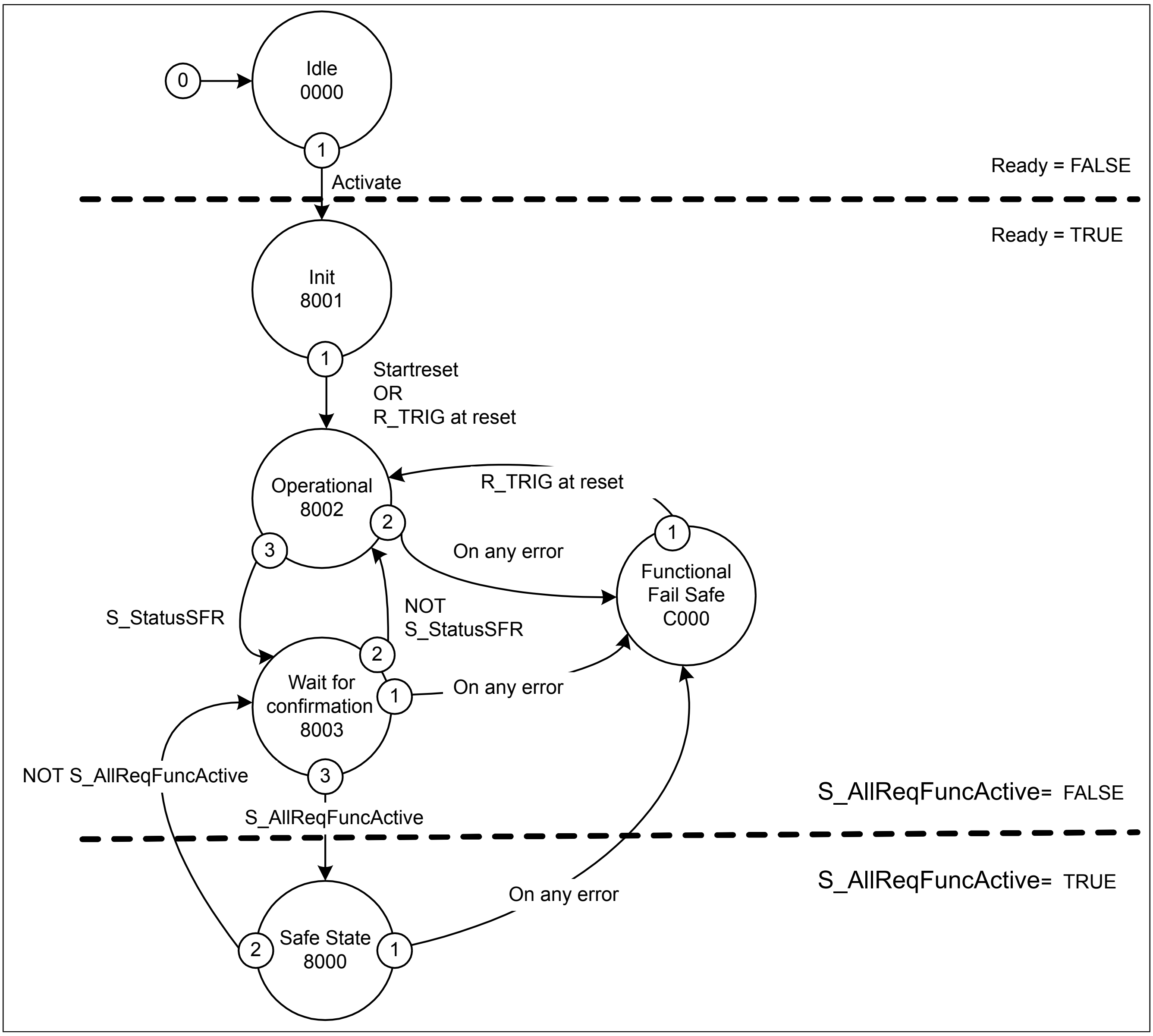


Figure 115: SF_SafeMC_BR(_V2): State machine

Individual states are reflected by the "DiagCode" output parameter. In this way, the function block provides a representation of the state machine on the SafeMOTION module.

7.5.9 Signal sequence diagram of the function block

A general signal sequence diagram of the function block cannot be specified since it depends on which safety functions are selected or deselected.

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

7.6 SF_SafeMC_Speed_BR

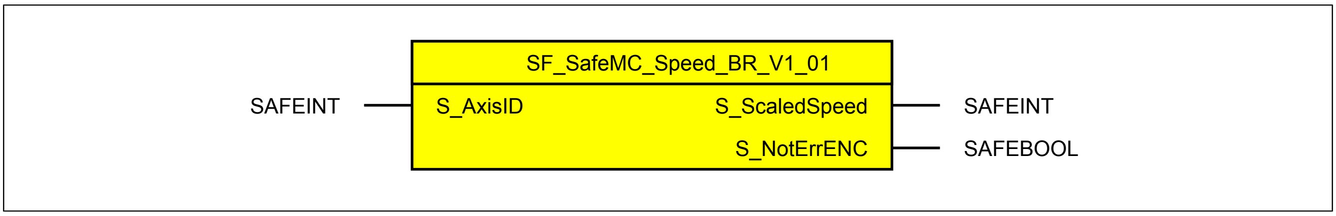


Figure 116: Function block SF_SafeMC_Speed_BR

7.6.1 Formal parameters of the function block

In the following, the term "variable" refers to both a variable as well as a graphic connection.

Name	Type	Connection	Signal type[1]	Initial value	Description / General function
S_AxisID	SAFEINT	Constant	State	-1	Assigns an axis to the function block

Table 479: SF_SafeMC_Speed_BR: Overview of input parameters

1) Evaluation of the input parameter signals in the function block. The signals must be controlled accordingly by the user.

Name	Type	Connection	Signal type[1]	Initial value	Description / General function
S_ScaledSpeed	SAFEINT	Variable	Value	-	Scaled safe speed
S_NotErrENC	SAFEBOOL	Variable	State	SAFEFALSE	No encoder error has been detected (=SAFETRUE), the signal S_ScaledSpeed is valid

Table 480: SF_SafeMC_Speed_BR: Overview of output parameters

1) Output of the output parameter signals. The signals must be evaluated and/or further processed accordingly by the user.

Type	Description	Size in bits	Format option
BOOL	Bit	1	Bit string
WORD	Word	16	Bit string
DINT	Double integer	32	Binary number, hexadecimal number, signed decimal number
SAFEBOOL	Bit	1	Bit string (signal source: safe device)
SAFEDWORD	Double word	32	Bit string (signal source: safe device)
SAFEDINT	Double integer	32	Binary number, hexadecimal number, signed decimal number (signal source: safe device)
SAFEINT	Integer	16	Binary number, hexadecimal number, signed decimal number (signal source: safe device)

Table 481: Format description of the data types

7.6.2 Function

The primary purpose of function block SF_SafeMC_Speed_BR is to establish a connection between the safe speed of an axis and the associated encoder error status. An assignment is then made to a defined safe axis.

The SF_SafeMC_Speed_BR function block can be used to process the current safe speed of an axis in the safety application.

Danger!

Make sure that the correct AxisID is always used on the input!
Each assignment must be validated separately.

To ensure valid evaluation of the speed signal, the corresponding encoder error status bit must also always be checked.
The speed signal itself is only considered valid if this output parameter is set to TRUE.

Danger!

If the speed signal is not validated, then an invalid speed value could be used in the safety application.
This can result in hazardous situations!

7.6.3 Fault avoidance

> ## Danger!
>
> **Validation**
>
> **Each safety function that is used must be validated separately.**
> **It is also necessary to test the entire safety application, including the interactions between individual functions.**

7.6.3.1 Plausibility errors

Plausibility errors (limit values, data types, variables/constants) that occur when using the function block are detected and reported by the function block or compiler.
This is not always possible in the event of connection errors, however.

It is not possible for the function block to check whether:

- Actual parameter values or constants within the valid range are in fact incorrect for the safety functions being executed. A static TRUE signal on the Reset input is detected by the function block and indicated as an error, however.
- Actual parameters have been connected incorrectly.
- I/O formal parameters were not connected inadvertently.

It is therefore important to note the following:

> ## Danger!
>
> **The user is responsible for the connection of the safety function (sub-application).**
>
> **The connection for validating the sub-application must be checked**

7.6.3.2 Validating the speed signal

In order for the speed signal to undergo a valid evaluation, the associated encoder error status bit must always be checked as well.
The speed signal itself is only considered valid if this output parameter is set to TRUE.

> ## Danger!
>
> **If the speed signal is not validated, then an invalid speed value could be used in the safety application. This can result in hazardous situations!**

7.6.3.3 Machine/System startup without performing functional testing of protective equipment

Faulty protective equipment is only detected following functional testing. Functional testing is not supported by this function block. If additional measures are not taken, faulty protective equipment can result in errors.

> ## Danger!
>
> **You are responsible for the functional testing of protective equipment.**
>
> **You must therefore validate the protective equipment!**

Possible causes of faulty protective equipment:

- Faulty devices (hardware error)
- Cross fault, short circuit and open circuit (user error, wiring error)

7.6.4 Input parameters

7.6.4.1 S_AxisID

General function

- This input parameter assigns a real axis to the function block.

Data type

- SAFEINT

Connection

- Constant

Function description

The corresponding axis can be connected to the input in SafeDESIGNER using drag-and-drop.

> ## Information:
> **The combination of AxisID and function block SF_SafeMC_Speed_BR is permitted to be used more than once in the safety application!**

7.6.5 Output parameters

7.6.5.1 S_ScaledSpeed

General function

- Indicates the current value of the scaled safe speed

Data type

- SAFEINT

Connection

- Variable

Function description

This output parameter indicates the current value of the scaled safe speed for a real axis.

> **Danger!**
>
> **The value of the "S_ScaledSpeed" output parameter is only valid if the "S_NotErrENC" output parameter is TRUE. Otherwise, it is invalid and is not permitted to be used further.**

7.6.5.2 S_NotErrENC

General function

- Information about the error state of the safe encoder signal

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the error state of the signal for a defined safe encoder.
If an encoder error is detected or the SafeMOTION module is in an error state, then the output is set to FALSE. This state is maintained until the error has been corrected.

TRUE

An error was not detected on the encoder signal. The value of the safe speed on the output parameter "S_ScaledSpeed" is valid.

FALSE

The encoder signal from a defined safe axis is faulty, or the axis itself is in an error state. For more information about the error, see the Safety Logger in Automation Studio.

Danger!

The purpose of this signal is only to provide additional information. It only provides information in connection with the requested safety functions.
"S_NotErrENC" does not represent the functional safe state of the SafeMOTION module!

Danger!

The value of the output parameter "S_ScaledSpeed" is only valid if the output parameter "S_NotErrENC" is TRUE. Otherwise, it is invalid and is not permitted to be used further.

7.6.6 Signal sequence diagram of the function block

A signal sequence diagram cannot be specified for this function block.

7.6.7 Application example

The following application example illustrates one possible comparison of the scaled safe speed with a permanent defined value in the safety application.

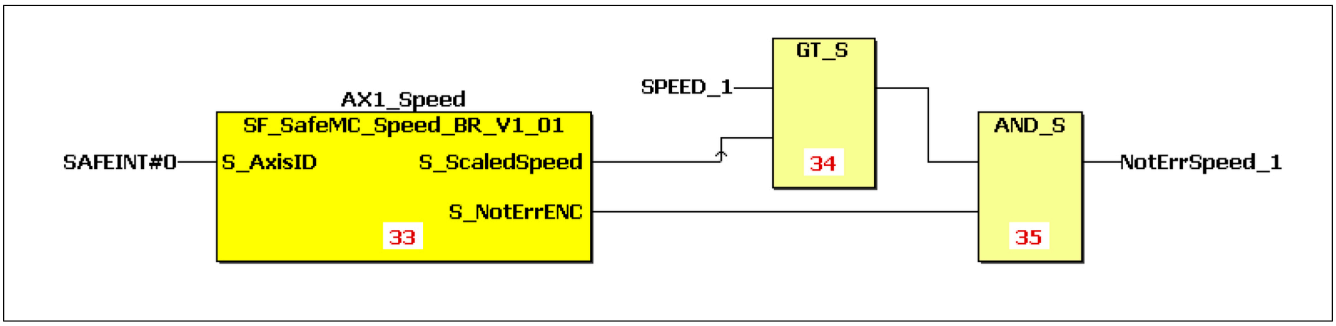


Figure 117: SF_SafeMC_Speed_BR: Evaluation of the scaled safe speed

7.7 SF_SafeMC_Position_BR

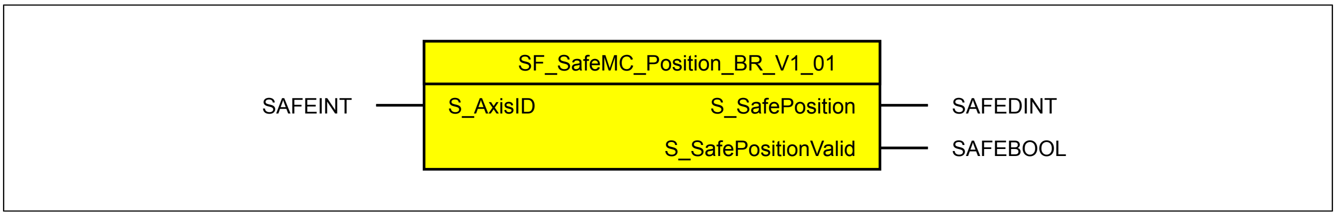


Figure 118: Function block SF_SafeMC_Position_BR

Information:

The SF_SafeMC_Position_BR_V1_01 function block can only be used with Safety Release 1.4.

If Safety Release 1.3 is being used, then SafeDESIGNER will return an error when compiling the safety application!

7.7.1 Formal parameters of the function block

In the following, the term "variable" refers to both a variable as well as a graphic connection.

Name	Type	Connection	Signal type 1)	Initial value	Description / General function
S_AxisID	SAFEINT	Constant	State	-1	Assigns an axis to the function block

Table 482: SF_SafeMC_Position_BR: Overview of input parameters

1) Evaluation of the input parameter signals in the function block. The signals must be controlled accordingly by the user.

Name	Type	Connection	Signal type 1)	Initial value	Description / General function
S_SafePosition	SAFEDINT	Variable	Value	-	Safe position in units
S_SafePositionValid	SAFEBOOL	Variable	State	SAFEFALSE	Specifies whether the safe position is valid (=SAFETRUE, homing procedure has completed successfully and there are no encoder errors)

Table 483: SF_SafeMC_Position_BR: Overview of output parameters

1) Output of the output parameter signals. The signals must be evaluated and/or further processed accordingly by the user.

Type	Description	Size in bits	Format option
BOOL	Bit	1	Bit string
WORD	Word	16	Bit string
DINT	Double integer	32	Binary number, hexadecimal number, signed decimal number
SAFEBOOL	Bit	1	Bit string (signal source: safe device)
SAFEDWORD	Double word	32	Bit string (signal source: safe device)
SAFEDINT	Double integer	32	Binary number, hexadecimal number, signed decimal number (signal source: safe device)
SAFEINT	Integer	16	Binary number, hexadecimal number, signed decimal number (signal source: safe device)

Table 484: Format description of the data types

7.7.2 Function

The primary purpose of function block SF_SafeMC_Position_BR is to establish a connection between the safe position of an axis and its associated status. An assignment is then made to a defined safe axis.

The SF_SafeMC_Position_BR function block can be used to process the current safe position of an axis in the safety application.

Danger!

Make sure that the correct AxisID is always used on the input!
Each assignment must be validated separately.

To ensure valid evaluation of the position signal, the corresponding status bit "S_PositionValid" must also always be checked.
The position itself is only considered homed and valid if this output parameter is set to SAFETRUE.

Danger!

If the position signal is not validated, then an invalid position could be used in the safety application. This can result in hazardous situations!

7.7.3 Fault avoidance

> **Danger!**
>
> **Validation**
>
> **Each safety function that is used must be validated separately.**
> **It is also necessary to test the entire safety application, including the interactions between individual functions.**

7.7.3.1 Plausibility errors

Plausibility errors (limit values, data types, variables/constants) that occur when using the function block are detected and reported by either the function block or compiler.

This is not possible in the event of connection errors, however.

The function block does not check for the following errors:

- Actual parameter values or constants are within their valid range but incorrect for the safety function being executed.
- Actual parameters have been connected incorrectly.
- Formal input/output parameters that should have been connected have not been connected.

> **Danger!**
>
> **Ensuring proper safety function connections (sub-application) is your responsibility as the user!**
>
> **Check the connections when validating the sub-application!**

7.7.3.2 Validating the position signal

To ensure valid evaluation of the position signal, the corresponding status bit **S_PositionValid** must also always be checked.
The position itself is only considered homed and valid if this output parameter is set to SAFETRUE.

> **Danger!**
>
> **If the position signal is not validated, then an invalid position could be used in the safety application. This can result in hazardous situations!**

7.7.3.3 Machine/System startup without performing functional testing of protective equipment

Faulty protective equipment is only detected following functional testing. Functional testing is not supported by this function block. If additional measures are not taken, faulty protective equipment can result in errors.

> **Danger!**
>
> **You are responsible for the functional testing of protective equipment.**
>
> **You must therefore validate the protective equipment!**

Possible causes of faulty protective equipment:

- Faulty devices (hardware error)
- Cross fault, short circuit and open circuit (user error, wiring error)

7.7.4 Input parameters

7.7.4.1 S_AxisID

General function

- This input parameter assigns a real axis to the function block.

Data type

- SAFEINT

Connection

- Constant

Function description

The corresponding axis can be connected to the input in SafeDESIGNER using drag-and-drop.

> **Information:**
>
> **The combination of AxisID and function block SF_SafeMC_Position_BR is permitted to be used more than once in the safety application!**

7.7.5 Output parameters

7.7.5.1 S_SafePosition

General function

- Indicates the current safe position in units

Data type

- SAFEDINT

Connection

- Variable

Function description

This output parameter indicates the current value of the safe position for a real axis in units.

Danger!

The value of the output parameter "S_SafePosition" is only valid if the output parameter "S_SafePositionValid" is SAFETRUE. Otherwise, it is invalid and is not permitted to be used further.

7.7.5.2 S_SafePositionValid

General function

- Status information for the "Safe Homing" safety function and the safe position

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies whether or not safe homing of the axis has been completed and whether or not the position signal is valid.

TRUE

The axis has been safely homed, and the safe position is valid.

FALSE

The axis has not yet been safely homed, the axis encoder signal contains errors, the SafeMOTION module is in an error state or the function block has not been enabled.
The safe position is invalid!

> **Danger!**
>
> **The purpose of this signal is only to provide additional information.**
>
> **"S_SafePositionValid" does not represent the functional safe state of the SafeMOTION module!**

> **Danger!**
>
> **The value of the output parameter "S_SafePosition" is only valid if the output parameter "S_SafePositionValid" is SAFETRUE. Otherwise, it is invalid and is not permitted to be used further.**

7.7.6 Signal sequence diagram of the function block

A signal sequence diagram cannot be specified for this function block.

7.7.7 Application example

The following application example illustrates one possible use of the Safe Position Monitor function on the SafeL-OGIC controller.

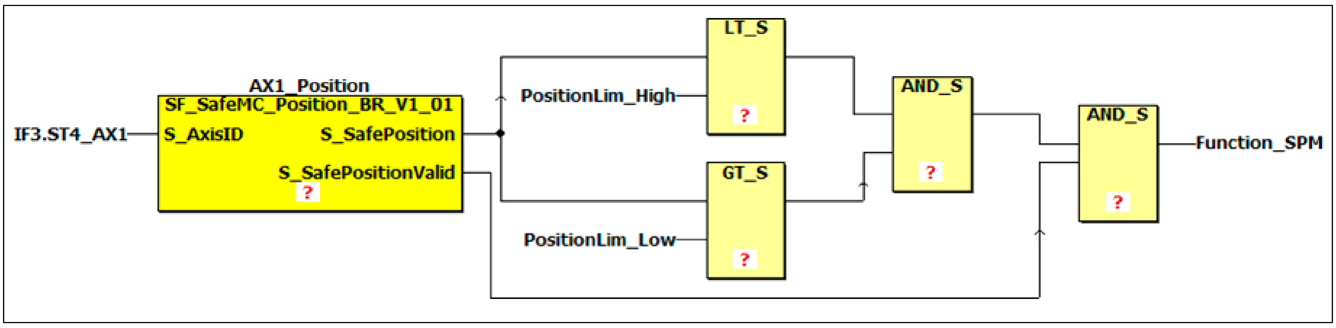


Figure 119: SF_SafeMC_Position_BR: The Safe Position Monitor function

7.8 SF_SafeMC_Position_BR_V2

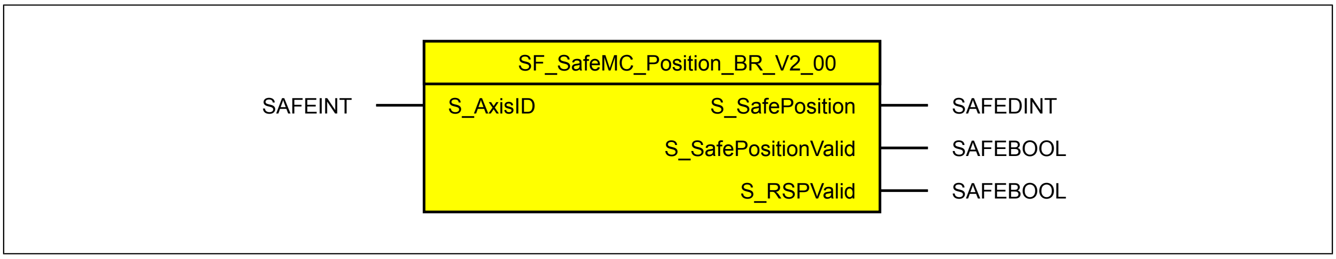


Figure 120: SF_SafeMC_Position_BR_V2 function block

Information:

The SF_SafeMC_Position_BR_V2 function block can only be used with Safety Release 1.9.

If a previous Safety Release is being used, then SafeDESIGNER will return an error when compiling the safety application!

7.8.1 Formal parameters of the function block

In the following, the term "variable" refers to both a variable as well as a graphic connection.

Name	Type	Connection	Signal type [1)]	Initial value	Description / General function
S_AxisID	SAFEINT	Constant	State	-1	Assigns an axis to the function block

Table 485: SF_SafeMC_Position_BR_V2: Overview of input parameters

1) Evaluation of the input parameter signals in the function block. The signals must be controlled accordingly by the user.

Name	Type	Connection	Signal type [1)]	Initial value	Description / General function
S_SafePosition	SAFEDINT	Variable	Value	-	Safe position in units
S_SafePositionValid	SAFEBOOL	Variable	State	SAFEFALSE	Specifies whether the safe position is valid (=SAFETRUE, homing procedure has completed successfully and there are no encoder errors)
S_RSPValid	SAFEBOOL	Variable	State	SAFEFALSE	Validates and stores the remanent safe position (TRUE = safe position is stored, power off for homing with RSP is now possible)

Table 486: SF_SafeMC_Position_BR_V2: Overview of output parameters

1) Output of the output parameter signals. The signals must be evaluated and/or further processed accordingly by the user.

Type	Description	Size in bits	Format option
BOOL	Bit	1	Bit string
WORD	Word	16	Bit string
DINT	Double integer	32	Binary number, hexadecimal number, signed decimal number
SAFEBOOL	Bit	1	Bit string (signal source: safe device)
SAFEDWORD	Double word	32	Bit string (signal source: safe device)
SAFEDINT	Double integer	32	Binary number, hexadecimal number, signed decimal number (signal source: safe device)
SAFEINT	Integer	16	Binary number, hexadecimal number, signed decimal number (signal source: safe device)

Table 487: Format description of the data types

7.8.2 Function

The primary purpose of function block SF_SafeMC_Position_BR_V2 is to establish a connection between the safe position of an axis and its associated status. An assignment is then made to a defined safe axis.

The SF_SafeMC_Position_BR_V2 function block can be used to process the current safe position of an axis in the safety application.

Danger!

Make sure that the correct AxisID is always used on the input!
Each assignment must be validated separately.

To ensure valid evaluation of the position signal, the corresponding status bit "S_PositionValid" must also always be checked.
The position itself is only considered homed and valid if this output parameter is set to SAFETRUE.

Danger!

If the position signal is not validated, then an invalid position could be used in the safety application. This can result in hazardous situations!

7.8.3 Fault avoidance

> ## Danger!
>
> **Validation**
>
> **Each safety function that is used must be validated separately.**
> **It is also necessary to test the entire safety application, including the interactions between individual functions.**

7.8.3.1 Plausibility error[32)]

Plausibility errors (limit values, data types, variables/constants) that occur when using the function block are detected and reported by either the function block or compiler.

This is not possible in the event of connection errors, however.

The function block does not check for the following errors:

- Actual parameter values or constants are within their valid range but incorrect for the safety function being executed.
- Actual parameters have been connected incorrectly.
- Formal input/output parameters that should have been connected have not been connected.

> ## Danger!
>
> **Ensuring proper safety function connections (sub-application) is your responsibility as the user!**
>
> **Check the connections when validating the sub-application!**

7.8.3.2 Validating the position signal

To ensure valid evaluation of the position signal, the corresponding status bit **S_PositionValid** must also always be checked.
The position itself is only considered homed and valid if this output parameter is set to SAFETRUE.

> ## Danger!
>
> **If the position signal is not validated, then an invalid position could be used in the safety application. This can result in hazardous situations!**

7.8.3.3 Machine/System startup without performing functional testing of protective equipment[33)]

Faulty protective equipment is only detected following functional testing. Functional testing is not supported by this function block. If additional measures are not taken, faulty protective equipment can result in errors.

> ## Danger!
>
> **You are responsible for the functional testing of protective equipment.**
> **You must therefore validate the protective equipment!**

Possible causes of faulty protective equipment:

- Faulty devices (hardware error)
- Cross fault, short circuit and open circuit (user error, wiring error)

32) This section applies to all function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF:
33) This section applies to all function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF:

7.8.4 Input parameters

7.8.4.1 S_AxisID

General function

- This input parameter assigns a real axis to the function block.

Data type

- SAFEINT

Connection

- Constant

Function description

The corresponding axis can be connected to the input in SafeDESIGNER using drag-and-drop.

> **Information:**
>
> **The combination of AxisID and function block SF_SafeMC_Position_BR is permitted to be used more than once in the safety application!**

7.8.5 Output parameters

7.8.5.1 S_SafePosition

General function

- Indicates the current safe position in units

Data type

- SAFEDINT

Connection

- Variable

Function description

This output parameter indicates the current value of the safe position for a real axis in units.

> ## Danger!
> **The value of the output parameter "S_SafePosition" is only valid if the output parameter "S_SafePositionValid" is SAFETRUE. Otherwise, it is invalid and is not permitted to be used further.**

7.8.5.2 S_SafePositionValid

General function

- Status information for the "Safe Homing" safety function and the safe position

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies whether or not safe homing of the axis has been completed and whether or not the position signal is valid.

TRUE

The axis has been safely homed, and the safe position is valid.

FALSE

The axis has not yet been safely homed, the axis encoder signal contains errors, the SafeMOTION module is in an error state or the function block has not been enabled.
The safe position is invalid!

> ## Danger!
>
> **The purpose of this signal is only to provide additional information.**
>
> **"S_SafePositionValid" does not represent the functional safe state of the SafeMOTION module!**

> ## Danger!
>
> **The value of the output parameter "S_SafePosition" is only valid if the output parameter "S_SafePositionValid" is SAFETRUE. Otherwise, it is invalid and is not permitted to be used further.**

7.8.5.3 S_RSPValid

General function

- Status information for the "Remanent safe position" safety function

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the following:

- The current safe position has been homed, validated and saved.
- Changes to the safe position are prevented by the active STO and SOS safety functions.
- Powering off the module does not result in loss of the safe remanent position.

TRUE

The safe position has been saved successfully. Power off for homing with RSP is possible in this state.

FALSE

One or more of the following is true:

- The axis was not successfully homed. (The state of "S_SafePositionValid" is not TRUE.)
- The STO safety function is not selected/active.
- The SOS safety function is not selected/active.

7.8.6 Signal sequence diagram of the function block

A signal sequence diagram cannot be specified for this function block.

7.8.7 Application example

The following application example illustrates one possible use of the Safe Position Monitor function on the SafeLOGIC controller.

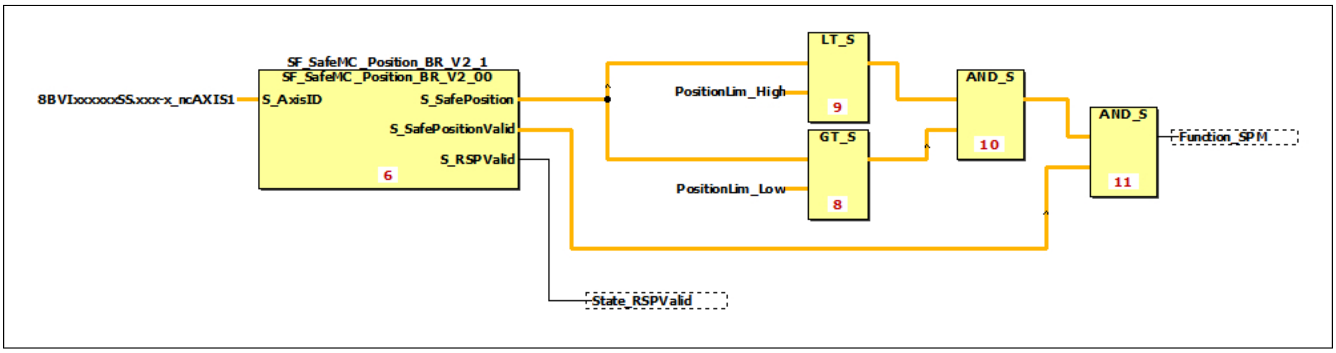


Figure 121: SF_SafeMC_Position_BR_V2: The "Safe Position Monitor" function

7.9 SF_SafeMC_SBT_BR

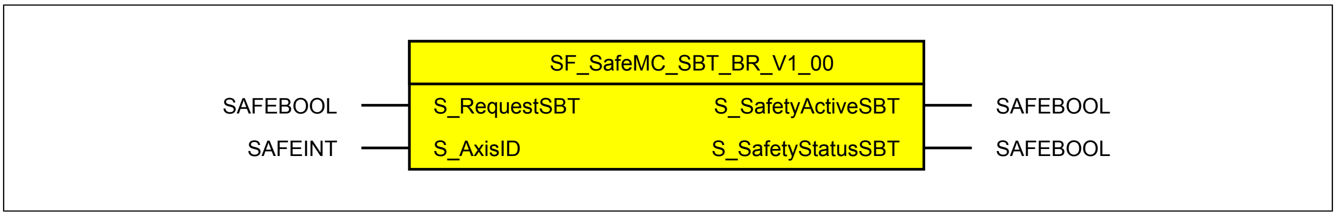


Figure 122: SF_SafeMC_SBT_BR function block

7.9.1 Formal parameters of the function block

In the following, the term "variable" refers to both a variable as well as a graphic connection.

Name	Type	Connection	Signal type	Initial value	Description / General function
S_RequestSBT	SAFEBOOL	Variable/Constant	Edge	SAFEFALSE	Requests the SBT safety function on a negative edge
S_AxisID	SAFEINT	Constant	State	-1	Assigns an axis to the function block

Table 488: SF_SafeMC_SBT_BR: Overview of input parameters

Name	Type	Connection	Signal type	Initial value	Description / General function
S_SafetyActiveSBT	SAFEBOOL	Variable	State	SAFEFALSE	SBT safety function active (= SAFETRUE)
S_SafetyStatusSBT	SAFEBOOL	Variable	State	SAFEFALSE	Safety function completed successfully, valid test status (= SAFETRUE)

Table 489: SF_SafeMC_SBT_BR: Overview of output parameters

Type	Description	Size in bits	Format option
BOOL	Bit	1	Bit string
WORD	Word	16	Bit string
DINT	Double integer	32	Binary number, hexadecimal number, signed decimal number
SAFEBOOL	Bit	1	Bit string (signal source: safe device)
SAFEDWORD	Double word	32	Bit string (signal source: safe device)
SAFEDINT	Double integer	32	Binary number, hexadecimal number, signed decimal number (signal source: safe device)
SAFEINT	Integer	16	Binary number, hexadecimal number, signed decimal number (signal source: safe device)

Table 490: Format description of the data types

7.9.2 Safe Brake Test (SBT)

See ACOPOSmulti SafeMOTION user's manual / Safety technology / Integrated safety functions / Safe Brake Test (SBT).

7.9.3 Fault avoidance

Danger!

Validation

Each safety function that is used must be validated separately.
It is also necessary to test the entire safety application, including the interactions between individual functions.

7.9.3.1 Plausibility error[34)]

Plausibility errors (limit values, data types, variables/constants) that occur when using the function block are detected and reported by either the function block or compiler.

This is not possible in the event of connection errors, however.

The function block does not check for the following errors:

- Actual parameter values or constants are within their valid range but incorrect for the safety function being executed.
- Actual parameters have been connected incorrectly.
- Formal input/output parameters that should have been connected have not been connected.

Danger!

Ensuring proper safety function connections (sub-application) is your responsibility as the user!

Check the connections when validating the sub-application!

7.9.3.2 Sporadically changing/toggling signal levels or impermissible signals

Sporadically changing/toggling signal levels or impermissible signals on

- edge-controlled formal input parameters cause the function block to interpret the signal as an edge, which results in an unintended action being triggered in the function block if error prevention measures are not in place.

Possible causes of these signals:

- Programming error in the application program (user error)
- Cross fault, short circuit or open circuit (user error, wiring error)
- Error in the standard controller

To prevent this, the following measures can be taken depending on the safety function:

- Use of safe device signals
- Implementing additional measures for preventing a hazard if using a signal from the standard controller (e.g. executing an additional function start after resetting a triggered safety function or correcting an error)
- Line control on the safe control system.
- Suitable wiring when using non-safe signals from the standard controller
- Verifying the source code in the application program and final validation of the safety functionality

The specified measures can also be combined to reliably avoid errors.

It is important to note that a signal change detected on a status-controlled formal parameter will be output as a diagnostic code.

[34)] This section applies to all function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF:

7.9.4 Input parameters

7.9.4.1 S_RequestSBT

General function

- Selects/Deselects safety function Safe Brake Test, SBT

Data type

- SAFEBOOL

Connection

- Variable

Function description

This input parameter is used to start the SBT safety function.

Negative edge

A negative edge or state transition from SafeTRUE to SafeFALSE on input parameter "S_RequestSBT" starts the Safe Brake Test, SBT safety function.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Parameter	Unit	Description	Default value
Safety Additional Parameters			
Delay time to start SBT (us)	[µs]	Delay time between the SBT request and activation of the safety function	0
Safe Brake Test			
Safe Brake Test interval (s)	[s]	Retry interval for the safe brake test	28800
Safe Brake Test threshold (uA)	[µA]	Threshold value for the stator current that must be exceeded during the brake test	0
Safe Brake Test external load (uA)	[µA]	External load	0
Safe Brake Test maximum torque duration (us)	[µs]	Duration of the test for which the maximum torque must be present	0
Safe Brake Test position tolerance (units)	[units]	Position tolerance	0

Table 491: SBT safety function - Parameters

7.9.4.2 S_AxisID

General function

- This input parameter assigns a real axis to the function block.

Data type

- SAFEINT

Connection

- Constant

Function description

The corresponding axis can be connected to the input in SafeDESIGNER using drag-and-drop.

> ## Information:
> **There is only permitted to be one combination of AxisID and SF_SafeMC_SBT_BR in the safety application. Otherwise, it will not be possible to compile the safety application.**

7.9.5 Output parameters

7.9.5.1 S_SafetyActiveSBT

General function

- Status information for safety function Safe Brake Test, SBT

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SBT safety function

TRUE

The SBT safety function is being executed.

FALSE

The SBT safety function has not been requested.

7.9.5.2 S_SafetyStatusSBT

General function

- Status information for testing the holding brake with Safe Brake Test, SBT

Data type

- SAFEBOOL

Connection

- Variable

Function description

Returns the status of the holding brake test with Safe Brake Test, SBT

TRUE

The SBT safety function has been executed. The status of the testing is valid.

FALSE

The SBT safety function has not been executed. The status of the testing is invalid or expired.

7.9.6 Signal sequence diagram

Signal sequence diagram for the Safe Brake Test, SBT safety function (see "ACOPOSmulti SafeMOTION user's manual / Safety technology / Integrated safety functions / Safe Brake Test, SBT").

7.10 Exceeding monitored limits[35)]

The SafeMOTION module monitors configurable limits. The drive itself, however, is controlled by the standard application on the standard PLC.

To prevent a violation of a monitored limit, the following points must be observed:

- The movement of the drive must be adapted to the requested safety function and initiated on time.
- The monitored limits must match the calculated limits and movement limitations. Make sure that the different configurations of the unit system match in the safety application and in the standard application!

> **Danger!**
>
> **Any violation of a monitored limit will cause the module to switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state.**
>
> **Function block output "S_Status_NotErrFUNC" is reset, and the drive loses all torque/power and coasts to a stop.**
>
> **Depending on the configuration, the motor holding brake will also be switched to 0 V.**
>
> **In the event of an error, a synchronous axis will no longer be synchronous.**
>
> **Check the Safety Logger in Automation Studio for detailed information about monitoring.**

[35)] This section applies to the following function blocks in libraries PLCopen_MOTION_SF_2 and openSAFETY_BuR_Motion_SF: SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR, SF_oS_MOTION_AbsPos_BR, SF_oS_MOTION_BR.

8 openSAFETY_BuR_Motion_SF

Library openSAFETY_BuR_Motion_SF is the vendor-specific implementation of the openSAFETY Safe Movement profile specification for B&R.

All function blocks are equipped with the general connections defined in the PLCopen specification ("Activate", "Ready", "Error", "DiagCode").
Input "Activate" solely affects the functionality of the function block; outputs "Ready", "Error" and "DiagCode" are exclusively generated by the function block.

- Input "Activate": Enables the function block
- Output "Ready": Function block is being processed
- Output "Error": Boolean error message
- Output "DiagCode": Error code

Connection "S_AxisID" references the axis to be used. This axis ID is made available as a constant by SafeDESIGNER.

All other connections correspond to the requirements or the status of the safety functions made available by the safe axis.

Information:

Library openSAFETY_BuR_Motion_SF can only be used to control ACOPOS P3 SafeMOTION servo drives.

Information:

It is mandatory for function block SF_oS_MOTION_Basic_BR to be applied to each axis being used in the safety application. Otherwise, the internal state machine of the axis remains in state IDLE, and pulse disabling and the holding brake output cannot be enabled.
Alternatively, function block SF_oS_MOTION_BR can be used; it represents the combination of all available function sets.

Information:

Only the inputs of safety functions that are actually used in the safety application are permitted to be linked.
Linking an input of a safety function to SAFETRUE or SAFEFALSE is not permitted since this identifies the function as being used but does not allow it to be tested!

8.1 Overview

Overview of function blocks in library openSAFETY_BuR_Motion_SF.

Function block	Description
SF_oS_MOTION_Basic_BR	Interface to the Basic Set of the openSAFETY Safe Motion profile
SF_oS_MOTION_Speed_BR	Interface to the Speed Extension Set of the openSAFETY Motion profile
SF_oS_MOTION_Advanced_BR	Interface to the Advanced Extension Set of the openSAFETY Motion profile
SF_oS_MOTION_AbsPos_BR	Interface to the Encoder Basic Set of the openSAFETY Motion profile
SF_oS_MOTION_BR	Combination of function blocks SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR and SF_oS_MOTION_AbsPos_BR
SF_oS_MOTION_ScaledSpeed_BR	Links the safe speed of an axis and the associated status of the encoder error
SF_oS_MOTION_Position_BR	Links the safe position of an axis and the associated status

8.2 System requirements

Library "openSAFETY_BuR_Motion_SF" is part of SafeDESIGNER and only permitted to be used there.

The following requirements must be met in order to use library "openSAFETY_BuR_Motion_SF":

- SafeDESIGNER: 4.2.2 or later
- Automation Studio: 4.2.5 or later
- SafeLOGIC: Safety Release 1.10 or later
- SafeLOGIC-X: Safety Release 1.10 and later, X20(c)SLX910 supports maximum 1 axis
- ACP10 motion software: 3.15.0 or later
- The safety functions being used must be unlocked using a Technology Guard.

8.3 Term definitions

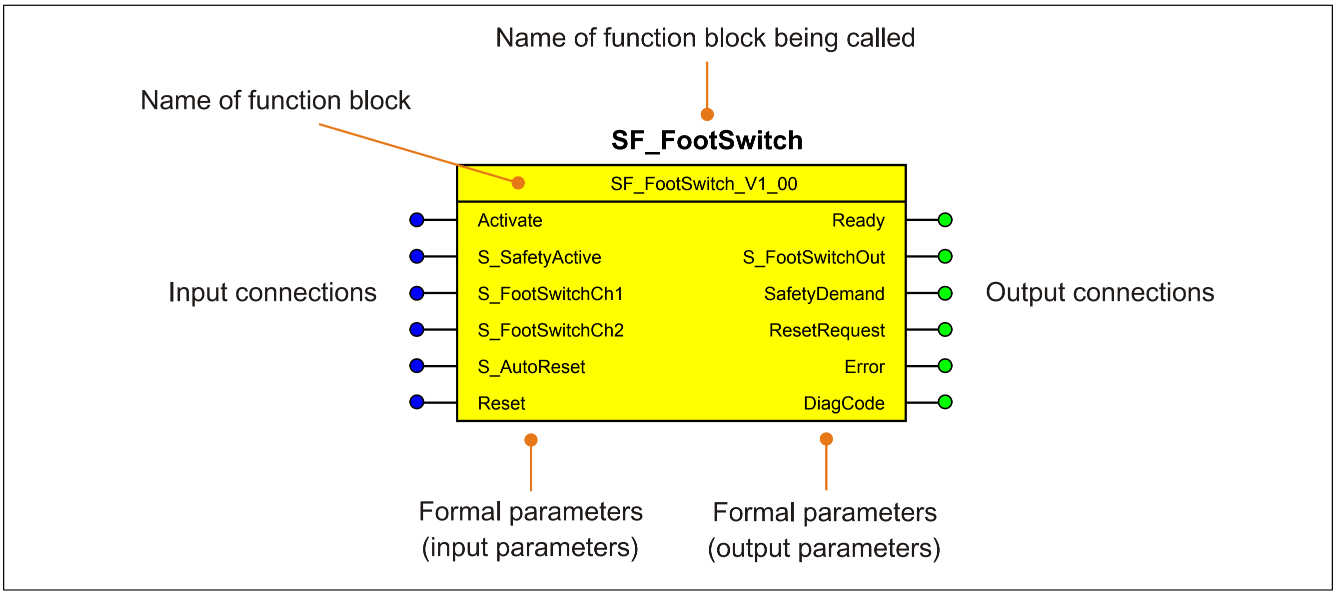


Figure 123: Components of a function block

When calling a function block, the inputs supply the input parameters with the current values of the variables or constants.
The output parameters supply the outputs with the associated values.

Inputs and outputs do not need to have the same name as the associated formal parameters, but they must be of the same data type. A difference in data type between formal parameters and inputs/outputs is reported as an error after compilation.

The name of a function block is composed of the function itself (e.g. "SF_FootSwitch", SF = safety function) and its version (Vx_yz). The format used to represent the version number in this document, Vx_yz, is a placeholder. For the actual version, see the function block being used.

8.4 SF_oS_MOTION_Basic_BR

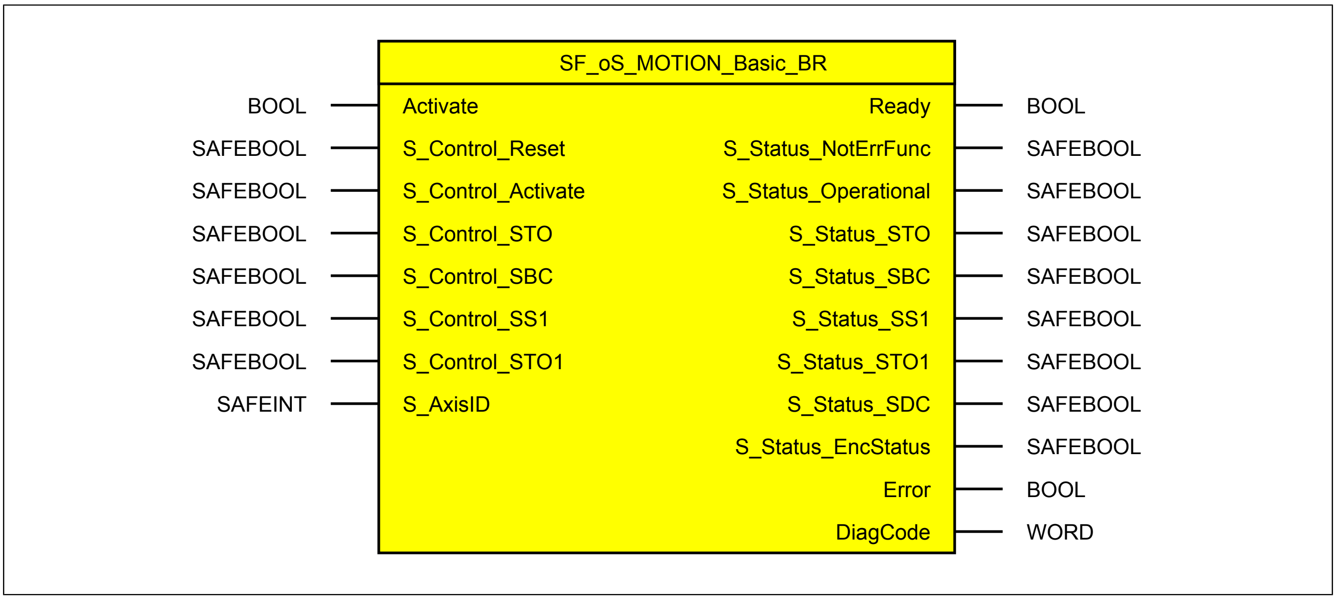


Figure 124: Function block SF_oS_MOTION_Basic_BR

Information:

Library openSAFETY_BuR_Motion_SF can only be used to control ACOPOS P3 SafeMOTION servo drives.

8.4.1 Formal parameters of the function block

In the following, the term "variable" refers to both a variable as well as a graphic connection.

Name	Type	Connection	Signal type [1)]	Initial value	Description / General function
Activate	BOOL	Variable/ Constant	State	FALSE	Enables the function block (= TRUE) Input **Activate** according to the PLCopen standard
S_Control_Reset	SAFEBOOL	Variable/ Constant	Edge	SAFEFALSE	Resets error messages and the SafeMOTION module after the cause of the error has been removed
S_Control_Activate	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SAFETRUE: Starts the state machine of the safe axis, safety functions can be enabled. SAFEFALSE: Sets the state machine of the safe axis to state IDLE
S_Control_STO	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function "Safe Torque Off" (STO). SAFEFALSE: Safety function requested
S_Control_SBC	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function "Safe Brake Control" (SBC). SAFEFALSE: Safety function requested
S_Control_SS1	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function "Safe Stop 1" (SS1). SAFEFALSE: Safety function requested
S_Control_STO1	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function "Safe Torque Off, One Channel" (STO1). SAFEFALSE: Safety function requested
S_AxisID	SAFEINT	Constant	State	-1	Assigns an axis to the function block

Table 492: SF_oS_MOTION_Basic_BR: Overview of input parameters

1) Evaluation of the input parameter signals in the function block. The signals must be controlled accordingly by the user.

Name	Type	Connection	Signal type [1)]	Initial value	Description / General function
Ready	BOOL	Variable	State	FALSE	Indicates that the function block is enabled Output **Ready** according to the PLCopen standard
S_Status_NotErrFunc	SAFEBOOL	Variable	State	SAFEFALSE	SafeMOTION module not in state FUNCTIONAL FAIL SAFE (i.e. SAFETRUE)
S_Status_Operational	SAFEBOOL	Variable	State	SAFEFALSE	Status of the state machine of the safe axis SAFEFALSE: State machine not in state OPERATIONAL SAFETRUE: State machine in state OPERATIONAL
S_Status_STO	SAFEBOOL	Variable	State	SAFEFALSE	Safety function "Safe Torque Off" (STO) is active (i.e. SAFETRUE).
S_Status_SBC	SAFEBOOL	Variable	State	SAFEFALSE	Safety function "Safe Brake Control" (SBC) is active (i.e. SAFETRUE).
S_Status_SS1	SAFEBOOL	Variable	State	SAFEFALSE	Safety function "Safe Stop 1" (SS1) is active, deceleration monitoring is completed, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_STO1	SAFEBOOL	Variable	State	SAFEFALSE	Safety function "Safe Torque Off, One Channel" (STO1) is active (i.e. SAFETRUE).
S_Status_SDC	SAFEBOOL	Variable	State	SAFEFALSE	Deceleration monitoring is active (i.e. SAFETRUE).
S_Status_EncStatus	SAFEBOOL	Variable	State	SAFEFALSE	No encoder error has been detected (i.e. SAFETRUE), signal S_ScaledSpeed is valid.
Error	BOOL	Variable	State	FALSE	Function block error message
DiagCode	WORD	Variable	State	16#0000	Function block diagnostic message

Table 493: SF_oS_MOTION_Basic_BR: Overview of output parameters

1) Output of the output parameter signals. The signals must be evaluated and/or further processed accordingly by the user.

Type	Description	Size in bits	Format option
BOOL	Bit	1	Bit string
WORD	Word	16	Bit string
DINT	Double integer	32	Binary number, hexadecimal number, signed decimal number
SAFEBOOL	Bit	1	Bit string (signal source: safe device)
SAFEDWORD	Double word	32	Bit string (signal source: safe device)
SAFEDINT	Double integer	32	Binary number, hexadecimal number, signed decimal number (signal source: safe device)
SAFEINT	Integer	16	Binary number, hexadecimal number, signed decimal number (signal source: safe device)

Table 494: Format description of the data types

You have the option of linking a safe signal with a non-safe input parameter. To do so, use a function block for type conversion.

Caution!

You are responsible for any conversion of a non-safe input parameter to a safe signal.

8.4.2 SafeMOTION module parameters

Group: General settings - Automatic reset on start (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Used Starting in Safety Release</th></tr>
<tr><td>Automatic reset on start - Enable

(previously Automatic Reset at Startup)</td><td>Enabled/ Disabled</td><td>Activates automatic reset of the function block at startup<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>After startup, the module automatically changes to state OPERATIONAL (Startreset). The reset input does not have to be controlled!</td></tr><tr><td>Disabled</td><td>After startup, the module remains in an Init state until a positive edge of the reset input is detected.</td></tr></table></td><td>Disabled</td><td>R1.3</td></tr>
</table>

Table 495: SafeMOTION parameter group: General settings - Automatic reset on start

Group: General settings - Encoder Unit System (previously *Encoder Unit System*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>EUS - Count of physical reference system

(previously Count of physical reference system)</td><td>-</td><td>Rotary encoder unit scale: X revolutions
Linear encoder unit scale: X reference lengths (reference length = length of the physical reference system)

Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration).
For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.</td><td>1</td><td>R 1.4</td></tr>
<tr><td>EUS - Units per count of physical reference system

(previously Units per count of physical reference system [units])</td><td>[units]</td><td>Rotary encoder unit scale: Units per x revolutions
Linear encoder unit scale: Units per x reference lengths

Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration).
For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.</td><td>1000</td><td>R 1.4</td></tr>
<tr><td>EUS - Counting direction

(previously Counting direction)</td><td>Standard / Inverse</td><td>Counting direction of the position or speed<table><tr><th>Value</th><th>Description</th></tr><tr><td>Default</td><td>Encoder counting direction is equal to the counting direction of the unit system.</td></tr><tr><td>Inverse</td><td>Encoder counting direction is negative to the counting direction of the unit system.</td></tr></table></td><td>Default</td><td>R 1.3</td></tr>
<tr><td>EUS - Length of physical reference system for linear encoder

(previously Length of physical reference system for linear encoder (nm))</td><td>[nm]</td><td>For linear measurement systems, the length of a physical reference system is defined here.
This value is not used for rotary encoders, where the reference system is a single revolution.</td><td>1000000000</td><td>R 1.4</td></tr>
<tr><td>EUS - Maximum speed to normalize speed range

(previously Maximum speed to normalize the speed range (units/s))</td><td>[units/s]</td><td>Maximum speed to which the displayed speed should be normalized</td><td>32767</td><td>R 1.3</td></tr>
<tr><td>EUS - Encoder acceleration limit

(previously Maximum acceleration (rad/s² or mm/s²))</td><td>[rad/s²] or [mm/s²]</td><td>Maximum permissible encoder acceleration</td><td>100000</td><td>R 1.4</td></tr>
</table>

Table 496: SafeMOTION parameter group: General settings - Encoder Unit System

Group: General settings - Encoder monitoring (previously *Encoder Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Encoder monitoring - Safe Encoder Mounting (Hardware upgrade 1.10.3.x and later)</td><td>From motor data record / Approved by user</td><td>Status of the proof of fatigue strength of the encoder mounting<table><tr><th>Value</th><th>Description</th></tr><tr><td>From motor data record</td><td>The status of the encoder mounting is determined using the motor data record.</td></tr><tr><td>Approved by user</td><td>The user confirms safe encoder mounting / no mounting information available in the motor data record.</td></tr></table></td><td>From motor data record</td><td>R1.10</td></tr>
<tr><td>Encoder monitoring - Position error monitoring - Enable

(previously Encoder Position monitoring)</td><td>Enabled/ Disabled</td><td>Enables/Disables monitoring of the position lag error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error monitoring - Enable

(previously Encoder Speed monitoring)</td><td>Enabled/ Disabled</td><td>Activates/Deactivates monitoring of the speed error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position setpoint alive testing (SPA) - Enable

(previously Set position alive testing)</td><td>Enabled/ Disabled</td><td>Activates/Deactivates the monitor that detects whether the position setpoint generated on the SafeMOTION module is frozen.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Disabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position error tolerance

(previously Encoder monitoring Position tolerance (units))</td><td>[units]</td><td>Position lag error tolerance for shaft breakage monitoring</td><td>0</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error tolerance

(previously Encoder monitoring Speed tolerance (units/s))</td><td>[units/s]</td><td>Speed error tolerance for encoder monitoring</td><td>0</td><td>R1.3</td></tr>
</table>

Table 497: SafeMOTION parameter group: General settings - Encoder monitoring

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 498: SafeMOTION parameter group: General settings - Standstill monitoring

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/ Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr><tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr></table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 499: SafeMOTION parameter group: General settings - Early limit monitoring

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[μs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 500: SafeMOTION parameter group: General settings - Ramp monitoring

Group: Basic functions - STO1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>STO1 - Channel

(previously Channel selection for One Channel STO (STO1))</td><td>High-side/
Low-side</td><td>Selects the high-side or low-side IGBT in the STO1 function<table><tr><th>Value</th><th>Description</th></tr><tr><td>High-side</td><td>The high-side IGBTs are actuated with the function STO1.</td></tr><tr><td>Low-side</td><td>The low-side IGBTs are actuated with the function STO1.</td></tr></table></td><td>High-side</td><td>R 1.3</td></tr>
</table>

Table 501: SafeMOTION parameter group: Basic functions - STO1

Group: Basic functions - SS1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS1 - Ramp monitoring - Enable

(previously Rampmonitoring for SS1)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SS1 function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When transitioning to the safe state of the SS1 function, a deceleration ramp is monitored in addition to the configurable time.</td></tr><tr><td>Disabled</td><td>When transitioning to the safe state of the SS1 function, only a configurable time is monitored.</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SS1 (us))</td><td>[μs]</td><td>Deceleration ramp monitoring time for SS1</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 502: SafeMOTION parameter group: Basic functions - SS1

Group: Basic functions - SBC (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBC - Enable delay time (previously *Delay time to start SBC (us)*)	[μs]	Delay time between the SBC request and activation of the safety function	0	R 1.3

Table 503: SafeMOTION parameter group: Basic functions - SBC

In a safety application, it is possible for multiple safety functions to be requested at the same time. In order to prevent this from turning into an unsafe situation, the individual safety functions are prioritized on the SafeMOTION module.

8.4.3 Integrated safety functions

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

8.4.4 Safe encoder connection

See 6.2.3.3 "Safe encoder connection" on page 307.

8.4.5 Fault avoidance

See 7.3.4 "Fault avoidance" on page 503.

8.4.6 Input parameters

> ## Information:
>
> **For detailed information about individual safety functions, see "SafeMOTION user's manual / chapter "Safety technology" / Integrated safety functions"!**

8.4.6.1 General information about "S_Control" inputs

"S_Control" inputs are used to request the respective safety functions.

> ## Information:
>
> **If a safety function is not used in the application, then the respective input must remain open.**

> ## Danger!
>
> **The safety functions that are used must be tested.**
> **A function is considered to be used if the respective input variable is connected!**

> ## Information:
>
> **To enable the function block itself and assign the functions to a defined axis, inputs "Activate" and "S_AxisID" must be connected at a minimum.**

> ## Information:
>
> **It is mandatory for function block SF_oS_MOTION_Basic_BR (or alternatively, function block SF_oS_MOTION_BR) to be applied to each axis being used in the safety application.**
>
> **In addition to inputs "Activate" and "S_AxisID", inputs "S_Control_Reset" and "S_Control_Activate" must also be used. Otherwise, the SafeDESIGNER project cannot be compiled.**

8.4.6.2 Activate

General function

- Enables the function block

Data type

- BOOL

Connection

- Constant or variable

Function description

This input parameter is used to activate the function block.

- When enabling or disabling safe devices, "Activate" must be linked to a variable that indicates the state (enabled or disabled) of the corresponding safe devices. This ensures that the function block does not output a triggered safety function as diagnostic information when a device is switched off.
- It is also possible to connect "Activate" to a constant (TRUE) in order to enable the function block.

TRUE

The function block is enabled.

FALSE

The function block is not enabled.
All binary output parameters are set to FALSE.
Sets the DiagCode diagnostic parameter to WORD#16#0000.

If you want to control function block diagnostics as needed in your diagnostic concept whenever error messages from safe devices and/or deactivated safe devices occur, connect "Activate" to a signal that indicates the status of the safe devices that are involved with the safety function supported by the function block. Form this signal using only safe devices whose I/O signals are connected to the function block via actual parameters. In this way, you prevent triggered safety functions from being reported by active safe devices. This measure is only used to control the diagnostic information from inactive safe devices in a defined manner.

8.4.6.3 S_Control_Reset

General function

- Input "S_Control_Reset" for acknowledging state FUNCTIONAL FAIL SAFE or for putting the SafeMOTION module into state OPERATIONAL after STARTUP

Data type

- SAFEBOOL

Connection

- Variable

Function description

Input "S_Control_Reset" for acknowledging the FUNCTIONAL FAIL SAFE state

A positive edge triggers the reset function.

Depending on the configuration of parameter "Automatic Reset at Startup", a positive edge may be necessary to get the SafeMOTION module from state INIT to state OPERATIONAL after startup.

Relevant configuration parameters

Group: General settings - Automatic reset on start (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Used Starting in Safety Release</th></tr>
<tr><td>Automatic reset on start - Enable

(previously Automatic Reset at Startup)</td><td>Enabled/
Disabled</td><td>Activates automatic reset of the function block at startup<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>After startup, the module automatically changes to state OPERATIONAL (Startreset). The reset input does not have to be controlled!</td></tr><tr><td>Disabled</td><td>After startup, the module remains in an Init state until a positive edge of the reset input is detected.</td></tr></table></td><td>Disabled</td><td>R1.3</td></tr>
</table>

Table 504: SafeMOTION parameter group: General settings - Automatic reset on start

Danger!

Parameter "Automatic reset on start" enables/disables the restart interlock during startup or when a network failure occurs on a reestablished network connection.

If parameter "Automatic reset on start" is set to "Enabled", then the module automatically changes to state OPERATIONAL state (i.e. pulse disabling and the motor holding brake are enabled)!

Configuring an automatic restart can result in critical safety conditions. Take additional measures to ensure proper safety-related functionality.

8.4.6.4 S_Control_Activate

General function

- Enables the module-internal state machine for a safe axis on the SafeMOTION module to execute the selected safety function

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to enable the module-internal state machine for a safe axis on the SafeMOTION module to execute the selected safety function.

SAFETRUE

Starts the state machine of the safe axis, safety functions can be enabled.

SAFEFALSE

Sets the state machine of the safe axis to state IDLE

8.4.6.5 S_Control_STO

General function

- Selects/Deselects safety function Safe Torque Off, STO

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the STO safety function.

SAFETRUE

The safety function is deselected. Safe pulse disabling is not active!

SAFEFALSE

The safety function is selected. Safe pulse disabling is active! Torque/Power are switched off on the drive.

Not connected

The safety function is deactivated.

Relevant configuration parameters

- None

8.4.6.6 S_Control_SBC

General function

- Selects/Deselects safety function Safe Brake Control, SBC

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SBC safety function.

SAFETRUE

The safety function is deselected. The motor holding brake output is enabled and can be used by the standard application.

SAFEFALSE

The safety function is selected. The motor holding brake output is switched to 0 V!

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Basic functions - SBC (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBC - Enable delay time (previously *Delay time to start SBC (us)*)	[µs]	Delay time between the SBC request and activation of the safety function	0	R 1.3

Table 505: SafeMOTION parameter group: Basic functions - SBC

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

8.4.6.7 S_Control_SS1

General function

- Selects/Deselects safety function Safe Stop 1, SS1

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SS1 safety function.

SAFETRUE

The safety function is deselected. SS1 is not active!

SAFEFALSE

The safety function is selected. Safe pulse disabling is activated after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 506: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Basic functions - SS1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS1 - Ramp monitoring - Enable

(previously Rampmonitoring for SS1)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SS1 function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When transitioning to the safe state of the SS1 function, a deceleration ramp is monitored in addition to the configurable time.</td></tr><tr><td>Disabled</td><td>When transitioning to the safe state of the SS1 function, only a configurable time is monitored.</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS1</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 507: SafeMOTION parameter group: Basic functions - SS1

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr><tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr></table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 508: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

To use this function without safe encoder evaluation, "Ramp monitoring for SS1" and "Early Limit Monitoring" must be disabled.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ < EUS - Maximum speed to normalize speed range

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

8.4.6.8 S_Control_STO1

General function

- Selects/Deselects safety function Safe Torque Off, One Channel, STO1

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the STO1 safety function.

SAFETRUE

The safety function is deselected. Safe pulse disabling is not active!

SAFEFALSE

The safety function is selected. Depending on the configuration, the high-side or low-side of safe pulse disabling is active! Torque/Power are switched off on the drive.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Basic functions - STO1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>STO1 - Channel

(previously Channel selection for One Channel STO (STO1))</td><td>High-side/
Low-side</td><td>Selects the high-side or low-side IGBT in the STO1 function<table><tr><th>Value</th><th>Description</th></tr><tr><td>High-side</td><td>The high-side IGBTs are actuated with the function STO1.</td></tr><tr><td>Low-side</td><td>The low-side IGBTs are actuated with the function STO1.</td></tr></table></td><td>High-side</td><td>R 1.3</td></tr>
</table>

Table 509: SafeMOTION parameter group: Basic functions - STO1

8.4.6.9 S_AxisID

General function

- This input parameter assigns a real axis to the function block.

Data type

- SAFEINT

Connection

- Constant

Function description

The corresponding axis can be connected to the input in SafeDESIGNER using drag-and-drop.

Information:

There is only permitted to be one combination of AxisID and function block oS_MOTION_Basic_BR or oS_MOTION_BR in the safety application. Otherwise, it will not be possible to compile the safety application.

8.4.7 Output parameters

Output parameters provide information about the state of the SafeMOTION module and the individual safety functions.

8.4.7.1 Ready

General function

- Message: Function block is enabled/disabled.

Data type

- BOOL

Connection

- Variable

Function description

This output parameter indicates whether the function block is enabled or not.

TRUE

The function block is enabled ("Activate" = TRUE). The output parameters indicate the current state of the safety function.

FALSE

The function block is not enabled ("Activate" = FALSE). The function block outputs are set to FALSE.

8.4.7.2 S_Status_NotErrFunc

General function

- Information about the error state of the safe axis of the SafeMOTION module

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies the error state of the safe axis of the SafeMOTION module.

SAFETRUE

No error was found on the SafeMOTION module.

SAFEFALSE

An error (e.g. exceeding a monitored limit) has been detected on the safe axis of the SafeMOTION module or the function block has not been activated.
In the event of an error, see the Safety Logger in Automation Studio for additional information about the error.
If the error is a functional error, then it can be acknowledged by changing the signal on input "S_Control_Reset" from SAFEFALSE to SAFETRUE (positive edge)!

> ## Danger!
>
> **The purpose of this signal is only to provide additional information. It only provides information in connection with the requested safety functions.**
> **"S_Status_NotErrFUNC" does not represent the functional safe state of the SafeMOTION module!**

> ## Danger!
>
> **It is your responsibility to ensure that all necessary corrective measures are initiated after an error occurs since subsequent errors can result in a hazard!**

8.4.7.3 S_Status_Operational

General function

- Information about the status of the state machine of the safe axis

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies the status of the state machine of the safe axis.

SAFETRUE

The state machine is in state OPERATIONAL.

SAFEFALSE

The state machine is not in state OPERATIONAL.

8.4.7.4 S_Status_STO

General function

- Status information for safety function Safe Torque Off, STO

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the STO safety function

SAFETRUE

The STO safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.4.7.5 S_Status_SBC

General function

- Status information for safety function Safe Brake Control, SBC

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SBC safety function

SAFETRUE

The SBC safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.4.7.6 S_Status_SS1

General function

- Status information for safety function Safe Stop 1, SS1

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SS1 safety function

SAFETRUE

The SS1 safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.4.7.7 S_Status_STO1

General function

- Status information for safety function Safe Torque Off, One Channel, STO1

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the STO1 safety function

SAFETRUE

The STO1 safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.4.7.8 S_Status_SDC

General function

- Information about the status of ramp monitoring

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the status of ramp monitoring.

SAFETRUE

Ramp monitoring is active.

SAFEFALSE

Ramp monitoring is not active. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

> **Danger!**
>
> **This signal should only be used for status information.**

8.4.7.9 S_Status_EncStatus

General function

- Information about the error state of the safe encoder signal

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the error state of the signal for a defined safe encoder.
If an encoder error is detected or the SafeMOTION module is in an error state, then the output is set to SAFEFALSE. This state is maintained until the error has been corrected.

SAFETRUE

An error was not detected on the encoder signal.

SAFEFALSE

The encoder signal from a defined safe axis is faulty, or the axis itself is in an error state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled. For more information about the error, see the Safety Logger in Automation Studio.

> **Danger!**
>
> **The purpose of this signal is only to provide additional information. It only provides information in connection with the requested safety functions.**
> **"S_Status_EncStatus" does not represent the functional safe state of the SafeMOTION module!**

8.4.7.10 Error

General function

- Function block error message

Data type

- BOOL

Connection

- Variable

Function description

This formal parameter indicates a pending function block error message.

TRUE

The enabled function block detected an error. "DiagCode" indicates the error code.

FALSE

The function block is not enabled, or the enabled function block did not detect an error. "DiagCode" indicates the status.

> **Danger!**
>
> **It is your responsibility to ensure that all necessary corrective measures are initiated after an error occurs since subsequent errors can result in a hazard!**

In order to exit an error state ("Error" = TRUE), the signal on input "S_Control_Reset" must change from SAFEFALSE to SAFETRUE (positive edge).

8.4.7.11 DiagCode

General function

- Function block diagnostic message

Data type

- WORD

Connection

- Variable

Function description

This output parameter is used to output diagnostic and status messages specific to the function block and make them available automatically to diagnostic tools.

These diagnostic tools cannot acknowledge diagnostic messages from function blocks. This is done exclusively in the **safety** application.

The function block indicates the presence of an error message on the "DiagCode" output via the "Error" output parameter.

Diagnostic code

The diagnostic code is specified as data type WORD. The values and meanings of these diagnostic codes are listed below.

In the event of status messages (0xxx$_{hex}$, 8xxx$_{hex}$), the function block sets "Error" to FALSE.

In the event of error messages (Cxxx$_{hex}$), the function block sets "Error" to TRUE.

8.4.7.12 Overview of diagnostic codes

Diagnostic codes

Code (hex)	Description	Corrective measures
0000	The function block is not enabled. If "Activate" is connected to a variable that indicates the state of the connected safe device (active, inactive or peripheral fault detected), then the safe device is not active or has detected a fault in the connected peripheral.	• Enable the function block by setting "Activate" to SAFETRUE. • Enable the safe device if "Activate" is connected to a variable that indicates the state of a connected safe device (active, inactive or peripheral fault detected), or correct the fault in the peripheral according to the device description.
8000	The function block detected neither a status nor an error to set the enable output to SAFEFALSE.	• If this is a desired signal combination at the signal inputs, no action is required. • If the signal combination on the signal inputs is unintended, check the connected peripheral and correct any faults.
C001	The function set for the control byte was not found.	Check whether the required safety function is supported by the connected axis.
C002	The function set for the status byte was not found.	Check whether the required safety function is supported by the connected axis.
C003	The function set ID that was read does not match.	Check whether the required safety function is supported by the connected axis.
C004	The data length of the function set that was read is invalid.	Check whether the required safety function is supported by the connected axis.
C005	The status byte could not be read.	Check whether the required safety function is supported by the connected axis.
C006	The control byte could not be written.	Check whether the required safety function is supported by the connected axis.

Table 510: SF_oS_MOTION_(Basic, Speed, Advanced, AbsPos)_BR: Diagnostic codes

8.4.8 Signal sequence diagram of the function block

A general signal sequence diagram of the function block cannot be specified since it depends on which safety functions are selected or deselected.

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

8.5 SF_oS_MOTION_Speed_BR

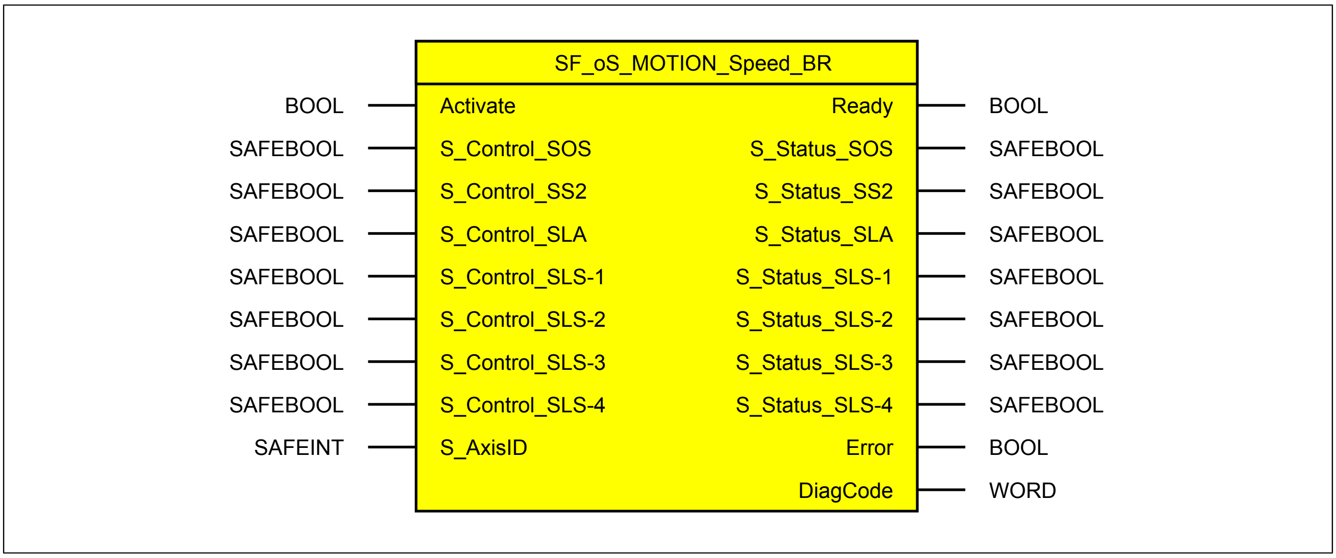


Figure 125: Function block SF_oS_MOTION_Speed_BR

Information:

Library openSAFETY_BuR_Motion_SF can only be used to control ACOPOS P3 SafeMOTION servo drives.

Information:

It is mandatory for function block SF_oS_MOTION_Basic_BR to be applied to each axis being used in the safety application. Otherwise, the internal state machine of the axis remains in state IDLE, and pulse disabling and the holding brake output cannot be enabled.
Alternatively, function block SF_oS_MOTION_BR can be used; it represents the combination of all available function sets.

8.5.1 Formal parameters of the function block

In the following, the term "variable" refers to both a variable as well as a graphic connection.

Name	Type	Connection	Signal type [1)]	Initial value	Description / General function
Activate	BOOL	Variable/ Constant	Status	FALSE	Enables the function block (= TRUE) Input "Activate" according to the PLCopen standard
S_Control_SOS	SAFEBOOL	Variable/ Constant	Status	SAFEFALSE	Request for safety function Safe Operating Stop (SOS). SAFEFALSE: Safety function requested
S_Control_SS2	SAFEBOOL	Variable/ Constant	Status	SAFEFALSE	Request for safety function Safe Stop 2 (SS2). SAFEFALSE: Safety function requested
S_Control_SLA	SAFEBOOL	Variable/ Constant	Status	SAFEFALSE	Request for safety function Safely Limited Acceleration (SLA). SAFEFALSE: Safety function requested
S_Control_SLS-1	SAFEBOOL	Variable/ Constant	Status	SAFEFALSE	Request for safety function Safely Limited Speed, Speed Limit 1 (SLS-1). SAFEFALSE: Safety function requested
S_Control_SLS-2	SAFEBOOL	Variable/ Constant	Status	SAFEFALSE	Request for safety function Safely Limited Speed, Speed Limit 2 (SLS-2). SAFEFALSE: Safety function requested
S_Control_SLS-3	SAFEBOOL	Variable/ Constant	Status	SAFEFALSE	Request for safety function Safely Limited Speed, Speed Limit 3 (SLS-3). SAFEFALSE: Safety function requested
S_Control_SLS-4	SAFEBOOL	Variable/ Constant	Status	SAFEFALSE	Request for safety function Safely Limited Speed, Speed Limit 4 (SLS-4). SAFEFALSE: Safety function requested
S_AxisID	SAFEINT	Constant	Status	-1	Assigns an axis to the function block

Table 511: SF_oS_MOTION_Speed_BR: Overview of input parameters

1) Evaluation of the input parameter signals in the function block. You must control the signals accordingly.

Name	Type	Connection	Signal type [1)]	Initial value	Description / General function
Ready	BOOL	Variable	Status	FALSE	Indicates that the function block is enabled Output **Ready** according to the PLCopen standard
S_Status_SOS	SAFEBOOL	Variable	Status	SAFEFALSE	Safety function "Safe Operating Stop" (SOS) active, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_SS2	SAFEBOOL	Variable	Status	SAFEFALSE	Safety function "Safe Stop 2" (SS2) is active, deceleration monitoring is completed, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_SLA	SAFEBOOL	Variable	Status	SAFEFALSE	Safety function "Safely Limited Acceleration" (SLA) active, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_SLS-1	SAFEBOOL	Variable	Status	SAFEFALSE	Safety function "Safely Limited Speed, Speed Limit 1" (SLS-1) is active, deceleration monitoring is completed, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_SLS-2	SAFEBOOL	Variable	Status	SAFEFALSE	Safety function "Safely Limited Speed, Speed Limit 2" (SLS-2) is active, deceleration monitoring is completed, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_SLS-3	SAFEBOOL	Variable	Status	SAFEFALSE	Safety function "Safely Limited Speed, Speed Limit 3" (SLS-3) is active, deceleration monitoring is completed, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_SLS-4	SAFEBOOL	Variable	Status	SAFEFALSE	Safety function "Safely Limited Speed, Speed Limit 4" (SLS-4) is active, deceleration monitoring is completed, no violation of a monitored limit (i.e. SAFETRUE)
Error	BOOL	Variable	Status	FALSE	Function block error message
DiagCode	WORD	Variable	Status	16#0000	Function block diagnostic message

Table 512: SF_oS_MOTION_Speed_BR: Overview of output parameters

1) Output of the output parameter signals. You must evaluate and/or further process the signals accordingly.

Type	Description	Size in bits	Format option
BOOL	Bit	1	Bit string
WORD	Word	16	Bit string
DINT	Double integer	32	Binary number, hexadecimal number, signed decimal number
SAFEBOOL	Bit	1	Bit string (signal source: safe device)
SAFEDWORD	Double word	32	Bit string (signal source: safe device)
SAFEDINT	Double integer	32	Binary number, hexadecimal number, signed decimal number (signal source: safe device)
SAFEINT	Integer	16	Binary number, hexadecimal number, signed decimal number (signal source: safe device)

Table 513: Format description of the data types

You have the option of linking a safe signal with a non-safe input parameter. To do so, use a function block for type conversion.

Caution!

You are responsible for any conversion of a non-safe input parameter to a safe signal.

8.5.2 SafeMOTION module parameters

Group: Speed functions - SS2 (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SS2 - Ramp monitoring - Enable (previously *Rampmonitoring for SS2*)	Enabled/ Disabled	Activates ramp monitoring (in addition to time-based monitoring) when the SS2 function is requested **Value** – **Description** Enabled – When changing to the safe state of the SS2 function, a deceleration ramp is also monitored, in addition to the configurable time Disabled – When changing to the safe state of the SS2 function, only a configurable time is monitored	Enabled	R 1.3
Ramp Monitoring Time for SS2 (us)	[µs]	Deceleration ramp monitoring time for SS2	0	R 1.3

Table 514: SafeMOTION parameter group: Speed functions - SS2

Group: Speed functions - SLA (previously *Safely Limited Acceleration*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLA - Acceleration limit in positive direction (previously *Safe acceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for acceleration in the positive direction of movement	0	R 1.9
SLA - Deceleration limit in positive direction (previously *Safe deceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for deceleration in the positive direction of movement	0	R 1.9
SLA - Acceleration limit in negative direction (previously *Safe acceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for acceleration in the negative direction of movement	0	R 1.9
SLA - Deceleration limit in negative direction (previously *Safe deceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for deceleration in the negative direction of movement	0	R 1.9
SLA - Enable delay time (previously *Delay time to start SLA (us)*)	[µs]	Delay time between the SLA request and activation of the safety function	0	R 1.9

Table 515: SafeMOTION parameter group: Speed functions - SLA

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SMS - Enable (previously *Safe Maximum Speed*)	Enabled/ Disabled	Activates the SMS safety function by configuration **Value** – **Description** Enabled – SMS activated Disabled – SMS deactivated	Enabled	R 1.3
SMS - Speed limit (previously *Maximum Speed for SMS (units/s)*)	[units/s]	Speed limit of the maximum speed (SMS)	0	R 1.3
SLS1 - Speed limit (previously *Safe Speedlimit 1 for SLS (units/s)*)	[units/s]	Speed limit 1 for SLS (SLS1)	0	R 1.3
SLS2 - Speed limit (previously *Safe Speedlimit 2 for SLS (units/s)*)	[units/s]	Speed limit 2 for SLS (SLS2)	0	R 1.3
SLS3 - Speed limit (previously *Safe Speedlimit 3 for SLS (units/s)*)	[units/s]	Speed limit 3 for SLS (SLS3)	0	R 1.3

Table 516: SafeMOTION parameter group: Speed functions - SMS/SLS

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SLS4 - Speed limit

(previously Safe Speedlimit 4 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 4 for SLS (SLS4)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS - Ramp monitoring - Enable

(previously Rampmonitoring for SLS)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr>
<tr><td>Disabled</td><td>When changing to the safe state of the SLS function, only a configurable time is monitored</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SLS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS1</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS2 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS2</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS3 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS3</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS4 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS4 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS4</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 516: SafeMOTION parameter group: Speed functions - SMS/SLS

Danger!

The respective monitored speed limit must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous speed cannot be exceeded in the event of error.
The dangerous speed must be determined by a risk analysis.

Information:

The following application rule must be observed:

$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS} \leq$ EUS - Maximum speed to normalize speed range

This is required for setting priority of the safety functions on the SafeMOTION module.

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

In a safety application, it is possible for multiple safety functions to be requested at the same time. In order to prevent this from turning into an unsafe situation, the individual safety functions are prioritized on the SafeMOTION module.

If several functions are active, then the lowest speed limit is always the value being monitored.

Information:

The following application rule must be observed:

$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS} \leq$ EUS - Maximum speed to normalize speed range

This is required for setting priority of the safety functions on the SafeMOTION module.

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

8.5.3 Integrated safety functions

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

8.5.4 Safe encoder connection

See 6.2.3.3 "Safe encoder connection" on page 307.

8.5.5 Fault avoidance

See 7.3.4 "Fault avoidance" on page 503.

8.5.6 Input parameters

> ## Information:
> **For detailed information about individual safety functions, see "SafeMOTION user's manual / chapter "Safety technology" / Integrated safety functions"!**

8.5.6.1 General information about "S_Control" inputs

"S_Control" inputs are used to request the respective safety functions.

> ## Information:
> **If a safety function is not used in the application, then the respective input must remain open.**

> ## Danger!
> **The safety functions that are used must be tested.**
> **A function is considered to be used if the respective input variable is connected!**

> ## Information:
> **To enable the function block itself and assign the functions to a defined axis, inputs "Activate" and "S_AxisID" must be connected at a minimum.**

> ## Information:
> **It is mandatory for function block SF_oS_MOTION_Basic_BR (or alternatively, function block SF_oS_MOTION_BR) to be applied to each axis being used in the safety application.**

8.5.6.2 Activate

General function

- Enables the function block

Data type

- BOOL

Connection

- Constant or variable

Function description

This input parameter is used to activate the function block.

- When enabling or disabling safe devices, "Activate" must be linked to a variable that indicates the state (enabled or disabled) of the corresponding safe devices. This ensures that the function block does not output a triggered safety function as diagnostic information when a device is switched off.
- It is also possible to connect "Activate" to a constant (TRUE) in order to enable the function block.

TRUE

The function block is enabled.

FALSE

The function block is not enabled.
All binary output parameters are set to FALSE.
Sets the DiagCode diagnostic parameter to WORD#16#0000.

If you want to control function block diagnostics as needed in your diagnostic concept whenever error messages from safe devices and/or deactivated safe devices occur, connect "Activate" to a signal that indicates the status of the safe devices that are involved with the safety function supported by the function block. Form this signal using only safe devices whose I/O signals are connected to the function block via actual parameters. In this way, you prevent triggered safety functions from being reported by active safe devices. This measure is only used to control the diagnostic information from inactive safe devices in a defined manner.

8.5.6.3 S_Control_SOS

General function

- Selects/Deselects safety function Safe Operating Stop, SOS

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SOS safety function.

SAFETRUE

The safety function is deselected. Standstill tolerances are not being monitored.

SAFEFALSE

The safety function is selected. Standstill tolerances are being monitored.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 517: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ < EUS - Maximum speed to normalize speed range

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

8.5.6.4 S_Control_SS2

General function

- Selects/Deselects safety function Safe Stop 2, SS2

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SS2 safety function.

SAFETRUE

The safety function is deselected. SS2 is not active!

SAFEFALSE

The safety function is selected. Standstill monitoring is activated after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 518: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SS2 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS2 - Ramp monitoring - Enable

(previously Rampmonitoring for SS2)</td><td>Enabled/
Disabled</td><td>Activates ramp monitoring (in addition to time-based monitoring) when the SS2 function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When changing to the safe state of the SS2 function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr>
<tr><td>Disabled</td><td>When changing to the safe state of the SS2 function, only a configurable time is monitored</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>Ramp Monitoring Time for SS2 (us)</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS2</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 519: SafeMOTION parameter group: Speed functions - SS2

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 520: SafeMOTION parameter group: General settings - Standstill monitoring

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** – **Description** Enabled – "Early Limit Monitoring" is active! Disabled – "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 521: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

8.5.6.5 S_Control_SLA

General function

- Selects/Deselects safety function Safely Limited Acceleration, SLA

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLA safety function.

SAFETRUE

The safety function is deselected. SLA is not active!

SAFEFALSE

The safety function is selected. A safe limit value for acceleration/deceleration is monitored with respect to the direction of movement.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 522: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Speed functions - SLA (previously *Safely Limited Acceleration*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLA - Acceleration limit in positive direction (previously *Safe acceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for acceleration in the positive direction of movement	0	R 1.9
SLA - Deceleration limit in positive direction (previously *Safe deceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for deceleration in the positive direction of movement	0	R 1.9
SLA - Acceleration limit in negative direction (previously *Safe acceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for acceleration in the negative direction of movement	0	R 1.9
SLA - Deceleration limit in negative direction (previously *Safe deceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for deceleration in the negative direction of movement	0	R 1.9
SLA - Enable delay time (previously *Delay time to start SLA (us)*)	[µs]	Delay time between the SLA request and activation of the safety function	0	R 1.9

Table 523: SafeMOTION parameter group: Speed functions - SLA

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

8.5.6.6 S_Control_SLS-1

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 1

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS1 safety function.

SAFETRUE

The safety function is deselected. SLS1 is not active!

SAFEFALSE

The safety function is selected. Speed limit 1 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 524: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SLS - Ramp monitoring - Enable

(previously Rampmonitoring for SLS)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr><tr><td>Disabled</td><td>When changing to the safe state of the SLS function, only a configurable time is monitored</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SLS1 - Speed limit

(previously Safe Speedlimit 1 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 1 for SLS (SLS1)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS1</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 525: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr><tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr></table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 526: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS} <$ **EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

8.5.6.7 S_Control_SLS-2

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 2

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS2 safety function.

SAFETRUE

The safety function is deselected. SLS2 is not active!

SAFEFALSE

The safety function is selected. Speed limit 2 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 527: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SLS - Ramp monitoring - Enable

(previously Rampmonitoring for SLS)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr>
<tr><td>Disabled</td><td>When changing to the safe state of the SLS function, only a configurable time is monitored</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Speed limit

(previously Safe Speedlimit 2 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 2 for SLS (SLS2)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS2 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS2</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 528: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr>
<tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr>
</table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 529: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$\mathbf{LIM_{SOS} \le LIM_{SLS4} \le LIM_{SLS3} \le LIM_{SLS2} \le LIM_{SLS1} \le LIM_{SMS} < EUS}$ **- Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

8.5.6.8 S_Control_SLS-3

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 3

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS3 safety function.

SAFETRUE

The safety function is deselected. SLS3 is not active!

SAFEFALSE

The safety function is selected. Speed limit 3 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 530: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLS - Ramp monitoring - Enable (previously *Rampmonitoring for SLS*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested **Value** / **Description** Enabled: When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time Disabled: When changing to the safe state of the SLS function, only a configurable time is monitored	Enabled	R 1.3
SLS3 - Speed limit (previously *Safe Speedlimit 3 for SLS (units/s)*)	[units/s]	Speed limit 3 for SLS (SLS3)	0	R 1.3
SLS3 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS3 (us)*)	[µs]	Deceleration ramp monitoring time for SLS3	0	R 1.3

Table 531: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** / **Description** Enabled: "Early Limit Monitoring" is active! Disabled: "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 532: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

8.5.6.9 S_Control_SLS-4

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 4

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS4 safety function.

SAFETRUE

The safety function is deselected. SLS4 is not active!

SAFEFALSE

The safety function is selected. Speed limit 4 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 533: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLS - Ramp monitoring - Enable (previously *Rampmonitoring for SLS*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested **Value** / **Description** Enabled: When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time Disabled: When changing to the safe state of the SLS function, only a configurable time is monitored	Enabled	R 1.3
SLS4 - Speed limit (previously *Safe Speedlimit 4 for SLS (units/s)*)	[units/s]	Speed limit 2 for SLS (SLS2)	0	R 1.3
SLS4 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS4 (us)*)	[µs]	Deceleration ramp monitoring time for SLS2	0	R 1.3

Table 534: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** / **Description** Enabled: "Early Limit Monitoring" is active! Disabled: "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 535: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \le LIM_{SLS4} \le LIM_{SLS3} \le LIM_{SLS2} \le LIM_{SLS1} \le LIM_{SMS} <$ **EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

8.5.6.10 S_AxisID

General function

- This input parameter assigns a real axis to the function block.

Data type

- SAFEINT

Connection

- Constant

Function description

The corresponding axis can be connected to the input in SafeDESIGNER using drag-and-drop.

> ## Information:
>
> **There is only permitted to be one combination of AxisID and function block oS_MOTION_Basic_BR or oS_MOTION_BR in the safety application. Otherwise, it will not be possible to compile the safety application.**

8.5.7 Output parameters

Output parameters provide information about the state of the SafeMOTION module and the individual safety functions.

8.5.7.1 Ready

General function

- Message: Function block is enabled/disabled.

Data type

- BOOL

Connection

- Variable

Function description

This output parameter indicates whether the function block is enabled or not.

TRUE

The function block is enabled ("Activate" = TRUE). The output parameters indicate the current state of the safety function.

FALSE

The function block is not enabled ("Activate" = FALSE). The function block outputs are set to FALSE.

8.5.7.2 S_Status_SOS

General function

- Status information for safety function Safe Operating Stop, SOS

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SOS safety function

SAFETRUE

The SOS safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.5.7.3 S_Status_SS2

General function

- Status information for safety function Safe Stop 2, SS2

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SS2 safety function

SAFETRUE

The SS2 safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.5.7.4 S_Status_SLA

General function

- Status information for safety function Safely Limited Acceleration, SLA

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLA safety function

SAFETRUE

The SLA safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.5.7.5 S_Status_SLS-1

General function

- Status information for safety function Safely Limited Speed, Speed Limit 1 (SLS-1)

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS1 safety function

SAFETRUE

The SLS1 safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.5.7.6 S_Status_SLS-2

General function

- Status information for safety function Safely Limited Speed, Speed Limit 2 (SLS-1)

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS2 safety function

SAFETRUE

The SLS2 safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.5.7.7 S_Status_SLS-3

General function

- Status information for safety function Safely Limited Speed, Speed Limit 3 (SLS-1)

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS3 safety function

SAFETRUE

The SLS3 safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.5.7.8 S_Status_SLS-4

General function

- Status information for safety function Safely Limited Speed, Speed Limit 4 (SLS-1)

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS4 safety function

SAFETRUE

The SLS4 safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.5.7.9 Error

General function

- Function block error message

Data type

- BOOL

Connection

- Variable

Function description

This formal parameter indicates a pending function block error message.

TRUE

The enabled function block detected an error. "DiagCode" indicates the error code.

FALSE

The function block is not enabled, or the enabled function block did not detect an error. "DiagCode" indicates the status.

> ## Danger!
>
> **It is your responsibility to ensure that all necessary corrective measures are initiated after an error occurs since subsequent errors can result in a hazard!**

In order to exit an error state ("Error" = TRUE), the signal on input "S_Control_Reset" must change from SAFEFALSE to SAFETRUE (positive edge).

8.5.7.10 DiagCode

General function

- Function block diagnostic message

Data type

- WORD

Connection

- Variable

Function description

This output parameter is used to output diagnostic and status messages specific to the function block and make them available automatically to diagnostic tools.

These diagnostic tools cannot acknowledge diagnostic messages from function blocks. This is done exclusively in the **safety** application.

The function block indicates the presence of an error message on the "DiagCode" output via the "Error" output parameter.

Diagnostic code

The diagnostic code is specified as data type WORD. The values and meanings of these diagnostic codes are listed below.

In the event of status messages ($0xxx_{hex}$, $8xxx_{hex}$), the function block sets "Error" to FALSE.

In the event of error messages ($Cxxx_{hex}$), the function block sets "Error" to TRUE.

8.5.7.11 Overview of diagnostic codes

Diagnostic codes

Code (hex)	Description	Corrective measures
0000	The function block is not enabled. If "Activate" is connected to a variable that indicates the state of the connected safe device (active, inactive or peripheral fault detected), then the safe device is not active or has detected a fault in the connected peripheral.	• Enable the function block by setting "Activate" to SAFETRUE. • Enable the safe device if "Activate" is connected to a variable that indicates the state of a connected safe device (active, inactive or peripheral fault detected), or correct the fault in the peripheral according to the device description.
8000	The function block detected neither a status nor an error to set the enable output to SAFEFALSE.	• If this is a desired signal combination at the signal inputs, no action is required. • If the signal combination on the signal inputs is unintended, check the connected peripheral and correct any faults.
C001	The function set for the control byte was not found.	Check whether the required safety function is supported by the connected axis.
C002	The function set for the status byte was not found.	Check whether the required safety function is supported by the connected axis.
C003	The function set ID that was read does not match.	Check whether the required safety function is supported by the connected axis.
C004	The data length of the function set that was read is invalid.	Check whether the required safety function is supported by the connected axis.
C005	The status byte could not be read.	Check whether the required safety function is supported by the connected axis.
C006	The control byte could not be written.	Check whether the required safety function is supported by the connected axis.

Table 536: SF_oS_MOTION_(Basic, Speed, Advanced, AbsPos)_BR: Diagnostic codes

8.5.8 Signal sequence diagram of the function block

A general signal sequence diagram of the function block cannot be specified since it depends on which safety functions are selected or deselected.

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

8.6 SF_oS_MOTION_Advanced_BR

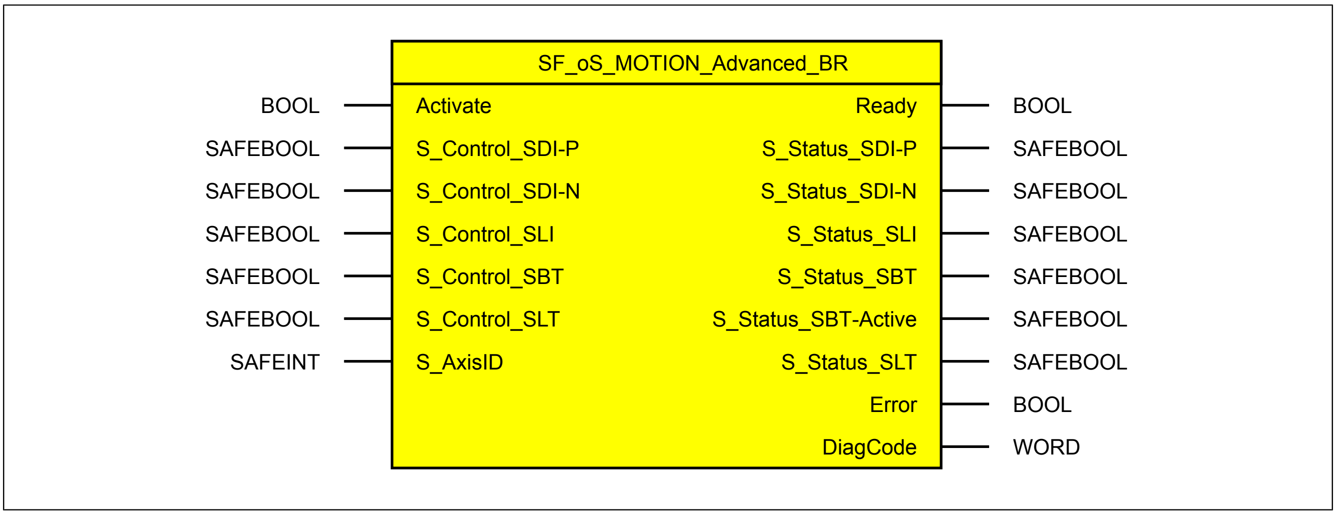


Figure 126: Function block SF_oS_MOTION_Advanced_BR

Information:

Library openSAFETY_BuR_Motion_SF can only be used to control ACOPOS P3 SafeMOTION servo drives.

Information:

It is mandatory for function block SF_oS_MOTION_Basic_BR to be applied to each axis being used in the safety application. Otherwise, the internal state machine of the axis remains in state IDLE, and pulse disabling and the holding brake output cannot be enabled.
Alternatively, function block SF_oS_MOTION_BR can be used; it represents the combination of all available function sets.

8.6.1 Formal parameters of the function block

In the following, the term "variable" refers to both a variable as well as a graphic connection.

Name	Type	Connection	Signal type 1)	Initial value	Description / General function
Activate	BOOL	Variable/ Constant	State	FALSE	Enables the function block (= TRUE) Input "Activate" according to the PLCopen standard
S_Control_SDI-P	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safe Direction (SDI). Movement in the positive direction is allowed. SAFEFALSE: Safety function requested
S_Control_SDI-N	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safe Direction (SDI). Movement in the negative direction is allowed. SAFEFALSE: Safety function requested
S_Control_SLI	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safely Limited Increment (SLI). SAFEFALSE: Safety function requested
S_Control_SBT	SAFEBOOL	Variable/ Constant	Edge	SAFEFALSE	Request for safety function Safe Brake Test (SBT). The request is made on a falling edge!
S_Control_SLT	SAFEBOOL	Variable/ Constant	Edge	SAFEFALSE	Request for safety function "Safely Limited Torque" (SLT) SAFEFALSE: Safety function requested
S_AxisID	SAFEINT	Constant	State	-1	Assigns an axis to the function block

Table 537: SF_oS_MOTION_Advanced_BR: Overview of input parameters

1) Evaluation of the input parameter signals in the function block. You must control the signals accordingly.

Name	Type	Connection	Signal type [1)]	Initial value	Description / General function
Ready	BOOL	Variable	State	FALSE	Indicates that the function block is enabled Output **Ready** according to the PLCopen standard
S_Status_SDI-P	SAFEBOOL	Variable	State	SAFEFALSE	Safety function "Safe Direction" (SDI, positive direction) active (i.e. SAFETRUE)
S_Status_SDI-N	SAFEBOOL	Variable	State	SAFEFALSE	Safety function "Safe Direction" (SDI, negative direction) active (i.e. SAFETRUE)
S_Status_SLI	SAFEBOOL	Variable	State	SAFEFALSE	Safety function "Safely Limited Increment" (SLI) active, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_SBT	SAFEBOOL	Variable	State	SAFEFALSE	Safety function "Safe Brake Test" (SBT) completed successfully, status of test is valid (i.e. SAFETRUE)
S_Status_SBT-Active	SAFEBOOL	Variable	State	SAFEFALSE	Safety function "Safe Brake Test" (SBT) active (i.e. SAFETRUE)
S_Status_SLT	SAFEBOOL	Variable	State	SAFEFALSE	Safety function "Safely Limited Torque" (SLT) active, no violation of a monitored limit (i.e. SAFETRUE)
Error	BOOL	Variable	State	FALSE	Function block error message
DiagCode	WORD	Variable	State	16#0000	Function block diagnostic message

Table 538: SF_oS_MOTION_Advanced_BR: Overview of output parameters

1) Output of the output parameter signals. You must evaluate and/or further process the signals accordingly.

Type	Description	Size in bits	Format option
BOOL	Bit	1	Bit string
WORD	Word	16	Bit string
DINT	Double integer	32	Binary number, hexadecimal number, signed decimal number
SAFEBOOL	Bit	1	Bit string (signal source: safe device)
SAFEDWORD	Double word	32	Bit string (signal source: safe device)
SAFEDINT	Double integer	32	Binary number, hexadecimal number, signed decimal number (signal source: safe device)
SAFEINT	Integer	16	Binary number, hexadecimal number, signed decimal number (signal source: safe device)

Table 539: Format description of the data types

You have the option of linking a safe signal with a non-safe input parameter. To do so, use a function block for type conversion.

Caution!

You are responsible for any conversion of a non-safe input parameter to a safe signal.

8.6.2 SafeMOTION module parameters

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 540: SafeMOTION parameter group: Advanced functions - SDI

Group: Advanced functions - SLI (previously *Safely Limited Increment*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLI - Position limit (previously *Safe Increments (units)*)	[units]	Maximum movable increments when SLI is active	0	R 1.3
SLI - Disable delay time (previously *SLI Off Delay (µs)*)	[µs]	Switch off delay of SLI	0	R 1.3

Table 541: SafeMOTION parameter group: Advanced functions - SLI

In a safety application, it is possible for multiple safety functions to be requested at the same time. In order to prevent this from turning into an unsafe situation, the individual safety functions are prioritized on the SafeMOTION module.

If several functions are active, then the lowest speed limit is always the value being monitored.

Information:

The following application rule must be observed:

$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS} \leq$ EUS - Maximum speed to normalize speed range

This is required for setting priority of the safety functions on the SafeMOTION module.

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

8.6.3 Integrated safety functions

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

8.6.4 Safe encoder connection

See 6.2.3.3 "Safe encoder connection" on page 307.

8.6.5 Fault avoidance

See 7.3.4 "Fault avoidance" on page 503.

8.6.6 Input parameters

> **Information:**
>
> **For detailed information about individual safety functions, see "SafeMOTION user's manual / chapter "Safety technology" / Integrated safety functions"!**

8.6.6.1 General information about "S_Control" inputs

"S_Control" inputs are used to request the respective safety functions.

> **Information:**
>
> **If a safety function is not used in the application, then the respective input must remain open.**

> **Danger!**
>
> **The safety functions that are used must be tested.**
> **A function is considered to be used if the respective input variable is connected!**

> **Information:**
>
> **To enable the function block itself and assign the functions to a defined axis, inputs "Activate" and "S_AxisID" must be connected at a minimum.**

> **Information:**
>
> **It is mandatory for function block SF_oS_MOTION_Basic_BR (or alternatively, function block SF_oS_MOTION_BR) to be applied to each axis being used in the safety application.**

8.6.6.2 Activate

General function

- Enables the function block

Data type

- BOOL

Connection

- Constant or variable

Function description

This input parameter is used to activate the function block.

- When enabling or disabling safe devices, "Activate" must be linked to a variable that indicates the state (enabled or disabled) of the corresponding safe devices. This ensures that the function block does not output a triggered safety function as diagnostic information when a device is switched off.
- It is also possible to connect "Activate" to a constant (TRUE) in order to enable the function block.

TRUE

The function block is enabled.

FALSE

The function block is not enabled.
All binary output parameters are set to FALSE.
Sets the DiagCode diagnostic parameter to WORD#16#0000.

If you want to control function block diagnostics as needed in your diagnostic concept whenever error messages from safe devices and/or deactivated safe devices occur, connect "Activate" to a signal that indicates the status of the safe devices that are involved with the safety function supported by the function block. Form this signal using only safe devices whose I/O signals are connected to the function block via actual parameters. In this way, you prevent triggered safety functions from being reported by active safe devices. This measure is only used to control the diagnostic information from inactive safe devices in a defined manner.

8.6.6.3 S_Control_SDI-P

General function

- Selects/Deselects safety function Safe Direction. Movement is allowed in the positive direction.

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the safety function SDI, movement is allowed in the positive direction of movement.

SAFETRUE

The safety function is deselected. SDI is not active!

SAFEFALSE

The direction of movement is monitored after the delay time has expired. Movement is allowed in the positive direction.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 542: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*)	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 543: SafeMOTION parameter group: Advanced functions - SDI

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

8.6.6.4 S_Control_SDI-N

General function

- Selects/Deselects safety function Safe Direction. Movement is allowed in the negative direction.

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the safety function SDI, movement is allowed in the negative direction of movement.

SAFETRUE

The safety function is deselected. SDI is not active!

SAFEFALSE

The direction of movement is monitored after the delay time has expired. Movement is allowed in the negative direction.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 544: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*)	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 545: SafeMOTION parameter group: Advanced functions - SDI

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

8.6.6.5 S_Control_SLI

General function

- Selects/Deselects safety function Safely Limited Increment, SLI

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLI safety function.

SAFETRUE

The safety function is deselected. SLI is not active!

SAFEFALSE

The safety function is selected. A safe range of increments is monitored.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3

Table 546: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SLI (previously *Safely Limited Increment*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLI - Position limit (previously *Safe Increments (units)*)	[units]	Maximum movable increments when SLI is active	0	R 1.3
SLI - Disable delay time (previously *SLI Off Delay (µs)*)	[µs]	Switch off delay of SLI	0	R 1.3

Table 547: SafeMOTION parameter group: Advanced functions - SLI

Danger!

The maximum increment range must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

8.6.6.6 S_Control_SBT

General function

- Selects/Deselects safety function Safe Brake Test, SBT

Data type

- SAFEBOOL

Connection

- Variable

Function description

This input parameter is used to start the SBT safety function.

Negative edge

A negative edge (state transition from SAFETRUE to SAFEFALSE on input parameter "S_Control_SBT") starts safety function Safe Brake Test, SBT.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Advanced functions - SBT (previously *Safe Brake Test*) (only available for ACOPOSmulti SafeMOTION SinCos and ACOPOS P3 SafeMOTION (hardware upgrade 1.10.2.x or later)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBT - Threshold (previously *Safe Brake Test threshold (uA)*)	[µA]	Threshold value for the stator current that must be exceeded during the brake test	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - External load (previously *Safe Brake Test external load (uA)*)	[µA]	External load	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Position tolerance (previously *Safe Brake Test position tolerance (units)*)	[units]	Position tolerance	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Maximum torque duration (previously *Safe Brake Test maximum torque duration (us)*)	[µs]	Duration of the test for which the maximum torque must be present	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Test interval (previously *Safe Brake Test interval (s)*)	[s]	Retry interval for the safe brake test	28800	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Enable delay time (previously *Delay Time to start SBT (us)*)	[µs]	Delay time between the SBT request and activation of the safety function	0	R 1.7 SinCos R 1.10 ACOPOS P3

Table 548: SafeMOTION parameter group: Advanced functions - SBT

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

8.6.6.7 S_Control_SLT

General function

- Selects/Deselects safety function Safely Limited Torque, SLT

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLT safety function.

SAFETRUE

The safety function is deselected. SLT is not active!

SAFEFALSE

The safety function is selected. The configured motor torque limit is monitored.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Advanced functions - SLT (only available for ACOPOS P3 SafeMOTION in hardware upgrade 1.10.2.x or later)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLT - Torque limit	[mNm]	Torque limitation monitored during activation of SLT	0	R 1.10
SLT - Enable delay time	[µs]	Delay time between the SLT request and activation of the safety function	0	R 1.10

Table 549: SafeMOTION parameter group: Advanced functions - SLT

Group: General settings - Motor (only available for ACOPOS P3 SafeMOTION in hardware upgrade 1.10.2.x or later)

Parameter	Unit	Description	Default value	Starting in Safety Release
Motor - Number of pole pairs (hardware upgrade 1.10.2.x and later)	-	Number of pole pairs on the rotor circumference	1	1.10
Motor - Direction*) (hardware upgrade 1.10.2.x and later)	Standard / Inverse	Direction of rotation of the motor	Standard	1.10
Motor - Stator resistance (hardware upgrade 1.10.2.x and later)	mOhm	Ohmic stator resistance measured between two connections (phase - phase) of the motor	0	1.10
Motor - Stator inductance (hardware upgrade 1.10.2.x and later)	µH	Stator inductance measured between two connections (phase - phase) of the motor	0	1.10
Motor - Torque constant (hardware upgrade 1.10.2.x and later)	µNm / A	Torque constant of the motor	0	1.10
Motor - Rated speed (hardware upgrade 1.10.2.x and later)	units/s	Nominal speed of the motor	0	1.10
Motor - Stall current (hardware upgrade 1.10.2.x and later)	mA	Stall current of the motor	0	1.10
Motor - Rated current (hardware upgrade 1.10.2.x and later)	mA	Nominal current of the motor	0	1.10
Motor - Peak current (hardware upgrade 1.10.2.x and later)	mA	Peak current of the motor	0	1.10

Table 550: SafeMOTION parameter group: General settings - Motor

Parameter	Unit	Description	Default value	Starting in Safety Release
Motor - Stall torque (hardware upgrade 1.10.2.x and later)	mNm	Stall torque of the motor that is output when the stall current is applied	0	1.10
Motor - Peak torque (hardware upgrade 1.10.2.x and later)	mNm	Peak torque of the motor that is briefly output when the peak current is applied	0	1.10
Motor - Moment of inertia (optional) (hardware upgrade 1.10.2.x and later)	µkgm²	Mass moment of inertia of the motor. Consists of the sum of the inertias of the rotor, encoder and holding brake.	0	1.10
Motor - External moment of inertia (optional) (hardware upgrade 1.10.2.x and later)	µkgm²	External mass moment of inertia, depends on the total external load	0	1.10

Table 550: SafeMOTION parameter group: General settings - Motor

*) The direction of rotation of the motor is not related to the counting direction of the speed ("EUS - Counting direction"), i.e. the direction of rotation of the motor can be changed explicitly in the non-safe application and must therefore also be taken into account in SafeDESIGNER.

8.6.6.8 S_AxisID

General function

- This input parameter assigns a real axis to the function block.

Data type

- SAFEINT

Connection

- Constant

Function description

The corresponding axis can be connected to the input in SafeDESIGNER using drag-and-drop.

> **Information:**
>
> **There is only permitted to be one combination of AxisID and function block SF_oS_MOTION_Advanced_BR or SF_oS_MOTION_BR in the safety application. Otherwise, it will not be possible to compile the safety application.**

8.6.7 Output parameters

Output parameters provide information about the state of the SafeMOTION module and the individual safety functions.

8.6.7.1 Ready

General function

- Message: Function block is enabled/disabled.

Data type

- BOOL

Connection

- Variable

Function description

This output parameter indicates whether the function block is enabled or not.

TRUE

The function block is enabled ("Activate" = TRUE). The output parameters indicate the current state of the safety function.

FALSE

The function block is not enabled ("Activate" = FALSE). The function block outputs are set to FALSE.

8.6.7.2 S_Status_SDI-P

General function

- Status information for safety function Safe Direction. Movement is allowed in the positive direction.

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SDIpos safety function

SAFETRUE

The SDIpos safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.6.7.3 S_Status_SDI-N

General function

- Status information for safety function Safe Direction. Movement is allowed in the negative direction.

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SDIneg safety function

SAFETRUE

The SDIneg safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.6.7.4 S_Status_SLI

General function

- Status information for safety function Safely Limited Increment

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLI safety function

SAFETRUE

The SLI safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.6.7.5 S_Status_SBT

General function

- Additional information for testing the holding brake with Safe Brake Test

Data type

- SAFEBOOL

Connection

- Variable

Function description

Returns the status of the holding brake test with Safe Brake Test, SBT

SAFETRUE

The SBT safety function has been executed. The status of the testing is valid.

SAFEFALSE

The SBT safety function has not been executed. The status of the testing is invalid or expired.

8.6.7.6 S_Status_SBT-Active

General function

- Additional information for testing the holding brake with Safe Brake Test

Data type

- SAFEBOOL

Connection

- Variable

Function description

Returns the status of the holding brake test with Safe Brake Test, SBT

SAFETRUE

Testing of the holding brake with SBT is being executed.

SAFEFALSE

Testing of the holding brake with SBT is not requested.

8.6.7.7 S_Status_SLT

General function

- Status information for safety function Safely Limited Torque

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLT safety function

SAFETRUE

The SLT safety function is active and currently in its safe state.

SAFEFALSE

Safety function SLT is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.6.7.8 Error

General function

- Function block error message

Data type

- BOOL

Connection

- Variable

Function description

This formal parameter indicates a pending function block error message.

TRUE

The enabled function block detected an error. "DiagCode" indicates the error code.

FALSE

The function block is not enabled, or the enabled function block did not detect an error. "DiagCode" indicates the status.

> **Danger!**
>
> **It is your responsibility to ensure that all necessary corrective measures are initiated after an error occurs since subsequent errors can result in a hazard!**

In order to exit an error state ("Error" = TRUE), the signal on input "S_Control_Reset" must change from SAFEFALSE to SAFETRUE (positive edge).

8.6.7.9 DiagCode

General function

- Function block diagnostic message

Data type

- WORD

Connection

- Variable

Function description

This output parameter is used to output diagnostic and status messages specific to the function block and make them available automatically to diagnostic tools.

These diagnostic tools cannot acknowledge diagnostic messages from function blocks. This is done exclusively in the **safety** application.

The function block indicates the presence of an error message on the "DiagCode" output via the "Error" output parameter.

Diagnostic code

The diagnostic code is specified as data type WORD. The values and meanings of these diagnostic codes are listed below.

In the event of status messages ($0xxx_{hex}$, $8xxx_{hex}$), the function block sets "Error" to FALSE.

In the event of error messages ($Cxxx_{hex}$), the function block sets "Error" to TRUE.

8.6.7.10 Overview of diagnostic codes

Diagnostic codes

Code (hex)	Description	Corrective measures
0000	The function block is not enabled. If "Activate" is connected to a variable that indicates the state of the connected safe device (active, inactive or peripheral fault detected), then the safe device is not active or has detected a fault in the connected peripheral.	• Enable the function block by setting "Activate" to SAFETRUE. • Enable the safe device if "Activate" is connected to a variable that indicates the state of a connected safe device (active, inactive or peripheral fault detected), or correct the fault in the peripheral according to the device description.
8000	The function block detected neither a status nor an error to set the enable output to SAFEFALSE.	• If this is a desired signal combination at the signal inputs, no action is required. • If the signal combination on the signal inputs is unintended, check the connected peripheral and correct any faults.
C001	The function set for the control byte was not found.	Check whether the required safety function is supported by the connected axis.
C002	The function set for the status byte was not found.	Check whether the required safety function is supported by the connected axis.
C003	The function set ID that was read does not match.	Check whether the required safety function is supported by the connected axis.
C004	The data length of the function set that was read is invalid.	Check whether the required safety function is supported by the connected axis.
C005	The status byte could not be read.	Check whether the required safety function is supported by the connected axis.
C006	The control byte could not be written.	Check whether the required safety function is supported by the connected axis.

Table 551: SF_oS_MOTION_(Basic, Speed, Advanced, AbsPos)_BR: Diagnostic codes

8.6.8 Signal sequence diagram of the function block

A general signal sequence diagram of the function block cannot be specified since it depends on which safety functions are selected or deselected.

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

8.7 SF_oS_MOTION_AbsPos_BR

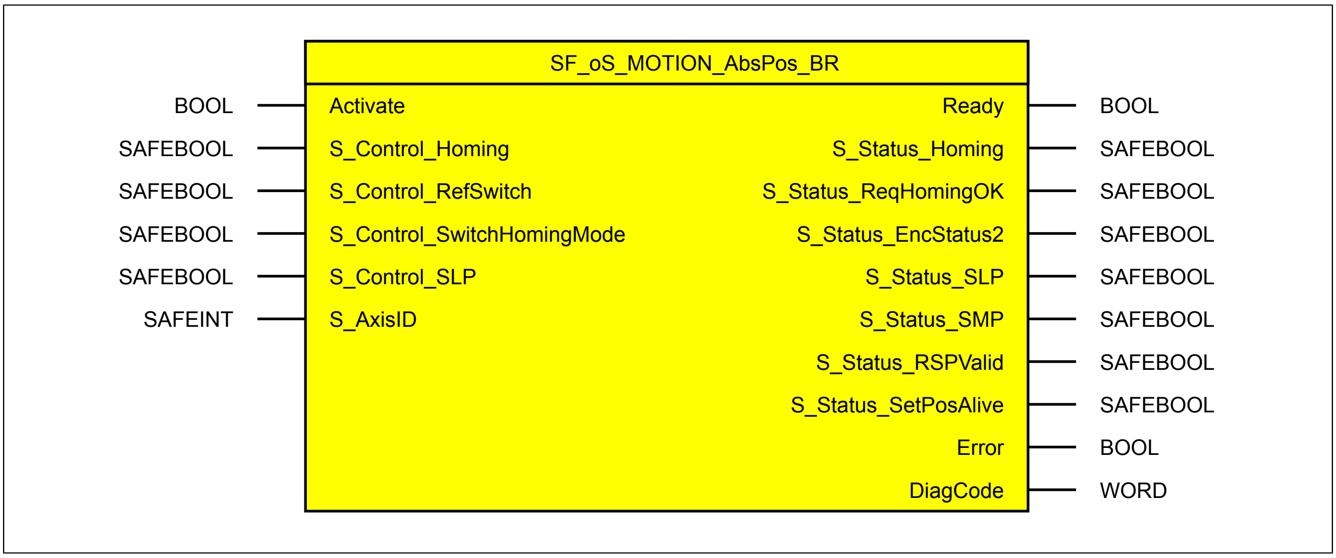


Figure 127: Function block SF_oS_MOTION_AbsPos_BR

Information:

Library openSAFETY_BuR_Motion_SF can only be used to control ACOPOS P3 SafeMOTION servo drives.

Information:

It is mandatory for function block SF_oS_MOTION_Basic_BR to be applied to each axis being used in the safety application. Otherwise, the internal state machine of the axis remains in state IDLE, and pulse disabling and the holding brake output cannot be enabled.
Alternatively, function block SF_oS_MOTION_BR can be used; it represents the combination of all available function sets.

8.7.1 Formal parameters of the function block

In the following, the term "variable" refers to both a variable as well as a graphic connection.

Name	Type	Connection	Signal type [1)]	Initial value	Description / General function
Activate	BOOL	Variable/ Constant	State	FALSE	Enables the function block (= TRUE) Input "Activate" according to the PLCopen standard
S_Control_Homing	SAFEBOOL	Variable	Edge	SAFEFALSE	Request for safe homing. The request is made on a rising edge!
S_Control_RefSwitch	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Safe input for a reference switch
S_Control_SwitchHom-ingMode	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Enables homing with remanent safe position (RSP). SAFEFALSE: Homing with RSP disabled.
S_Control_SLP	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safely Limited Position (SLP). SAFEFALSE: Safety function requested
S_AxisID	SAFEINT	Constant	State	-1	Assigns an axis to the function block

Table 552: SF_oS_MOTION_AbsPos_BR: Overview of input parameters

1) Evaluation of the input parameter signals in the function block. You must control the signals accordingly.

Name	Type	Connection	Signal type 1)	Initial value	Description / General function
Ready	BOOL	Variable	State	FALSE	Indicates that the function block is enabled Output "Ready" according to the PLCopen standard
S_Status_Homing	SAFEBOOL	Variable	State	SAFEFALSE	Specifies whether the safe position is valid (i.e. SAFETRUE, homing procedure has completed successfully and there are no encoder errors)
S_Status_ReqHomingOk	SAFEBOOL	Variable	State	SAFEFALSE	Feedback for homing in SafeDESIGNER (i.e. SAFETRUE, safe position is valid and request for safe homing is SAFETRUE)
S_Status_EncStatus2	SAFEBOOL	Variable	State	SAFEFALSE	No encoder error has been detected (i.e. SAFETRUE), signal "S_ScaledSpeed_2Byte" is valid.
S_Status_SLP	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safely Limited Position (SLP) active (i.e. SAFETRUE)
S_Status_SMP	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safe Maximum Position (SMP) active (i.e. SAFETRUE)
S_Status_RSPValid	SAFEBOOL	Variable	State	SAFEFALSE	Validates and stores the remanent safe position (RSP) (TRUE = safe position is stored, power off for homing with RSP is now possible)
S_Status_SetPosAlive	SAFEBOOL	Variable	State	SAFEFALSE	Status information about plausibility check of the position setpoint
Error	BOOL	Variable	State	FALSE	Function block error message
DiagCode	WORD	Variable	State	16#0000	Function block diagnostic message

Table 553: SF_oS_MOTION_AbsPos_BR: Overview of output parameters

1) Output of the output parameter signals. You must evaluate and/or further process the signals accordingly.

Type	Description	Size in bits	Format option
BOOL	Bit	1	Bit string
WORD	Word	16	Bit string
DINT	Double integer	32	Binary number, hexadecimal number, signed decimal number
SAFEBOOL	Bit	1	Bit string (signal source: safe device)
SAFEDWORD	Double word	32	Bit string (signal source: safe device)
SAFEDINT	Double integer	32	Binary number, hexadecimal number, signed decimal number (signal source: safe device)
SAFEINT	Integer	16	Binary number, hexadecimal number, signed decimal number (signal source: safe device)

Table 554: Format description of the data types

You have the option of linking a safe signal with a non-safe input parameter. To do so, use a function block for type conversion.

Caution!

You are responsible for any conversion of a non-safe input parameter to a safe signal.

8.7.2 SafeMOTION module parameters

Group: Absolute position functions - Homing (previously *Homing*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Home position or home offset (previously *Home Position or Home Offset (units)*)	[units]	Home position or home offset	0	R 1.4
Homing - Maximum trigger speed (previously *Max. trigger speed (units/s)*)	[units/s]	Maximum permissible speed for evaluating the reference switch / reference pulse	0	R 1.4
Homing - Monitoring time (previously *Homing Monitoring Time (µs)*)	[µs]	Monitoring time for the homing procedure	0	R 1.4
Homing - Mode (previously *Mode*)	Direct / Reference switch / *Home Offset / Home offset with correction*	Selects the homing mode *Modes "Home offset" and "Home offset with correction" are only available for ACOPOSmulti SafeMOTION EnDat 2.2!*	Direct	R 1.4
Homing - Edge of reference switch (previously *Edge of reference switch*)	Positive / Negative	Selects the switching edge for the reference switch The switching edge for the reference switch input is positive if the logical state of the reference switch changes from SAFEFALSE to SAFETRUE in the positive direction of movement.	Positive	R 1.4
Homing - Trigger direction (previously *Trigger direction*)	Positive / Negative	Selects the trigger direction If the homing procedure requires a movement, then this parameter specifies the direction for evaluating the reference switch / reference pulse.	Positive	R 1.4
Homing - Enable reference pulse *(previously Reference pulse)*	*Enabled/ Disabled*	*Selects whether or not to use a reference pulse for homing* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2!*	*Disabled*	R 1.4
Homing - Blocking distance *(previously Blocking distance (% encoder reference system))*	*%*	*Distance within which evaluation of the reference pulse will be suppressed.* *This is calculated starting at the configured reference switch edge and indicated as a percentage of the encoder reference system.* *A single revolution is used as the encoder reference system for rotary encoders.* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2!*	*0*	R 1.4

Table 555: SafeMOTION parameter group: Absolute position functions - Homing

Group: Absolute position functions - SMP/SLP (previously *Safety Position Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SMP - Enable (previously *Safe Maximum Position*)	Enabled/ Disabled	Activates the SMP safety function from the configuration **Value** – **Description** Enabled – SMP is activated Disabled – SMP is deactivated	Disabled	R 1.4
SMP - Lower position limit (previously *Safe Lower Position Limit for SMP (units)*)	[units]	Lower position limit for the machine's full travel range	0	R 1.4
SMP - Upper position limit (previously *Safe Upper Position Limit for SMP (units)*)	[units]	Upper position limit for the machine's full travel range	0	R 1.4
SLP - Lower position limit (previously *Safe Lower Position Limit for SLP (units)*)	[units]	Lower position limit for the monitoring range	0	R 1.4
SLP - Upper position limit (previously *Safe Upper Position Limit for SLP (units)*)	[units]	Upper position limit for the monitoring range	0	R 1.4
SLP - Enable delay time (previously *Delay time to start SLP (us)*)	[µs]	Delay time between the SLP request and start of monitoring	0	R 1.4

Table 556: SafeMOTION parameter group: Absolute position functions - SMP/SLP

Group: General settings - Behavior of Functional Fail Safe (FFS) (previously *Behavior of Functional Fail Safe*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Used Starting in Safety Release</th></tr>
<tr><td>FFS - Mode

(previously Behavior of Functional Fail Safe)</td><td>STO /
STO1 and STO with time delay</td><td>In the FUNCTIONAL FAIL SAFE state, STO and SBC are activated immediately, or STO1 is activated and then STO after a delay.<table><tr><th>Value</th><th>Description</th></tr><tr><td>STO</td><td>In the FUNCTIONAL FAIL SAFE state, STO and SBC are activated immediately.</td></tr><tr><td>STO1 and STO with time delay</td><td>In the FUNCTIONAL FAIL SAFE state, STO1 and SBC are activated first, and then STO after a delay.</td></tr></table></td><td>STO</td><td>R 1.3</td></tr>
<tr><td>FFS - STO Enable delay time

(previously Delay for STO in Functional Fail Safe [µs])</td><td>[µs]</td><td>Delay time between STO1 and STO (and SBC) in the FUNCTIONAL FAIL SAFE state</td><td>0</td><td>R 1.3</td></tr>
<tr><td>FFS - Delay time until brake engages

(previously Delay time until the brake engages [µs])</td><td>[µs]</td><td>Delay time before the brake engages
The second enable channel is activated after this delay time if STO1 and time-delayed STO and SBC are configured for FUNCTIONAL FAIL SAFE.</td><td>0</td><td>R 1.3</td></tr>
<tr><td>FFS - Caused by encoder error
(1.10.1.x for ACOPOSmulti SafeMOTION and hardware upgrade 1.10.2.x or later for ACOPOS P3 SafeMOTION)</td><td>Always / Only if safety functions requiring an encoder are enabled</td><td>Enable FUNCTIONAL FAIL SAFE on encoder error:
Always:
FFS occurs if at least one safety function that requires an encoder is used and an encoder error is present.
Only if safety functions requiring an encoder are enabled:
FFS occurs if at least one safety function that requires an encoder is active and an encoder error is present.</td><td>Always</td><td>R 1.10.1</td></tr>
</table>

Table 557: SafeMOTION parameter group: General settings - Behavior of Functional Fail Safe (FFS)

In a safety application, it is possible for multiple safety functions to be requested at the same time. In order to prevent this from turning into an unsafe situation, the individual safety functions are prioritized on the SafeMOTION module.

If several functions are active, then the lowest speed limit is always the value being monitored.

Information:

The following application rule must be observed:

$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS} \leq$ EUS - Maximum speed to normalize speed range

This is required for setting priority of the safety functions on the SafeMOTION module.

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

In a safety application, it is possible for multiple safety functions to be requested at the same time. In order to prevent this from turning into an unsafe situation, the individual safety functions are prioritized on the SafeMOTION module.

If several functions are active, then the lowest speed limit is always the value being monitored.

Information:

The following application rule must be observed:

$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS} \leq$ EUS - Maximum speed to normalize speed range

This is required for setting priority of the safety functions on the SafeMOTION module.

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

8.7.3 Integrated safety functions

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

8.7.4 Safe encoder connection

See 6.2.3.3 "Safe encoder connection" on page 307.

8.7.5 Fault avoidance

See 7.3.4 "Fault avoidance" on page 503.

8.7.6 Input parameters

> **Information:**
>
> **For detailed information about individual safety functions, see "SafeMOTION user's manual / chapter "Safety technology" / Integrated safety functions"!**

8.7.6.1 General information about "S_Control" inputs

"S_Control" inputs are used to request the respective safety functions.

> **Information:**
>
> **If a safety function is not used in the application, then the respective input must remain open.**

> **Danger!**
>
> **The safety functions that are used must be tested.**
> **A function is considered to be used if the respective input variable is connected!**

> **Information:**
>
> **To enable the function block itself and assign the functions to a defined axis, inputs "Activate" and "S_AxisID" must be connected at a minimum.**

> **Information:**
>
> **It is mandatory for function block SF_oS_MOTION_Basic_BR (or alternatively, function block SF_oS_MOTION_BR) to be applied to each axis being used in the safety application.**
>
> **In addition to inputs "Activate" and "S_AxisID", inputs "S_Control_Reset" and "S_Control_Activate" must also be used. Otherwise, the SafeDESIGNER project cannot be compiled.**

8.7.6.2 Activate

General function

- Enables the function block

Data type

- BOOL

Connection

- Constant or variable

Function description

This input parameter is used to activate the function block.

- When enabling or disabling safe devices, "Activate" must be linked to a variable that indicates the state (enabled or disabled) of the corresponding safe devices. This ensures that the function block does not output a triggered safety function as diagnostic information when a device is switched off.
- It is also possible to connect "Activate" to a constant (TRUE) in order to enable the function block.

TRUE

The function block is enabled.

FALSE

The function block is not enabled.
All binary output parameters are set to FALSE.
Sets the DiagCode diagnostic parameter to WORD#16#0000.

If you want to control function block diagnostics as needed in your diagnostic concept whenever error messages from safe devices and/or deactivated safe devices occur, connect "Activate" to a signal that indicates the status of the safe devices that are involved with the safety function supported by the function block. Form this signal using only safe devices whose I/O signals are connected to the function block via actual parameters. In this way, you prevent triggered safety functions from being reported by active safe devices. This measure is only used to control the diagnostic information from inactive safe devices in a defined manner.

8.7.6.3 S_Control_Homing

General function

- Selects/Deselects safety function "Safe Homing"

Data type

- SAFEBOOL

Connection

- Variable

Function description

This input parameter is used to start a "Safe Homing" procedure. A positive edge of the input starts the safety function.

Positive edge: Change from SAFEFALSE to SAFETRUE

Starts "Safe Homing".

Negative edge: Change from SAFETRUE to SAFEFALSE

If still active, the homing procedure will be terminated by the negative edge. This state transition has no effect if the homing procedure has already been completed.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Absolute position functions - Homing (previously *Homing*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Mode (previously *Mode*)	Direct / Reference switch / *Home Offset /* *Home offset with correction*	Selects the homing mode *Modes "Home offset" and "Home offset with correction" are only available for ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	Direct	R 1.4
Homing - Home position or home offset (previously *Home Position or Home Offset (units)*)	[units]	Home position or home offset	0	R 1.4
Homing - Enable RSP (Remanent safe position) *(previously Remanent safe position)*	*Enabled/* *Disabled*	*Selects whether or not to use the remanent safe position* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*Disabled*	R 1.9
Homing - Edge of reference switch (previously *Edge of reference switch*)	Positive / Negative	Selects the switching edge for the reference switch The switching edge for the reference switch input is positive if the logical state of the reference switch changes from SAFEFALSE to SAFETRUE in the positive direction of movement.	Positive	R 1.4
Homing - Trigger direction (previously *Trigger direction*)	Positive / Negative	Selects the trigger direction If the homing procedure requires a movement, then this parameter specifies the direction for evaluating the reference switch / reference pulse.	Positive	R 1.4

Table 558: SafeMOTION parameter group: Absolute position functions - Homing

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Enable reference pulse *(previously Reference pulse)*	*Enabled/ Disabled*	*Selects whether or not to use a reference pulse for homing* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*Disabled*	R 1.4
Homing - Blocking distance *(previously Blocking distance (% encoder reference system))*	*%*	*Distance within which evaluation of the reference pulse will be suppressed.* *This is calculated starting at the configured reference switch edge and indicated as a percentage of the encoder reference system.* *A single revolution is used as the encoder reference system for rotary encoders.* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*0*	R 1.4
Homing - Maximum trigger speed (previously *Max. trigger speed (units/s)*)	[units/s]	Maximum permissible speed for evaluating the reference switch / reference pulse	0	R 1.4
Homing - Monitoring time (previously *Homing Monitoring Time (µs)*)	[µs]	Monitoring time for the homing procedure	0	R 1.4

Table 558: SafeMOTION parameter group: Absolute position functions - Homing

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

The Safe Homing function is needed in order to implement the safety functions SLP and SMP and for using the safe position.
The "SafePositionValid" status bit will remain set to SAFEFALSE until safe homing has been performed!

8.7.6.4 S_Control_RefSwitch

General function

- Reference switch input for safety function "Safe Homing"

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter serves as a reference switch input for the "Safe Homing" safety function and is only evaluated in the "Reference Switch" homing mode.
The status of a safe reference switch that was read into the safety application via a safe input module (X20SIxxxx), for example, should be linked to the input.

Not connected

The reference switch is not being used!

> ## Information:
>
> **If "Reference Switch" homing mode is configured and the reference switch input "S_ReferenceSwitch" is not wired on the function block, then the SafeMOTION module will switch to the FAIL SAFE state. The only way to exit the FAIL SAFE state is to complete a power off/on cycle and modify the safety application!**

> ## Information:
>
> **Input "S_Control_RefSwitch" is only evaluated in homing mode "Reference Switch".
> The input is ignored in other homing modes!**

8.7.6.5 S_Control_SwitchHomingMode

General function

- This input is used by safety function "Remanent Safe Position" and enables a homing procedure that confirms the remanent safe position.

Data type

- SAFEBOOL

Connection

- Variable

Function description

This input parameter is used to switch between homing with RSP and the configured homing mode.

SAFETRUE

When a homing command is given (i.e. positive edge on input "S_Control_RequestHoming"), then homing mode "Homing with RSP" is used.

SAFEFALSE

When a homing command is given (i.e. positive edge on input "S_Control_RequestHoming"), then the configured homing mode is used.

Relevant configuration parameters

Parameter	Unit	Description	Default value
Homing			
Remanent Safe Position	*Enabled/ Disabled*	*Selects whether or not to use the remanent safe position* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2!*	*Disabled*
Safety Standstill and Direction Tolerances			
Speed Tolerance	[units/s]	Speed tolerance for standstill monitoring	0
Position Tolerance	[units]	Position tolerance for standstill and direction monitoring	0

Table 559: RSP safety function - Parameters

8.7.6.6 S_Control_SLP

General function

- Selects/Deselects safety function Safely Limited Position, SLP

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLP safety function.

SAFETRUE

The safety function is deselected. SLP is not active!

SAFEFALSE

The configured position window will be safety-monitored after "Delay time to start SLP (us)".

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 560: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Absolute position functions - SMP/SLP (previously *Safety Position Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLP - Lower position limit (previously *Safe Lower Position Limit for SLP (units)*)	[units]	Lower position limit for the monitoring range	0	R 1.4
SLP - Upper position limit (previously *Safe Upper Position Limit for SLP (units)*)	[units]	Upper position limit for the monitoring range	0	R 1.4
SLP - Enable delay time (previously *Delay time to start SLP (us)*)	[µs]	Delay time between the SLP request and start of monitoring	0	R 1.4

Table 561: SafeMOTION parameter group: Absolute position functions - SMP/SLP

Danger!

The position limits being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement, a dangerous movement cannot occur in the event of a worst case scenario.

The dangerous movement must be determined by a risk analysis.

Information:

The following application rule must be observed:

$LIM_{SMP,NEG} \leq LIM_{SLP,NEG} \leq LIM_{SLP,POS} \leq LIM_{SMP,POS}$

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 562: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

The following application rule must be observed:
$LIM_{SMP,NEG} \leq LIM_{SLP,NEG} \leq LIM_{SLP,POS} \leq LIM_{SMP,POS}$
Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

Information:

Safe homing of the axis must be completed prior to using this safety function.
If a homing procedure is not completed successfully or the "S_SafePositionValid" status changes, then the request for the SLP safety function causes the module to switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state.
The drive loses all torque/power and coasts to a stop! In the event of an error, a synchronous axis will no longer be synchronous. The output of function block "S_NotErrFUNC" is reset.

8.7.6.7 S_AxisID

General function

- This input parameter assigns a real axis to the function block.

Data type

- SAFEINT

Connection

- Constant

Function description

The corresponding axis can be connected to the input in SafeDESIGNER using drag-and-drop.

> ## Information:
>
> **There is only permitted to be one combination of AxisID and function block SF_oS_MOTION_Advanced_BR or SF_oS_MOTION_BR in the safety application. Otherwise, it will not be possible to compile the safety application.**

8.7.7 Output parameters

Output parameters provide information about the state of the SafeMOTION module and the individual safety functions.

8.7.7.1 Ready

General function

- Message: Function block is enabled/disabled.

Data type

- BOOL

Connection

- Variable

Function description

This output parameter indicates whether the function block is enabled or not.

TRUE

The function block is enabled ("Activate" = TRUE). The output parameters indicate the current state of the safety function.

FALSE

The function block is not enabled ("Activate" = FALSE). The function block outputs are set to FALSE.

8.7.7.2 S_Status_Homing

General function

- Status information for safety function "Safe Homing" and the safe position

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies whether or not safe homing of the axis has been completed and whether or not the position signal is valid.

SAFETRUE

The axis has been safely homed, and the safe position is valid.

SAFEFALSE

The axis has not yet been successfully homed; the encoder signal of the axis is faulty. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.
The safe position is invalid!

> **Danger!**
>
> **The purpose of this signal is only to provide additional information.**
>
> **"S_Status_Homing" does not represent the functional safe state of the SafeMOTION module!**

> **Danger!**
>
> **The value of output parameter "S_SafePosition_4Byte" is only valid if output parameter S_SafePositionValid is SAFETRUE. Otherwise, it is invalid and is not permitted to be used further.**

8.7.7.3 S_Status_ReqHomingOK

General function

- Feedback for homing in SafeDESIGNER

Data type

- SAFEBOOL

Connection

- Variable

Function description

This status is set to provide feedback in the event that homing is requested when already in a homed state ("S_Control_Homing" and "S_Status_Homing" are set).

SAFETRUE

The input for homing is set ("S_Control_Homing" = SAFETRUE), and the safe position is valid ("S_Status_Homing" = SAFETRUE).

SAFEFALSE

The input for homing is not set or the safe position is not valid. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.7.7.4 S_Status_EncStatus2

General function

- Information about the error state of the safe encoder signal

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the error state of the signal for a defined safe encoder.
If an encoder error is detected or the SafeMOTION module is in an error state, then the output is set to FALSE.
This state is maintained until the error has been corrected.

SAFETRUE

An error was not detected on the encoder signal.

SAFEFALSE

The encoder signal from a defined safe axis is faulty, or the axis itself is in an error state. For more information about the error, see the Safety Logger in Automation Studio.

> **Danger!**
>
> **The purpose of this signal is only to provide additional information. It only provides information in connection with the requested safety functions.**
> **"S_Status_EncStatus2" does not represent the functional safe state of the SafeMOTION module!**

8.7.7.5 S_Status_SLP

General function

- Status information for safety function Safely Limited Position, SLP

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLP safety function

SAFETRUE

The SLP safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.7.7.6 S_Status_SMP

General function

- Status information for safety function Safe Maximum Position, SMP

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SMP safety function

SAFETRUE

The SMP safety function is active and currently in its safe state.

SAFEFALSE

Monitoring of the SMP position limits is not active. Monitoring is not yet active since the SafeMOTION module has not yet been homed. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.7.7.7 S_Status_RSPValid

General function

- Status information for the "Remanent safe position" safety function

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the following:

- The current safe position has been homed, validated and saved.
- Changes to the safe position are prevented by the active STO and SOS safety functions.
- Powering off the module does not result in loss of the safe remanent position.

SAFETRUE

The safe position has been saved successfully. Power off for homing with RSP is possible in this state.

SAFEFALSE

One or more of the following is true:

- The axis was not successfully homed. (The state of "S_Status_Homing" is not TRUE.)
- The STO safety function is not selected/active.
- The SOS safety function is not selected/active.
- The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.7.7.8 S_Status_SetPosAlive

General function

- Status information about plausibility check of the position setpoint

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies whether the plausibility of the position setpoint has been checked.

SAFETRUE

The plausibility of the position setpoint was checked successfully.

SAFEFALSE

The plausibility of the position setpoint was faulty or not checked. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.7.7.9 Error

General function

- Function block error message

Data type

- BOOL

Connection

- Variable

Function description

This formal parameter indicates a pending function block error message.

TRUE

The enabled function block detected an error. "DiagCode" indicates the error code.

FALSE

The function block is not enabled, or the enabled function block did not detect an error. "DiagCode" indicates the status.

> ## Danger!
>
> **It is your responsibility to ensure that all necessary corrective measures are initiated after an error occurs since subsequent errors can result in a hazard!**

In order to exit an error state ("Error" = TRUE), the signal on input "S_Control_Reset" must change from SAFE-FALSE to SAFETRUE (positive edge).

8.7.7.10 DiagCode

General function

- Function block diagnostic message

Data type

- WORD

Connection

- Variable

Function description

This output parameter is used to output diagnostic and status messages specific to the function block and make them available automatically to diagnostic tools.

These diagnostic tools cannot acknowledge diagnostic messages from function blocks. This is done exclusively in the **safety** application.

The function block indicates the presence of an error message on the "DiagCode" output via the "Error" output parameter.

Diagnostic code

The diagnostic code is specified as data type WORD. The values and meanings of these diagnostic codes are listed below.

In the event of status messages ($0xxx_{hex}$, $8xxx_{hex}$), the function block sets "Error" to FALSE.

In the event of error messages ($Cxxx_{hex}$), the function block sets "Error" to TRUE.

8.7.7.11 Overview of diagnostic codes

Diagnostic codes

Code (hex)	Description	Corrective measures
0000	The function block is not enabled. If "Activate" is connected to a variable that indicates the state of the connected safe device (active, inactive or peripheral fault detected), then the safe device is not active or has detected a fault in the connected peripheral.	• Enable the function block by setting "Activate" to SAFETRUE. • Enable the safe device if "Activate" is connected to a variable that indicates the state of a connected safe device (active, inactive or peripheral fault detected), or correct the fault in the peripheral according to the device description.
8000	The function block detected neither a status nor an error to set the enable output to SAFEFALSE.	• If this is a desired signal combination at the signal inputs, no action is required. • If the signal combination on the signal inputs is unintended, check the connected peripheral and correct any faults.
C001	The function set for the control byte was not found.	Check whether the required safety function is supported by the connected axis.
C002	The function set for the status byte was not found.	Check whether the required safety function is supported by the connected axis.
C003	The function set ID that was read does not match.	Check whether the required safety function is supported by the connected axis.
C004	The data length of the function set that was read is invalid.	Check whether the required safety function is supported by the connected axis.
C005	The status byte could not be read.	Check whether the required safety function is supported by the connected axis.
C006	The control byte could not be written.	Check whether the required safety function is supported by the connected axis.

Table 563: SF_oS_MOTION_(Basic, Speed, Advanced, AbsPos)_BR: Diagnostic codes

8.7.8 Signal sequence diagram of the function block

A general signal sequence diagram of the function block cannot be specified since it depends on which safety functions are selected or deselected.

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

8.8 SF_oS_MOTION_BR

	SF_oS_MOTION_BR		
BOOL	Activate	Ready	BOOL
SAFEINT	S_AxisID	Error	BOOL
SAFEBOOL	S_Control_Reset	DiagCode	WORD
SAFEBOOL	S_Control_Activate	S_Status_NotErrFunc	SAFEBOOL
SAFEBOOL	S_Control_STO	S_Status_Operational	SAFEBOOL
SAFEBOOL	S_Control_SBC	S_Status_STO	SAFEBOOL
SAFEBOOL	S_Control_SS1	S_Status_SBC	SAFEBOOL
SAFEBOOL	S_Control_STO1	S_Status_SS1	SAFEBOOL
SAFEBOOL	S_Control_SOS	S_Status_STO1	SAFEBOOL
SAFEBOOL	S_Control_SS2	S_Status_SDC	SAFEBOOL
SAFEBOOL	S_Control_SLA	S_Status_EncStatus	SAFEBOOL
SAFEBOOL	S_Control_SLS-1	S_Status_SOS	SAFEBOOL
SAFEBOOL	S_Control_SLS-2	S_Status_SS2	SAFEBOOL
SAFEBOOL	S_Control_SLS-3	S_Status_SLA	SAFEBOOL
SAFEBOOL	S_Control_SLS-4	S_Status_SLS-1	SAFEBOOL
SAFEBOOL	S_Control_SDI-P	S_Status_SLS-2	SAFEBOOL
SAFEBOOL	S_Control_SDI-N	S_Status_SLS-3	SAFEBOOL
SAFEBOOL	S_Control_SLI	S_Status_SLS-4	SAFEBOOL
SAFEBOOL	S_Control_SBT	S_Status_SDI-P	SAFEBOOL
SAFEBOOL	S_Control_SLT	S_Status_SDI-N	SAFEBOOL
SAFEBOOL	S_Control_Homing	S_Status_SLI	SAFEBOOL
SAFEBOOL	S_Control_RefSwitch	S_Status_SBT	SAFEBOOL
SAFEBOOL	S_Control_SwitchHomingMode	S_Status_SBT-Active	SAFEBOOL
SAFEBOOL	S_Control_SLP	S_Status_SLT	SAFEBOOL
		S_Status_Homing	SAFEBOOL
		S_Status_ReqHomingOK	SAFEBOOL
		S_Status_EncStatus2	SAFEBOOL
		S_Status_SLP	SAFEBOOL
		S_Status_SMP	SAFEBOOL
		S_Status_RSPValid	SAFEBOOL
		S_Status_SetPosAlive	SAFEBOOL

Figure 128: Function block "SF_oS_MOTION_BR"

Information:

Library openSAFETY_BuR_Motion_SF can only be used to control ACOPOS P3 SafeMOTION servo drives.

Information:

This function block provides access to all available function sets.

If this function block is used in SafeDESIGNER, then the same "S_AxisID" is not permitted to be simultaneously used with function block SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR or SF_oS_MOTION_AbsPos_BR!

8.8.1 Formal parameters of the function block

In the following, the term "variable" refers to both a variable as well as a graphic connection.

Name	Type	Connection	Signal type [1]	Initial value	Description / General function
Activate	BOOL	Variable/ Constant	State	FALSE	Enables the function block (= TRUE) Input "Activate" according to the PLCopen standard
S_AxisID	SAFEINT	Constant	State	-1	Assigns an axis to the function block
S_Control_Reset	SAFEBOOL	Variable/ Constant	Edge	SAFEFALSE	Resets error messages and the SafeMOTION module after the cause of the error has been removed
S_Control_Activate	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	SAFETRUE: Starts the state machine of the safe axis, safety functions can be enabled. SAFEFALSE: Sets the state machine of the safe axis to state IDLE
S_Control_STO	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safe Torque Off (STO). SAFEFALSE: Safety function requested
S_Control_SBC	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safe Brake Control (SBC). SAFEFALSE: Safety function requested
S_Control_SS1	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safe Stop 1 (SS1). SAFEFALSE: Safety function requested
S_Control_STO1	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safe Torque Off, One Channel (STO1). SAFEFALSE: Safety function requested
S_Control_SOS	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safe Operating Stop (SOS). SAFEFALSE: Safety function requested
S_Control_SS2	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safe Stop 2 (SS2). SAFEFALSE: Safety function requested
S_Control_SLA	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safely Limited Acceleration (SLA). SAFEFALSE: Safety function requested
S_Control_SLS-1	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safely Limited Speed, Speed Limit 1 (SLS-1). SAFEFALSE: Safety function requested
S_Control_SLS-2	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safely Limited Speed, Speed Limit 2 (SLS-2). SAFEFALSE: Safety function requested
S_Control_SLS-3	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safely Limited Speed, Speed Limit 3 (SLS-3). SAFEFALSE: Safety function requested
S_Control_SLS-4	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safely Limited Speed, Speed Limit 4 (SLS-4). SAFEFALSE: Safety function requested
S_Control_SDI-P	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safe Direction (SDI). Movement in the positive direction is allowed. SAFEFALSE: Safety function requested
S_Control_SDI-N	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safe Direction (SDI). Movement in the negative direction is allowed. SAFEFALSE: Safety function requested
S_Control_SLI	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safely Limited Increment (SLI). SAFEFALSE: Safety function requested
S_Control_SBT	SAFEBOOL	Variable/ Constant	Edge	SAFEFALSE	Request for safety function Safe Brake Test (SBT). The request is made on a falling edge!
S_Control_SLT	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safely Limited Torque (SLT) SAFEFALSE: Safety function requested
S_Control_Homing	SAFEBOOL	Variable	Edge	SAFEFALSE	Request for safe homing. The request is made on a rising edge!
S_Control_RefSwitch	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Safe input for a reference switch
S_Control_SwitchHomingMode	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Enables homing with remanent safe position (RSP). SAFEFALSE: Homing with RSP disabled.
S_Control_SLP	SAFEBOOL	Variable/ Constant	State	SAFEFALSE	Request for safety function Safely Limited Position (SLP). SAFEFALSE: Safety function requested

Table 564: "SF_oS_MOTION_BR": Overview of input parameters

1) Evaluation of the input parameter signals in the function block. You must control the signals accordingly.

Name	Type	Connection	Signal type 1)	Initial value	Description / General function
Ready	BOOL	Variable	State	FALSE	Indicates that the function block is enabled Output "Ready" according to the PLCopen standard
Error	BOOL	Variable	State	FALSE	Function block error message
DiagCode	WORD	Variable	State	16#0000	Function block diagnostic message
S_Status_NotErrFunc	SAFEBOOL	Variable	State	SAFEFALSE	SafeMOTION module not in state FUNCTIONAL FAIL SAFE (i.e. SAFETRUE)
S_Status_Operational	SAFEBOOL	Variable	State	SAFEFALSE	Status of the state machine of the safe axis SAFEFALSE: State machine not in state OPERATION-AL SAFETRUE: State machine in state OPERATIONAL
S_Status_STO	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safe Torque Off (STO) is active (i.e. SAFETRUE).
S_Status_SBC	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safe Brake Control (SBC) is active (i.e. SAFETRUE).
S_Status_SS1	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safe Stop 1 (SS1) is active, deceleration monitoring is completed, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_STO1	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safe Torque Off, One Channel (STO1) is active (i.e. SAFETRUE).
S_Status_SDC	SAFEBOOL	Variable	State	SAFEFALSE	Deceleration monitoring is active (i.e. SAFETRUE).
S_Status_EncStatus	SAFEBOOL	Variable	State	SAFEFALSE	No encoder error has been detected (i.e. SAFETRUE), signal "S_ScaledSpeed" is valid.
S_Status_SOS	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safe Operating Stop (SOS) active, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_SS2	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safe Stop 2 (SS2) is active, deceleration monitoring is completed, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_SLA	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safely Limited Acceleration (SLA) ac-tive, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_SLS-1	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safely Limited Speed, Speed Limit 1 (SLS-1) is active, deceleration monitoring is completed, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_SLS-2	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safely Limited Speed, Speed Limit 2 (SLS-2) is active, deceleration monitoring is completed, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_SLS-3	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safely Limited Speed, Speed Limit 3 (SLS-3) is active, deceleration monitoring is completed, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_SLS-4	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safely Limited Speed, Speed Limit 4 (SLS-4) is active, deceleration monitoring is completed, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_SDI-P	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safe Direction (SDI, positive direction) active (i.e. SAFETRUE)
S_Status_SDI-N	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safe Direction (SDI, negative direction) active (i.e. SAFETRUE)
S_Status_SLI	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safely Limited Increment (SLI) active, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_SBT	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safe Brake Test (SBT) completed suc-cessfully, status of test is valid (i.e. SAFETRUE)
S_Status_SBT-Active	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safe Brake Test (SBT) active (i.e. SAFETRUE)
S_Status_SLT	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safely Limited Torque (SLT) active, no violation of a monitored limit (i.e. SAFETRUE)
S_Status_Homing	SAFEBOOL	Variable	State	SAFEFALSE	Specifies whether the safe position is valid (i.e. SAFETRUE, homing procedure has completed suc-cessfully and there are no encoder errors)
S_Status_ReqHomingOK	SAFEBOOL	Variable	State	SAFEFALSE	Feedback for homing in SafeDESIGNER (i.e. SAFETRUE, safe position is valid and request for safe homing is SAFETRUE)
S_Status_EncStatus2	SAFEBOOL	Variable	State	SAFEFALSE	No encoder error has been detected (i.e. SAFETRUE), signal "S_ScaledSpeed" is valid.
S_Status_SLP	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safely Limited Position (SLP) active (i.e. SAFETRUE)
S_Status_SMP	SAFEBOOL	Variable	State	SAFEFALSE	Safety function Safe Maximum Position (SMP) active (i.e. SAFETRUE)
S_Status_RSPValid	SAFEBOOL	Variable	State	SAFEFALSE	Validates and stores the remanent safe position (RSP) (TRUE = safe position is stored, power off for homing with RSP is now possible)
S_Status_SetPosAlive	SAFEBOOL	Variable	State	SAFEFALSE	Status information about plausibility check of the posi-tion setpoint

Table 565: "SF_oS_MOTION_BR": Overview of output parameters

1) Output of the output parameter signals. You must evaluate and/or further process the signals accordingly.

Type	Description	Size in bits	Format option
BOOL	Bit	1	Bit string
WORD	Word	16	Bit string
DINT	Double integer	32	Binary number, hexadecimal number, signed decimal number
SAFEBOOL	Bit	1	Bit string (signal source: safe device)
SAFEDWORD	Double word	32	Bit string (signal source: safe device)
SAFEDINT	Double integer	32	Binary number, hexadecimal number, signed decimal number (signal source: safe device)
SAFEINT	Integer	16	Binary number, hexadecimal number, signed decimal number (signal source: safe device)

Table 566: Format description of the data types

You have the option of linking a safe signal with a non-safe input parameter. To do so, use a function block for type conversion.

Caution!

You are responsible for any conversion of a non-safe input parameter to a safe signal.

8.8.2 SafeMOTION module parameters

Group: General settings - Automatic reset on start (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Used Starting in Safety Release</th></tr>
<tr><td>Automatic reset on start - Enable

(previously Automatic Reset at Startup)</td><td>Enabled/
Disabled</td><td>Activates automatic reset of the function block at startup
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>After startup, the module automatically changes to state OPERATIONAL (Startreset). The reset input does not have to be controlled!</td></tr>
<tr><td>Disabled</td><td>After startup, the module remains in an Init state until a positive edge of the reset input is detected.</td></tr>
</table></td><td>Disabled</td><td>R1.3</td></tr>
</table>

Table 567: SafeMOTION parameter group: General settings - Automatic reset on start

Group: General settings - Behavior of Functional Fail Safe (FFS) (previously *Behavior of Functional Fail Safe*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Used Starting in Safety Release</th></tr>
<tr><td>FFS - Mode

(previously Behavior of Functional Fail Safe)</td><td>STO /
STO1 and STO with time delay</td><td>In the FUNCTIONAL FAIL SAFE state, STO and SBC are activated immediately, or STO1 is activated and then STO after a delay.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>STO</td><td>In the FUNCTIONAL FAIL SAFE state, STO and SBC are activated immediately.</td></tr>
<tr><td>STO1 and STO with time delay</td><td>In the FUNCTIONAL FAIL SAFE state, STO1 and SBC are activated first, and then STO after a delay.</td></tr>
</table></td><td>STO</td><td>R 1.3</td></tr>
<tr><td>FFS - STO Enable delay time

(previously Delay for STO in Functional Fail Safe [µs])</td><td>[µs]</td><td>Delay time between STO1 and STO (and SBC) in the FUNCTIONAL FAIL SAFE state</td><td>0</td><td>R 1.3</td></tr>
<tr><td>FFS - Delay time until brake engages

(previously Delay time until the brake engages [µs])</td><td>[µs]</td><td>Delay time before the brake engages
The second enable channel is activated after this delay time if STO1 and time-delayed STO and SBC are configured for FUNCTIONAL FAIL SAFE.</td><td>0</td><td>R 1.3</td></tr>
<tr><td>FFS - Caused by encoder error
(1.10.1.x for ACOPOSmulti SafeMOTION and hardware upgrade 1.10.2.x or later for ACOPOS P3 SafeMOTION)</td><td>Always / Only if safety functions requiring an encoder are enabled</td><td>Enable FUNCTIONAL FAIL SAFE on encoder error:
Always:
FFS occurs if at least one safety function that requires an encoder is used and an encoder error is present.
Only if safety functions requiring an encoder are enabled:
FFS occurs if at least one safety function that requires an encoder is active and an encoder error is present.</td><td>Always</td><td>R 1.10.1</td></tr>
</table>

Table 568: SafeMOTION parameter group: General settings - Behavior of Functional Fail Safe (FFS)

Group: General settings - Encoder Unit System (previously *Encoder Unit System*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>EUS - Count of physical reference system

(previously Count of physical reference system)</td><td>-</td><td>Rotary encoder unit scale: X revolutions
Linear encoder unit scale: X reference lengths (reference length = length of the physical reference system)

Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration).
For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.</td><td>1</td><td>R 1.4</td></tr>
<tr><td>EUS - Units per count of physical reference system

(previously Units per count of physical reference system [units])</td><td>[units]</td><td>Rotary encoder unit scale: Units per x revolutions
Linear encoder unit scale: Units per x reference lengths

Any unit (mm, 1/100 mm, 1/20 inch, degree of angle, etc.) can be used for positions (and data that can result such as speed and acceleration).
For this reason, the relationship between an integer multiple of this unit (units per x revolutions / units per x reference lengths) and a certain number of x revolutions / x reference lengths has to be previously defined.</td><td>1000</td><td>R 1.4</td></tr>
<tr><td>EUS - Counting direction

(previously Counting direction)</td><td>Standard / Inverse</td><td>Counting direction of the position or speed<table><tr><th>Value</th><th>Description</th></tr><tr><td>Default</td><td>Encoder counting direction is equal to the counting direction of the unit system.</td></tr><tr><td>Inverse</td><td>Encoder counting direction is negative to the counting direction of the unit system.</td></tr></table></td><td>Default</td><td>R 1.3</td></tr>
<tr><td>EUS - Length of physical reference system for linear encoder

(previously Length of physical reference system for linear encoder (nm))</td><td>[nm]</td><td>For linear measurement systems, the length of a physical reference system is defined here.
This value is not used for rotary encoders, where the reference system is a single revolution.</td><td>1000000000</td><td>R 1.4</td></tr>
<tr><td>EUS - Maximum speed to normalize speed range

(previously Maximum speed to normalize the speed range (units/s))</td><td>[units/s]</td><td>Maximum speed to which the displayed speed should be normalized</td><td>32767</td><td>R 1.3</td></tr>
<tr><td>EUS - Encoder acceleration limit

(previously Maximum acceleration (rad/s² or mm/s²))</td><td>[rad/s²] or [mm/s²]</td><td>Maximum permissible encoder acceleration</td><td>100000</td><td>R 1.4</td></tr>
</table>

Table 569: SafeMOTION parameter group: General settings - Encoder Unit System

Group: General settings - Encoder monitoring (previously *Encoder Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Encoder monitoring - Safe Encoder Mounting (Hardware upgrade 1.10.3.x and later)</td><td>From motor data record / Approved by user</td><td>Status of the proof of fatigue strength of the encoder mounting<table><tr><th>Value</th><th>Description</th></tr><tr><td>From motor data record</td><td>The status of the encoder mounting is determined using the motor data record.</td></tr><tr><td>Approved by user</td><td>The user confirms safe encoder mounting / no mounting information available in the motor data record.</td></tr></table></td><td>From motor data record</td><td>R1.10</td></tr>
<tr><td>Encoder monitoring - Position error monitoring - Enable

(previously Encoder Position monitoring)</td><td>Enabled/ Disabled</td><td>Enables/Disables monitoring of the position lag error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error monitoring - Enable

(previously Encoder Speed monitoring)</td><td>Enabled/ Disabled</td><td>Activates/Deactivates monitoring of the speed error generated on the SafeMOTION module<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Enabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position setpoint alive testing (SPA) - Enable

(previously Set position alive testing)</td><td>Enabled/ Disabled</td><td>Activates/Deactivates the monitor that detects whether the position setpoint generated on the SafeMOTION module is frozen.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>Monitoring active</td></tr><tr><td>Disabled</td><td>Monitoring not active</td></tr></table></td><td>Disabled</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Position error tolerance

(previously Encoder monitoring Position tolerance (units))</td><td>[units]</td><td>Position lag error tolerance for shaft breakage monitoring</td><td>0</td><td>R1.3</td></tr>
<tr><td>Encoder monitoring - Speed error tolerance

(previously Encoder monitoring Speed tolerance (units/s))</td><td>[units/s]</td><td>Speed error tolerance for encoder monitoring</td><td>0</td><td>R1.3</td></tr>
</table>

Table 570: SafeMOTION parameter group: General settings - Encoder monitoring

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 571: SafeMOTION parameter group: General settings - Standstill monitoring

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/ Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr><tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr></table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 572: SafeMOTION parameter group: General settings - Early limit monitoring

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 573: SafeMOTION parameter group: General settings - Ramp monitoring

Group: Basic functions - STO1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>STO1 - Channel

(previously Channel selection for One Channel STO (STO1))</td><td>High-side/
Low-side</td><td>Selects the high-side or low-side IGBT in the STO1 function<table><tr><th>Value</th><th>Description</th></tr><tr><td>High-side</td><td>The high-side IGBTs are actuated with the function STO1.</td></tr><tr><td>Low-side</td><td>The low-side IGBTs are actuated with the function STO1.</td></tr></table></td><td>High-side</td><td>R 1.3</td></tr>
</table>

Table 574: SafeMOTION parameter group: Basic functions - STO1

Group: Basic functions - SS1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS1 - Ramp monitoring - Enable

(previously Rampmonitoring for SS1)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SS1 function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When transitioning to the safe state of the SS1 function, a deceleration ramp is monitored in addition to the configurable time.</td></tr><tr><td>Disabled</td><td>When transitioning to the safe state of the SS1 function, only a configurable time is monitored.</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS1</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 575: SafeMOTION parameter group: Basic functions - SS1

Group: Basic functions - SBC (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBC - Enable delay time (previously *Delay time to start SBC (us)*)	[µs]	Delay time between the SBC request and activation of the safety function	0	R 1.3

Table 576: SafeMOTION parameter group: Basic functions - SBC

Group: Speed functions - SS2 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS2 - Ramp monitoring - Enable

(previously Rampmonitoring for SS2)</td><td>Enabled/ Disabled</td><td>Activates ramp monitoring (in addition to time-based monitoring) when the SS2 function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When changing to the safe state of the SS2 function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr>
<tr><td>Disabled</td><td>When changing to the safe state of the SS2 function, only a configurable time is monitored</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>Ramp Monitoring Time for SS2 (us)</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS2</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 577: SafeMOTION parameter group: Speed functions - SS2

Group: Speed functions - SLA (previously *Safely Limited Acceleration*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLA - Acceleration limit in positive direction (previously *Safe acceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for acceleration in the positive direction of movement	0	R 1.9
SLA - Deceleration limit in positive direction (previously *Safe deceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for deceleration in the positive direction of movement	0	R 1.9
SLA - Acceleration limit in negative direction (previously *Safe acceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for acceleration in the negative direction of movement	0	R 1.9
SLA - Deceleration limit in negative direction (previously *Safe deceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for deceleration in the negative direction of movement	0	R 1.9
SLA - Enable delay time (previously *Delay time to start SLA (us)*)	[µs]	Delay time between the SLA request and activation of the safety function	0	R 1.9

Table 578: SafeMOTION parameter group: Speed functions - SLA

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SMS - Enable

(previously Safe Maximum Speed)</td><td>Enabled/ Disabled</td><td>Activates the SMS safety function by configuration
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>SMS activated</td></tr>
<tr><td>Disabled</td><td>SMS deactivated</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SMS - Speed limit

(previously Maximum Speed for SMS (units/s))</td><td>[units/s]</td><td>Speed limit of the maximum speed (SMS)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS1 - Speed limit

(previously Safe Speedlimit 1 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 1 for SLS (SLS1)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Speed limit

(previously Safe Speedlimit 2 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 2 for SLS (SLS2)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS3 - Speed limit

(previously Safe Speedlimit 3 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 3 for SLS (SLS3)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS4 - Speed limit

(previously Safe Speedlimit 4 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 4 for SLS (SLS4)</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 579: SafeMOTION parameter group: Speed functions - SMS/SLS

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SLS - Ramp monitoring - Enable

(previously Rampmonitoring for SLS)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr><tr><td>Disabled</td><td>When changing to the safe state of the SLS function, only a configurable time is monitored</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SLS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS1</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS2 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS2</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS2 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS3 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS3</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS4 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS4 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS4</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 579: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 580: SafeMOTION parameter group: Advanced functions - SDI

Group: Advanced functions - SLI (previously *Safely Limited Increment*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLI - Position limit (previously *Safe Increments (units)*)	[units]	Maximum movable increments when SLI is active	0	R 1.3
SLI - Disable delay time (previously *SLI Off Delay (µs)*)	[µs]	Switch off delay of SLI	0	R 1.3

Table 581: SafeMOTION parameter group: Advanced functions - SLI

Group: Absolute position functions - Homing (previously *Homing*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Home position or home offset (previously *Home Position or Home Offset (units)*)	[units]	Home position or home offset	0	R 1.4
Homing - Maximum trigger speed (previously *Max. trigger speed (units/s)*)	[units/s]	Maximum permissible speed for evaluating the reference switch / reference pulse	0	R 1.4
Homing - Monitoring time (previously *Homing Monitoring Time (µs)*)	[µs]	Monitoring time for the homing procedure	0	R 1.4

Table 582: SafeMOTION parameter group: Absolute position functions - Homing

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Mode (previously *Mode*)	Direct / Reference switch / *Home Offset / Home offset with correction*	Selects the homing mode *Modes "Home offset" and "Home offset with correction" are only available for ACOPOSmulti SafeMOTION EnDat 2.2!*	Direct	R 1.4
Homing - Edge of reference switch (previously *Edge of reference switch*)	Positive / Negative	Selects the switching edge for the reference switch The switching edge for the reference switch input is positive if the logical state of the reference switch changes from SAFEFALSE to SAFETRUE in the positive direction of movement.	Positive	R 1.4
Homing - Trigger direction (previously *Trigger direction*)	Positive / Negative	Selects the trigger direction If the homing procedure requires a movement, then this parameter specifies the direction for evaluating the reference switch / reference pulse.	Positive	R 1.4
Homing - Enable reference pulse *(previously Reference pulse)*	*Enabled/ Disabled*	*Selects whether or not to use a reference pulse for homing* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2!*	*Disabled*	R 1.4
Homing - Blocking distance *(previously Blocking distance (% encoder reference system))*	*%*	*Distance within which evaluation of the reference pulse will be suppressed. This is calculated starting at the configured reference switch edge and indicated as a percentage of the encoder reference system.* *A single revolution is used as the encoder reference system for rotary encoders.* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2!*	*0*	R 1.4

Table 582: SafeMOTION parameter group: Absolute position functions - Homing

Group: Absolute position functions - SMP/SLP (previously *Safety Position Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SMP - Enable (previously *Safe Maximum Position*)	Enabled/ Disabled	Activates the SMP safety function from the configuration **Value** – **Description** Enabled – SMP is activated Disabled – SMP is deactivated	Disabled	R 1.4
SMP - Lower position limit (previously *Safe Lower Position Limit for SMP (units)*)	[units]	Lower position limit for the machine's full travel range	0	R 1.4
SMP - Upper position limit (previously *Safe Upper Position Limit for SMP (units)*)	[units]	Upper position limit for the machine's full travel range	0	R 1.4
SLP - Lower position limit (previously *Safe Lower Position Limit for SLP (units)*)	[units]	Lower position limit for the monitoring range	0	R 1.4
SLP - Upper position limit (previously *Safe Upper Position Limit for SLP (units)*)	[units]	Upper position limit for the monitoring range	0	R 1.4
SLP - Enable delay time (previously *Delay time to start SLP (us)*)	[µs]	Delay time between the SLP request and start of monitoring	0	R 1.4

Table 583: SafeMOTION parameter group: Absolute position functions - SMP/SLP

In a safety application, it is possible for multiple safety functions to be requested at the same time. In order to prevent this from turning into an unsafe situation, the individual safety functions are prioritized on the SafeMOTION module.

If several functions are active, then the lowest speed limit is always the value being monitored.

Information:

The following application rule must be observed:

$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS} \leq$ EUS - Maximum speed to normalize speed range

This is required for setting priority of the safety functions on the SafeMOTION module.

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

8.8.3 Integrated safety functions

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

8.8.4 Safe encoder connection

See 6.2.3.3 "Safe encoder connection" on page 307.

8.8.5 Fault avoidance

See 7.3.4 "Fault avoidance" on page 503.

8.8.6 Input parameters

Information:

For detailed information about individual safety functions, see "SafeMOTION user's manual / chapter "Safety technology" / Integrated safety functions"!

8.8.6.1 General information about "S_Control" inputs

"S_Control" inputs are used to request the respective safety functions.

Information:

If a safety function is not used in the application, then the respective input must remain open.

Danger!

The safety functions that are used must be tested.
A function is considered to be used if the respective input variable is connected!

Information:

To enable the function block itself and assign the functions to a defined axis, inputs "Activate" and "S_AxisID" must be connected at a minimum.

Information:

It is mandatory for function block SF_oS_MOTION_Basic_BR (or alternatively, function block SF_oS_MOTION_BR) to be applied to each axis being used in the safety application.

In addition to inputs "Activate" and "S_AxisID", inputs "S_Control_Reset" and "S_Control_Activate" must also be used. Otherwise, the SafeDESIGNER project cannot be compiled.

8.8.6.2 Activate

General function

- Enables the function block

Data type

- BOOL

Connection

- Constant or variable

Function description

This input parameter is used to activate the function block.

- When enabling or disabling safe devices, "Activate" must be linked to a variable that indicates the state (enabled or disabled) of the corresponding safe devices. This ensures that the function block does not output a triggered safety function as diagnostic information when a device is switched off.
- It is also possible to connect "Activate" to a constant (TRUE) in order to enable the function block.

TRUE

The function block is enabled.

FALSE

The function block is not enabled.
All binary output parameters are set to FALSE.
Sets the DiagCode diagnostic parameter to WORD#16#0000.

If you want to control function block diagnostics as needed in your diagnostic concept whenever error messages from safe devices and/or deactivated safe devices occur, connect "Activate" to a signal that indicates the status of the safe devices that are involved with the safety function supported by the function block. Form this signal using only safe devices whose I/O signals are connected to the function block via actual parameters. In this way, you prevent triggered safety functions from being reported by active safe devices. This measure is only used to control the diagnostic information from inactive safe devices in a defined manner.

8.8.6.3 S_Control_Reset

General function

- Input "S_Control_Reset" for acknowledging state FUNCTIONAL FAIL SAFE or for putting the SafeMOTION module into state OPERATIONAL after STARTUP

Data type

- SAFEBOOL

Connection

- Variable

Function description

Input "S_Control_Reset" for acknowledging the FUNCTIONAL FAIL SAFE state

A positive edge triggers the reset function.

Depending on the configuration of parameter "Automatic Reset at Startup", a positive edge may be necessary to get the SafeMOTION module from state INIT to state OPERATIONAL after startup.

Relevant configuration parameters

Group: General settings - Automatic reset on start (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Used Starting in Safety Release</th></tr>
<tr><td>Automatic reset on start - Enable

(previously Automatic Reset at Startup)</td><td>Enabled/
Disabled</td><td>Activates automatic reset of the function block at startup
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>After startup, the module automatically changes to state OPERATIONAL (Startreset). The reset input does not have to be controlled!</td></tr>
<tr><td>Disabled</td><td>After startup, the module remains in an Init state until a positive edge of the reset input is detected.</td></tr>
</table></td><td>Disabled</td><td>R1.3</td></tr>
</table>

Table 584: SafeMOTION parameter group: General settings - Automatic reset on start

Danger!

Parameter "Automatic reset on start" enables/disables the restart interlock during startup or when a network failure occurs on a reestablished network connection.

If parameter "Automatic reset on start" is set to "Enabled", then the module automatically changes to state OPERATIONAL state (i.e. pulse disabling and the motor holding brake are enabled)!

Configuring an automatic restart can result in critical safety conditions. Take additional measures to ensure proper safety-related functionality.

8.8.6.4 S_Control_Activate

General function

- Enables the module-internal state machine for a safe axis on the SafeMOTION module to execute the selected safety function

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to enable the module-internal state machine for a safe axis on the SafeMOTION module to execute the selected safety function.

SAFETRUE

Starts the state machine of the safe axis, safety functions can be enabled.

SAFEFALSE

Sets the state machine of the safe axis to state IDLE

8.8.6.5 S_Control_STO

General function

- Selects/Deselects safety function Safe Torque Off, STO

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the STO safety function.

SAFETRUE

The safety function is deselected. Safe pulse disabling is not active!

SAFEFALSE

The safety function is selected. Safe pulse disabling is active! Torque/Power are switched off on the drive.

Not connected

The safety function is deactivated.

Relevant configuration parameters

- None

8.8.6.6 S_Control_SBC

General function

- Selects/Deselects safety function Safe Brake Control, SBC

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SBC safety function.

SAFETRUE

The safety function is deselected. The motor holding brake output is enabled and can be used by the standard application.

SAFEFALSE

The safety function is selected. The motor holding brake output is switched to 0 V!

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Basic functions - SBC (previously *General Settings*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBC - Enable delay time (previously *Delay time to start SBC (us)*)	[µs]	Delay time between the SBC request and activation of the safety function	0	R 1.3

Table 585: SafeMOTION parameter group: Basic functions - SBC

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

8.8.6.7 S_Control_SS1

General function

- Selects/Deselects safety function Safe Stop 1, SS1

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SS1 safety function.

SAFETRUE

The safety function is deselected. SS1 is not active!

SAFEFALSE

The safety function is selected. Safe pulse disabling is activated after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 586: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Basic functions - SS1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS1 - Ramp monitoring - Enable

(previously Rampmonitoring for SS1)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SS1 function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When transitioning to the safe state of the SS1 function, a deceleration ramp is monitored in addition to the configurable time.</td></tr>
<tr><td>Disabled</td><td>When transitioning to the safe state of the SS1 function, only a configurable time is monitored.</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SS1 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SS1 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS1</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 587: SafeMOTION parameter group: Basic functions - SS1

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr>
<tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr>
</table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 588: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

To use this function without safe encoder evaluation, "Ramp monitoring for SS1" and "Early Limit Monitoring" must be disabled.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \le LIM_{SLS4} \le LIM_{SLS3} \le LIM_{SLS2} \le LIM_{SLS1} \le LIM_{SMS}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

8.8.6.8 S_Control_STO1

General function

- Selects/Deselects safety function Safe Torque Off, One Channel, STO1

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the STO1 safety function.

SAFETRUE

The safety function is deselected. Safe pulse disabling is not active!

SAFEFALSE

The safety function is selected. Depending on the configuration, the high-side or low-side of safe pulse disabling is active! Torque/Power are switched off on the drive.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Basic functions - STO1 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th colspan="2">Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td rowspan="4">STO1 - Channel

(previously Channel selection for One Channel STO (STO1))</td><td rowspan="4">High-side/
Low-side</td><td colspan="2">Selects the high-side or low-side IGBT in the STO1 function</td><td rowspan="4">High-side</td><td rowspan="4">R 1.3</td></tr>
<tr><td>Value</td><td>Description</td></tr>
<tr><td>High-side</td><td>The high-side IGBTs are actuated with the function STO1.</td></tr>
<tr><td>Low-side</td><td>The low-side IGBTs are actuated with the function STO1.</td></tr>
</table>

Table 589: SafeMOTION parameter group: Basic functions - STO1

8.8.6.9 S_Control_SOS

General function

- Selects/Deselects safety function Safe Operating Stop, SOS

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SOS safety function.

SAFETRUE

The safety function is deselected. Standstill tolerances are not being monitored.

SAFEFALSE

The safety function is selected. Standstill tolerances are being monitored.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 590: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ < EUS - Maximum speed to normalize speed range

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

8.8.6.10 S_Control_SS2

General function

- Selects/Deselects safety function Safe Stop 2, SS2

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SS2 safety function.

SAFETRUE

The safety function is deselected. SS2 is not active!

SAFEFALSE

The safety function is selected. Standstill monitoring is activated after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 591: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SS2 (previously *General Settings*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SS2 - Ramp monitoring - Enable

(previously Rampmonitoring for SS2)</td><td>Enabled/
Disabled</td><td>Activates ramp monitoring (in addition to time-based monitoring) when the SS2 function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When changing to the safe state of the SS2 function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr>
<tr><td>Disabled</td><td>When changing to the safe state of the SS2 function, only a configurable time is monitored</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>Ramp Monitoring Time for SS2 (us)</td><td>[µs]</td><td>Deceleration ramp monitoring time for SS2</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 592: SafeMOTION parameter group: Speed functions - SS2

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 593: SafeMOTION parameter group: General settings - Standstill monitoring

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** – **Description** Enabled – "Early Limit Monitoring" is active! Disabled – "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 594: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$\mathbf{LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

8.8.6.11 S_Control_SLA

General function

- Selects/Deselects safety function Safely Limited Acceleration, SLA

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLA safety function.

SAFETRUE

The safety function is deselected. SLA is not active!

SAFEFALSE

The safety function is selected. A safe limit value for acceleration/deceleration is monitored with respect to the direction of movement.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 595: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Speed functions - SLA (previously *Safely Limited Acceleration*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLA - Acceleration limit in positive direction (previously *Safe acceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for acceleration in the positive direction of movement	0	R 1.9
SLA - Deceleration limit in positive direction (previously *Safe deceleration limit for SLA (units/s²) in positive direction*)	[units/s²]	Limit value for deceleration in the positive direction of movement	0	R 1.9
SLA - Acceleration limit in negative direction (previously *Safe acceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for acceleration in the negative direction of movement	0	R 1.9
SLA - Deceleration limit in negative direction (previously *Safe deceleration limit for SLA (units/s²) in negative direction*)	[units/s²]	Limit value for deceleration in the negative direction of movement	0	R 1.9
SLA - Enable delay time (previously *Delay time to start SLA (us)*)	[µs]	Delay time between the SLA request and activation of the safety function	0	R 1.9

Table 596: SafeMOTION parameter group: Speed functions - SLA

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

8.8.6.12 S_Control_SLS-1

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 1

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS1 safety function.

SAFETRUE

The safety function is deselected. SLS1 is not active!

SAFEFALSE

The safety function is selected. Speed limit 1 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 597: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLS - Ramp monitoring - Enable (previously *Rampmonitoring for SLS*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested **Value** / **Description** Enabled: When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time Disabled: When changing to the safe state of the SLS function, only a configurable time is monitored	Enabled	R 1.3
SLS1 - Speed limit (previously *Safe Speedlimit 1 for SLS (units/s)*)	[units/s]	Speed limit 1 for SLS (SLS1)	0	R 1.3
SLS1 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS1 (us)*)	[µs]	Deceleration ramp monitoring time for SLS1	0	R 1.3

Table 598: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** / **Description** Enabled: "Early Limit Monitoring" is active! Disabled: "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 599: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

8.8.6.13 S_Control_SLS-2

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 2

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS2 safety function.

SAFETRUE

The safety function is deselected. SLS2 is not active!

SAFEFALSE

The safety function is selected. Speed limit 2 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 600: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLS - Ramp monitoring - Enable (previously *Rampmonitoring for SLS*)	Enabled/ Disabled	Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested **Value** / **Description** Enabled: When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time Disabled: When changing to the safe state of the SLS function, only a configurable time is monitored	Enabled	R 1.3
SLS2 - Speed limit (previously *Safe Speedlimit 2 for SLS (units/s)*)	[units/s]	Speed limit 2 for SLS (SLS2)	0	R 1.3
SLS2 - Ramp monitoring - Time (previously *Ramp Monitoring Time for SLS2 (us)*)	[µs]	Deceleration ramp monitoring time for SLS2	0	R 1.3

Table 601: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Early limit monitoring - Enable (previously *Early Limit Monitoring)*	Enabled/ Disabled	Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit "Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely. **Value** / **Description** Enabled: "Early Limit Monitoring" is active! Disabled: "Early Limit Monitoring" is not active!	Disabled	R 1.3
Early limit monitoring - Time (previously *Early Limit Monitoring time (us))*	[µs]	Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state	0	R 1.3

Table 602: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$\mathbf{LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

8.8.6.14 S_Control_SLS-3

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 3

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS3 safety function.

SAFETRUE

The safety function is deselected. SLS3 is not active!

SAFEFALSE

The safety function is selected. Speed limit 3 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 603: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SLS - Ramp monitoring - Enable

(previously Rampmonitoring for SLS)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr><tr><td>Disabled</td><td>When changing to the safe state of the SLS function, only a configurable time is monitored</td></tr></table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SLS3 - Speed limit

(previously Safe Speedlimit 3 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 3 for SLS (SLS3)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS3 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS3 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS3</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 604: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.<table><tr><th>Value</th><th>Description</th></tr><tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr><tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr></table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 605: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS}$ **< EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

8.8.6.15 S_Control_SLS-4

General function

- Selects/Deselects safety function Safely Limited Speed, Speed Limit 4

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLS4 safety function.

SAFETRUE

The safety function is deselected. SLS4 is not active!

SAFEFALSE

The safety function is selected. Speed limit 4 is monitored after the end of ramp monitoring.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 606: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Speed functions - SMS/SLS (previously *Safety Speed Limits*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>SLS - Ramp monitoring - Enable

(previously Rampmonitoring for SLS)</td><td>Enabled/
Disabled</td><td>Activates ramp-based monitoring (in addition to time-based monitoring) when the SLS function is requested
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>When changing to the safe state of the SLS function, a deceleration ramp is also monitored, in addition to the configurable time</td></tr>
<tr><td>Disabled</td><td>When changing to the safe state of the SLS function, only a configurable time is monitored</td></tr>
</table></td><td>Enabled</td><td>R 1.3</td></tr>
<tr><td>SLS4 - Speed limit

(previously Safe Speedlimit 4 for SLS (units/s))</td><td>[units/s]</td><td>Speed limit 2 for SLS (SLS2)</td><td>0</td><td>R 1.3</td></tr>
<tr><td>SLS4 - Ramp monitoring - Time

(previously Ramp Monitoring Time for SLS4 (us))</td><td>[µs]</td><td>Deceleration ramp monitoring time for SLS2</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 607: SafeMOTION parameter group: Speed functions - SMS/SLS

Group: General settings - Early limit monitoring (previously *Early Limit Monitoring*)

<table>
<tr><th>Parameter</th><th>Unit</th><th>Description</th><th>Default value</th><th>Starting in Safety Release</th></tr>
<tr><td>Early limit monitoring - Enable

(previously Early Limit Monitoring)</td><td>Enabled/
Disabled</td><td>Deceleration ramp monitoring is terminated prematurely if the value falls below the lower limit
"Early limit monitoring": If the current speed during the deceleration process falls below the end speed limit of the activated safety function for a defined amount of time, then the safe state of the respective function will be activated prematurely.
<table>
<tr><th>Value</th><th>Description</th></tr>
<tr><td>Enabled</td><td>"Early Limit Monitoring" is active!</td></tr>
<tr><td>Disabled</td><td>"Early Limit Monitoring" is not active!</td></tr>
</table></td><td>Disabled</td><td>R 1.3</td></tr>
<tr><td>Early limit monitoring - Time

(previously Early Limit Monitoring time (us))</td><td>[µs]</td><td>Time during which the speed must be below the target speed limit in order to prematurely end the deceleration ramp and to assume the safety function's end state</td><td>0</td><td>R 1.3</td></tr>
</table>

Table 608: SafeMOTION parameter group: General settings - Early limit monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

If several safety functions are active, then the lowest speed limit is always the value being monitored.

The following application rule must be observed:
$LIM_{SOS} \leq LIM_{SLS4} \leq LIM_{SLS3} \leq LIM_{SLS2} \leq LIM_{SLS1} \leq LIM_{SMS} <$ **EUS - Maximum speed to normalize speed range**

Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

8.8.6.16 S_Control_SDI-P

General function

- Selects/Deselects safety function Safe Direction. Movement is allowed in the positive direction.

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the safety function SDI, movement is allowed in the positive direction of movement.

SAFETRUE

The safety function is deselected. SDI is not active!

SAFEFALSE

The direction of movement is monitored after the delay time has expired. Movement is allowed in the positive direction.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 609: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*)	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 610: SafeMOTION parameter group: Advanced functions - SDI

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

8.8.6.17 S_Control_SDI-N

General function

- Selects/Deselects safety function Safe Direction. Movement is allowed in the negative direction.

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the safety function SDI, movement is allowed in the negative direction of movement.

SAFETRUE

The safety function is deselected. SDI is not active!

SAFEFALSE

The direction of movement is monitored after the delay time has expired. Movement is allowed in the negative direction.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 611: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SDI (previously *Safety Additional Parameters*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SDI - Enable delay time (previously *Delay time to start SDI (us)*)	[µs]	Delay time between the SDI request and activation of the safety function	0	R 1.3

Table 612: SafeMOTION parameter group: Advanced functions - SDI

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

8.8.6.18 S_Control_SLI

General function

- Selects/Deselects safety function Safely Limited Increment, SLI

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLI safety function.

SAFETRUE

The safety function is deselected. SLI is not active!

SAFEFALSE

The safety function is selected. A safe range of increments is monitored.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3

Table 613: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Group: Advanced functions - SLI (previously *Safely Limited Increment*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLI - Position limit (previously *Safe Increments (units)*)	[units]	Maximum movable increments when SLI is active	0	R 1.3
SLI - Disable delay time (previously *SLI Off Delay (µs)*)	[µs]	Switch off delay of SLI	0	R 1.3

Table 614: SafeMOTION parameter group: Advanced functions - SLI

Danger!

The maximum increment range must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

8.8.6.19 S_Control_SBT

General function

- Selects/Deselects safety function Safe Brake Test, SBT

Data type

- SAFEBOOL

Connection

- Variable

Function description

This input parameter is used to start the SBT safety function.

Negative edge

A negative edge (state transition from SAFETRUE to SAFEFALSE on input parameter "S_Control_SBT") starts safety function Safe Brake Test, SBT.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Advanced functions - SBT (previously *Safe Brake Test*) (only available for ACOPOSmulti SafeMOTION SinCos and ACOPOS P3 SafeMOTION (hardware upgrade 1.10.2.x or later)

Parameter	Unit	Description	Default value	Starting in Safety Release
SBT - Threshold (previously *Safe Brake Test threshold (uA)*)	[µA]	Threshold value for the stator current that must be exceeded during the brake test	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - External load (previously *Safe Brake Test external load (uA)*)	[µA]	External load	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Position tolerance (previously *Safe Brake Test position tolerance (units)*)	[units]	Position tolerance	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Maximum torque duration (previously *Safe Brake Test maximum torque duration (us)*)	[µs]	Duration of the test for which the maximum torque must be present	0	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Test interval (previously *Safe Brake Test interval (s)*)	[s]	Retry interval for the safe brake test	28800	R 1.7 SinCos R 1.10 ACOPOS P3
SBT - Enable delay time (previously *Delay Time to start SBT (us)*)	[µs]	Delay time between the SBT request and activation of the safety function	0	R 1.7 SinCos R 1.10 ACOPOS P3

Table 615: SafeMOTION parameter group: Advanced functions - SBT

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

8.8.6.20 S_Control_SLT

General function

- Selects/Deselects safety function Safely Limited Torque, SLT

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLT safety function.

SAFETRUE

The safety function is deselected. SLT is not active!

SAFEFALSE

The safety function is selected. The configured motor torque limit is monitored.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Advanced functions - SLT (only available for ACOPOS P3 SafeMOTION in hardware upgrade 1.10.2.x or later)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLT - Torque limit	[mNm]	Torque limitation monitored during activation of SLT	0	R 1.10
SLT - Enable delay time	[µs]	Delay time between the SLT request and activation of the safety function	0	R 1.10

Table 616: SafeMOTION parameter group: Advanced functions - SLT

Group: General settings - Motor (only available for ACOPOS P3 SafeMOTION in hardware upgrade 1.10.2.x or later)

Parameter	Unit	Description	Default value	Starting in Safety Release
Motor - Number of pole pairs (hardware upgrade 1.10.2.x and later)	-	Number of pole pairs on the rotor circumference	1	1.10
Motor - Direction*) (hardware upgrade 1.10.2.x and later)	Standard / Inverse	Direction of rotation of the motor	Standard	1.10
Motor - Stator resistance (hardware upgrade 1.10.2.x and later)	mOhm	Ohmic stator resistance measured between two connections (phase - phase) of the motor	0	1.10
Motor - Stator inductance (hardware upgrade 1.10.2.x and later)	µH	Stator inductance measured between two connections (phase - phase) of the motor	0	1.10
Motor - Torque constant (hardware upgrade 1.10.2.x and later)	µNm / A	Torque constant of the motor	0	1.10
Motor - Rated speed (hardware upgrade 1.10.2.x and later)	units/s	Nominal speed of the motor	0	1.10
Motor - Stall current (hardware upgrade 1.10.2.x and later)	mA	Stall current of the motor	0	1.10
Motor - Rated current (hardware upgrade 1.10.2.x and later)	mA	Nominal current of the motor	0	1.10
Motor - Peak current (hardware upgrade 1.10.2.x and later)	mA	Peak current of the motor	0	1.10

Table 617: SafeMOTION parameter group: General settings - Motor

Parameter	Unit	Description	Default value	Starting in Safety Release
Motor - Stall torque (hardware upgrade 1.10.2.x and later)	mNm	Stall torque of the motor that is output when the stall current is applied	0	1.10
Motor - Peak torque (hardware upgrade 1.10.2.x and later)	mNm	Peak torque of the motor that is briefly output when the peak current is applied	0	1.10
Motor - Moment of inertia (optional) (hardware upgrade 1.10.2.x and later)	μkgm²	Mass moment of inertia of the motor. Consists of the sum of the inertias of the rotor, encoder and holding brake.	0	1.10
Motor - External moment of inertia (optional) (hardware upgrade 1.10.2.x and later)	μkgm²	External mass moment of inertia, depends on the total external load	0	1.10

Table 617: SafeMOTION parameter group: General settings - Motor

*) The direction of rotation of the motor is not related to the counting direction of the speed ("EUS - Counting direction"), i.e. the direction of rotation of the motor can be changed explicitly in the non-safe application and must therefore also be taken into account in SafeDESIGNER.

8.8.6.21 S_Control_Homing

General function

- Selects/Deselects safety function "Safe Homing"

Data type

- SAFEBOOL

Connection

- Variable

Function description

This input parameter is used to start a "Safe Homing" procedure. A positive edge of the input starts the safety function.

Positive edge: Change from SAFEFALSE to SAFETRUE

Starts "Safe Homing".

Negative edge: Change from SAFETRUE to SAFEFALSE

If still active, the homing procedure will be terminated by the negative edge. This state transition has no effect if the homing procedure has already been completed.

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: Absolute position functions - Homing (previously *Homing*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Mode (previously *Mode*)	Direct / Reference switch / *Home Offset /* *Home offset with correction*	Selects the homing mode *Modes "Home offset" and "Home offset with correction" are only available for ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	Direct	R 1.4
Homing - Home position or home offset (previously *Home Position or Home Offset (units)*)	[units]	Home position or home offset	0	R 1.4
Homing - Enable RSP (Remanent safe position) *(previously Remanent safe position)*	*Enabled/* *Disabled*	*Selects whether or not to use the remanent safe position* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*Disabled*	R 1.9
Homing - Edge of reference switch (previously *Edge of reference switch*)	Positive / Negative	Selects the switching edge for the reference switch The switching edge for the reference switch input is positive if the logical state of the reference switch changes from SAFEFALSE to SAFETRUE in the positive direction of movement.	Positive	R 1.4
Homing - Trigger direction (previously *Trigger direction*)	Positive / Negative	Selects the trigger direction If the homing procedure requires a movement, then this parameter specifies the direction for evaluating the reference switch / reference pulse.	Positive	R 1.4

Table 618: SafeMOTION parameter group: Absolute position functions - Homing

Parameter	Unit	Description	Default value	Starting in Safety Release
Homing - Enable reference pulse *(previously Reference pulse)*	*Enabled/ Disabled*	*Selects whether or not to use a reference pulse for homing* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*Disabled*	R 1.4
Homing - Blocking distance *(previously Blocking distance (% encoder reference system))*	*%*	*Distance within which evaluation of the reference pulse will be suppressed.* *This is calculated starting at the configured reference switch edge and indicated as a percentage of the encoder reference system.* *A single revolution is used as the encoder reference system for rotary encoders.* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2, ACOPOS P3 SafeMOTION and ACOPOSmotor SafeMOTION!*	*0*	R 1.4
Homing - Maximum trigger speed (previously *Max. trigger speed (units/s)*)	[units/s]	Maximum permissible speed for evaluating the reference switch / reference pulse	0	R 1.4
Homing - Monitoring time (previously *Homing Monitoring Time (μs)*)	[μs]	Monitoring time for the homing procedure	0	R 1.4

Table 618: SafeMOTION parameter group: Absolute position functions - Homing

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

The Safe Homing function is needed in order to implement the safety functions SLP and SMP and for using the safe position.
The "SafePositionValid" status bit will remain set to SAFEFALSE until safe homing has been performed!

8.8.6.22 S_Control_RefSwitch

General function

- Reference switch input for safety function "Safe Homing"

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter serves as a reference switch input for the "Safe Homing" safety function and is only evaluated in the "Reference Switch" homing mode.
The status of a safe reference switch that was read into the safety application via a safe input module (X20SIxxxx), for example, should be linked to the input.

Not connected

The reference switch is not being used!

Information:

If "Reference Switch" homing mode is configured and the reference switch input "S_ReferenceSwitch" is not wired on the function block, then the SafeMOTION module will switch to the FAIL SAFE state. The only way to exit the FAIL SAFE state is to complete a power off/on cycle and modify the safety application!

Information:

**Input "S_Control_RefSwitch" is only evaluated in homing mode "Reference Switch".
The input is ignored in other homing modes!**

8.8.6.23 S_Control_SwitchHomingMode

General function

- This input is used by safety function "Remanent Safe Position" and enables a homing procedure that confirms the remanent safe position.

Data type

- SAFEBOOL

Connection

- Variable

Function description

This input parameter is used to switch between homing with RSP and the configured homing mode.

SAFETRUE

When a homing command is given (i.e. positive edge on input "S_Control_RequestHoming"), then homing mode "Homing with RSP" is used.

SAFEFALSE

When a homing command is given (i.e. positive edge on input "S_Control_RequestHoming"), then the configured homing mode is used.

Relevant configuration parameters

Parameter	Unit	Description	Default value
Homing			
Remanent Safe Position	*Enabled/ Disabled*	*Selects whether or not to use the remanent safe position* *This parameter is only available with ACOPOSmulti SafeMOTION EnDat 2.2!*	*Disabled*
Safety Standstill and Direction Tolerances			
Speed Tolerance	[units/s]	Speed tolerance for standstill monitoring	0
Position Tolerance	[units]	Position tolerance for standstill and direction monitoring	0

Table 619: RSP safety function - Parameters

8.8.6.24 S_Control_SLP

General function

- Selects/Deselects safety function Safely Limited Position, SLP

Data type

- SAFEBOOL

Connection

- Constant or variable

Function description

This input parameter is used to select or deselect the SLP safety function.

SAFETRUE

The safety function is deselected. SLP is not active!

SAFEFALSE

The configured position window will be safety-monitored after "Delay time to start SLP (us)".

Not connected

The safety function is deactivated.

Relevant configuration parameters

Group: General settings - Ramp monitoring (previously *Safety Deceleration Ramp*)

Parameter	Unit	Description	Default value	Starting in Safety Release
Ramp monitoring - Speed deceleration limit (previously *Deceleration Ramp [units/s²]*)	[units/s²]	Slope of the deceleration ramp to be monitored	1073676289	R 1.3
Ramp monitoring - Enable delay time (previously *Delay time to start ramp monitoring (us)*)	[µs]	Delay time between the request for ramp-based monitoring and the start of monitoring	0	R 1.3

Table 620: SafeMOTION parameter group: General settings - Ramp monitoring

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: Absolute position functions - SMP/SLP (previously *Safety Position Limits*)

Parameter	Unit	Description	Default value	Starting in Safety Release
SLP - Lower position limit (previously *Safe Lower Position Limit for SLP (units)*)	[units]	Lower position limit for the monitoring range	0	R 1.4
SLP - Upper position limit (previously *Safe Upper Position Limit for SLP (units)*)	[units]	Upper position limit for the monitoring range	0	R 1.4
SLP - Enable delay time (previously *Delay time to start SLP (us)*)	[µs]	Delay time between the SLP request and start of monitoring	0	R 1.4

Table 621: SafeMOTION parameter group: Absolute position functions - SMP/SLP

Danger!

The position limits being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement, a dangerous movement cannot occur in the event of a worst case scenario.

The dangerous movement must be determined by a risk analysis.

Information:

The following application rule must be observed:

$\mathbf{LIM_{SMP,NEG} \le LIM_{SLP,NEG} \le LIM_{SLP,POS} \le LIM_{SMP,POS}}$

If this rule is not adhered to, then the SafeMOTION module immediately switches to the FAIL SAFE state after startup. The application must be set accordingly in SafeDESIGNER!

Danger!

The delay parameters cause a delay before the safety function is started. This delay must be taken into account when determining the intervals and performing the risk analysis!

Group: General settings - Standstill monitoring (previously *Safety Standstill and Direction Tolerances*)

Parameter	**Unit**	**Description**	**Default value**	**Starting in Safety Release**
Standstill monitoring - Speed tolerance (previously *Speed Tolerance (units/s)*)	[units/s]	Speed tolerance for standstill monitoring (SOS)	0	R 1.3
Standstill monitoring - Position tolerance (previously *Position Tolerance (units)*)	[units]	Position tolerance for standstill and direction monitoring	0	R 1.3

Table 622: SafeMOTION parameter group: General settings - Standstill monitoring

Danger!

The speed limit and position limit being monitored must be set in such a manner that, with consideration for the error response time and the resulting movement in the worst case scenario, a dangerous movement cannot occur in the event of error.

The dangerous movement must be determined by a risk analysis.

Information:

This safety function requires safe evaluation of the position and speed.
If an evaluation error is detected, then the SafeMOTION module switches to the acknowledgeable FUNCTIONAL FAIL SAFE error state.

Information:

The following application rule must be observed:
$\mathbf{LIM_{SMP,NEG} \le LIM_{SLP,NEG} \le LIM_{SLP,POS} \le LIM_{SMP,POS}}$
Failure to follow the application rule will cause the SafeMOTION module to enter the FAIL SAFE state. If this occurs, it can only be brought back to the OPERATIONAL state by modifying the safety application and completing a power off/on cycle!

Information:

Safe homing of the axis must be completed prior to using this safety function.
If a homing procedure is not completed successfully or the "S_SafePositionValid" status changes, then the request for the SLP safety function causes the module to switch to the acknowledgeable FUNCTIONAL FAIL SAFE error state.
The drive loses all torque/power and coasts to a stop! In the event of an error, a synchronous axis will no longer be synchronous. The output of function block "S_NotErrFUNC" is reset.

8.8.6.25 S_AxisID

General function

- This input parameter assigns a real axis to the function block.

Data type

- SAFEINT

Connection

- Constant

Function description

The corresponding axis can be connected to the input in SafeDESIGNER using drag-and-drop.

> ## Information:
> **If function block SF_oS_MOTION_BR is used in SafeDESIGNER, then the same "S_AxisID" is not permitted to be simultaneously used with function block SF_oS_MOTION_Basic_BR, SF_oS_MOTION_Speed_BR, SF_oS_MOTION_Advanced_BR or SF_oS_MOTION_AbsPos_BR!**

8.8.7 Output parameters

Output parameters provide information about the state of the SafeMOTION module and the individual safety functions.

8.8.7.1 Ready

General function

- Message: Function block is enabled/disabled.

Data type

- BOOL

Connection

- Variable

Function description

This output parameter indicates whether the function block is enabled or not.

TRUE

The function block is enabled ("Activate" = TRUE). The output parameters indicate the current state of the safety function.

FALSE

The function block is not enabled ("Activate" = FALSE). The function block outputs are set to FALSE.

8.8.7.2 S_Status_NotErrFunc

General function

- Information about the error state of the safe axis of the SafeMOTION module

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies the error state of the safe axis of the SafeMOTION module.

SAFETRUE

No error was found on the SafeMOTION module.

SAFEFALSE

An error (e.g. exceeding a monitored limit) has been detected on the safe axis of the SafeMOTION module or the function block has not been activated.
In the event of an error, see the Safety Logger in Automation Studio for additional information about the error.
If the error is a functional error, then it can be acknowledged by changing the signal on input "S_Control_Reset" from SAFEFALSE to SAFETRUE (positive edge)!

> ## Danger!
>
> **The purpose of this signal is only to provide additional information. It only provides information in connection with the requested safety functions.**
> **"S_Status_NotErrFUNC" does not represent the functional safe state of the SafeMOTION module!**

> ## Danger!
>
> **It is your responsibility to ensure that all necessary corrective measures are initiated after an error occurs since subsequent errors can result in a hazard!**

8.8.7.3 S_Status_Operational

General function

- Information about the status of the state machine of the safe axis

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies the status of the state machine of the safe axis.

SAFETRUE

The state machine is in state OPERATIONAL.

SAFEFALSE

The state machine is not in state OPERATIONAL.

8.8.7.4 S_Status_STO

General function

- Status information for safety function Safe Torque Off, STO

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the STO safety function

SAFETRUE

The STO safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.5 S_Status_SBC

General function

- Status information for safety function Safe Brake Control, SBC

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SBC safety function

SAFETRUE

The SBC safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.6 S_Status_SS1

General function

- Status information for safety function Safe Stop 1, SS1

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SS1 safety function

SAFETRUE

The SS1 safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.7 S_Status_STO1

General function

- Status information for safety function Safe Torque Off, One Channel, STO1

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the STO1 safety function

SAFETRUE

The STO1 safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.8 S_Status_SDC

General function

- Information about the status of ramp monitoring

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the status of ramp monitoring.

SAFETRUE

Ramp monitoring is active.

SAFEFALSE

Ramp monitoring is not active. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

> **Danger!**
>
> **This signal should only be used for status information.**

8.8.7.9 S_Status_EncStatus

General function

- Information about the error state of the safe encoder signal

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the error state of the signal for a defined safe encoder.
If an encoder error is detected or the SafeMOTION module is in an error state, then the output is set to SAFEFALSE.
This state is maintained until the error has been corrected.

SAFETRUE

An error was not detected on the encoder signal.

SAFEFALSE

The encoder signal from a defined safe axis is faulty, or the axis itself is in an error state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled. For more information about the error, see the Safety Logger in Automation Studio.

> **Danger!**
>
> **The purpose of this signal is only to provide additional information. It only provides information in connection with the requested safety functions.**
> **"S_Status_EncStatus" does not represent the functional safe state of the SafeMOTION module!**

8.8.7.10 S_Status_SOS

General function

- Status information for safety function Safe Operating Stop, SOS

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SOS safety function

SAFETRUE

The SOS safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.11 S_Status_SS2

General function

- Status information for safety function Safe Stop 2, SS2

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SS2 safety function

SAFETRUE

The SS2 safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.12 S_Status_SLA

General function

- Status information for safety function Safely Limited Acceleration, SLA

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLA safety function

SAFETRUE

The SLA safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.13 S_Status_SLS-1

General function

- Status information for safety function Safely Limited Speed, Speed Limit 1 (SLS-1)

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS1 safety function

SAFETRUE

The SLS1 safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.14 S_Status_SLS-2

General function

- Status information for safety function Safely Limited Speed, Speed Limit 2 (SLS-1)

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS2 safety function

SAFETRUE

The SLS2 safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.15 S_Status_SLS-3

General function

- Status information for safety function Safely Limited Speed, Speed Limit 3 (SLS-1)

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS3 safety function

SAFETRUE

The SLS3 safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.16 S_Status_SLS-4

General function

- Status information for safety function Safely Limited Speed, Speed Limit 4 (SLS-1)

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLS4 safety function

SAFETRUE

The SLS4 safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.17 S_Status_SDI-P

General function

- Status information for safety function Safe Direction. Movement is allowed in the positive direction.

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SDIpos safety function

SAFETRUE

The SDIpos safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.18 S_Status_SDI-N

General function

- Status information for safety function Safe Direction. Movement is allowed in the negative direction.

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SDIneg safety function

SAFETRUE

The SDIneg safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.19 S_Status_SLI

General function

- Status information for safety function Safely Limited Increment

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLI safety function

SAFETRUE

The SLI safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.20 S_Status_SBT

General function

- Additional information for testing the holding brake with Safe Brake Test

Data type

- SAFEBOOL

Connection

- Variable

Function description

Returns the status of the holding brake test with Safe Brake Test, SBT

SAFETRUE

The SBT safety function has been executed. The status of the testing is valid.

SAFEFALSE

The SBT safety function has not been executed. The status of the testing is invalid or expired.

8.8.7.21 S_Status_SBT-Active

General function

- Additional information for testing the holding brake with Safe Brake Test

Data type

- SAFEBOOL

Connection

- Variable

Function description

Returns the status of the holding brake test with Safe Brake Test, SBT

SAFETRUE

Testing of the holding brake with SBT is being executed.

SAFEFALSE

Testing of the holding brake with SBT is not requested.

8.8.7.22 S_Status_SLT

General function

- Status information for safety function Safely Limited Torque

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLT safety function

SAFETRUE

The SLT safety function is active and currently in its safe state.

SAFEFALSE

Safety function SLT is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.23 S_Status_Homing

General function

- Status information for safety function "Safe Homing" and the safe position

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies whether or not safe homing of the axis has been completed and whether or not the position signal is valid.

SAFETRUE

The axis has been safely homed, and the safe position is valid.

SAFEFALSE

The axis has not yet been successfully homed; the encoder signal of the axis is faulty. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.
The safe position is invalid!

> ## Danger!
>
> **The purpose of this signal is only to provide additional information.**
>
> **"S_Status_Homing" does not represent the functional safe state of the SafeMOTION module!**

> ## Danger!
>
> **The value of output parameter "S_SafePosition_4Byte" is only valid if output parameter S_SafePositionValid is SAFETRUE. Otherwise, it is invalid and is not permitted to be used further.**

8.8.7.24 S_Status_ReqHomingOK

General function

- Feedback for homing in SafeDESIGNER

Data type

- SAFEBOOL

Connection

- Variable

Function description

This status is set to provide feedback in the event that homing is requested when already in a homed state ("S_Control_Homing" and "S_Status_Homing" are set).

SAFETRUE

The input for homing is set ("S_Control_Homing" = SAFETRUE), and the safe position is valid ("S_Status_Homing" = SAFETRUE).

SAFEFALSE

The input for homing is not set or the safe position is not valid. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.25 S_Status_EncStatus2

General function

- Information about the error state of the safe encoder signal

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the error state of the signal for a defined safe encoder.
If an encoder error is detected or the SafeMOTION module is in an error state, then the output is set to FALSE. This state is maintained until the error has been corrected.

SAFETRUE

An error was not detected on the encoder signal.

SAFEFALSE

The encoder signal from a defined safe axis is faulty, or the axis itself is in an error state. For more information about the error, see the Safety Logger in Automation Studio.

> **Danger!**
>
> **The purpose of this signal is only to provide additional information. It only provides information in connection with the requested safety functions.**
> **"S_Status_EncStatus2" does not represent the functional safe state of the SafeMOTION module!**

8.8.7.26 S_Status_SLP

General function

- Status information for safety function Safely Limited Position, SLP

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SLP safety function

SAFETRUE

The SLP safety function is active and currently in its safe state.

SAFEFALSE

The safety function is not requested or has not yet reached its safe state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.27 S_Status_SMP

General function

- Status information for safety function Safe Maximum Position, SMP

Data type

- SAFEBOOL

Connection

- Variable

Function description

Indicates the functional safe state of the SMP safety function

SAFETRUE

The SMP safety function is active and currently in its safe state.

SAFEFALSE

Monitoring of the SMP position limits is not active. Monitoring is not yet active since the SafeMOTION module has not yet been homed. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.28 S_Status_RSPValid

General function

- Status information for the "Remanent safe position" safety function

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the following:

- The current safe position has been homed, validated and saved.
- Changes to the safe position are prevented by the active STO and SOS safety functions.
- Powering off the module does not result in loss of the safe remanent position.

SAFETRUE

The safe position has been saved successfully. Power off for homing with RSP is possible in this state.

SAFEFALSE

One or more of the following is true:

- The axis was not successfully homed. (The state of "S_Status_Homing" is not TRUE.)
- The STO safety function is not selected/active.
- The SOS safety function is not selected/active.
- The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.29 S_Status_SetPosAlive

General function

- Status information about plausibility check of the position setpoint

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies whether the plausibility of the position setpoint has been checked.

SAFETRUE

The plausibility of the position setpoint was checked successfully.

SAFEFALSE

The plausibility of the position setpoint was faulty or not checked. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.8.7.30 Error

General function

- Function block error message

Data type

- BOOL

Connection

- Variable

Function description

This formal parameter indicates a pending function block error message.

TRUE

The enabled function block detected an error. "DiagCode" indicates the error code.

FALSE

The function block is not enabled, or the enabled function block did not detect an error. "DiagCode" indicates the status.

> **Danger!**
>
> **It is your responsibility to ensure that all necessary corrective measures are initiated after an error occurs since subsequent errors can result in a hazard!**

In order to exit an error state ("Error" = TRUE), the signal on input "S_Control_Reset" must change from SAFEFALSE to SAFETRUE (positive edge).

8.8.7.31 DiagCode

General function

- Function block diagnostic message

Data type

- WORD

Connection

- Variable

Function description

This output parameter is used to output diagnostic and status messages specific to the function block and make them available automatically to diagnostic tools.

These diagnostic tools cannot acknowledge diagnostic messages from function blocks. This is done exclusively in the **safety** application.

The function block indicates the presence of an error message on the "DiagCode" output via the "Error" output parameter.

Diagnostic code

The diagnostic code is specified as data type WORD. The values and meanings of these diagnostic codes are listed below.

In the event of status messages (0xxx$_{hex}$, 8xxx$_{hex}$), the function block sets "Error" to FALSE.

In the event of error messages (Cxxx$_{hex}$), the function block sets "Error" to TRUE.

8.8.7.32 Overview of diagnostic codes

Diagnostic codes

Code (hex)	Description	Corrective measures
0000	The function block is not enabled. If "Activate" is connected to a variable that indicates the state of the connected safe device (active, inactive or peripheral fault detected), then the safe device is not active or has detected a fault in the connected peripheral.	• Enable the function block by setting "Activate" to SAFETRUE. • Enable the safe device if "Activate" is connected to a variable that indicates the state of a connected safe device (active, inactive or peripheral fault detected), or correct the fault in the peripheral according to the device description.
8000	The function block detected neither a status nor an error to set the enable output to SAFEFALSE.	• If this is a desired signal combination at the signal inputs, no action is required. • If the signal combination on the signal inputs is unintended, check the connected peripheral and correct any faults.
C001	The function set for the control byte was not found.	Check whether the required safety function is supported by the connected axis.
C002	The function set for the status byte was not found.	Check whether the required safety function is supported by the connected axis.
C003	The function set ID that was read does not match.	Check whether the required safety function is supported by the connected axis.
C004	The data length of the function set that was read is invalid.	Check whether the required safety function is supported by the connected axis.
C005	The status byte could not be read.	Check whether the required safety function is supported by the connected axis.
C006	The control byte could not be written.	Check whether the required safety function is supported by the connected axis.

Table 623: SF_oS_MOTION_(Basic, Speed, Advanced, AbsPos)_BR: Diagnostic codes

8.8.8 Signal sequence diagram of the function block

A general signal sequence diagram of the function block cannot be specified since it depends on which safety functions are selected or deselected.

See 6.4 "SafeMOTION user's manual / Safety technology / Integrated safety functions" on page 325.

8.9 SF_oS_MOTION_ScaledSpeed_BR

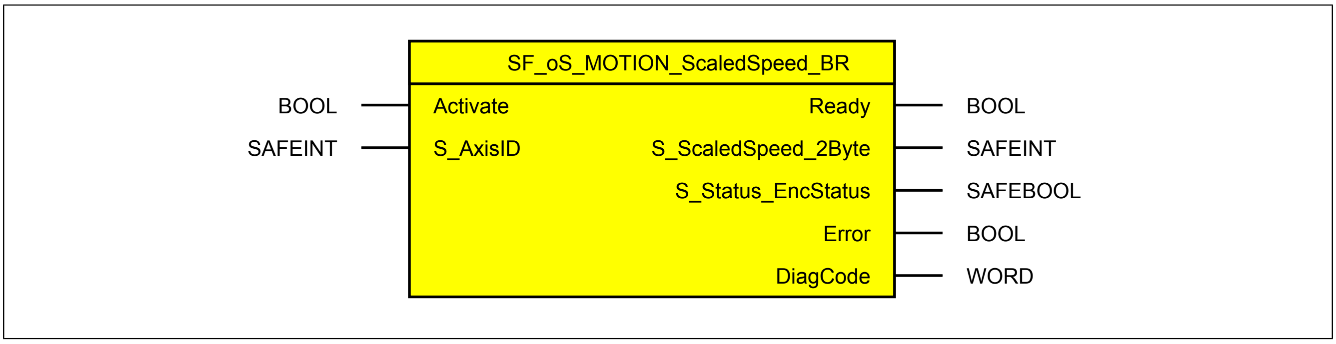


Figure 129: Function block SF_oS_MOTION_ScaledSpeed_BR

Information:

Library openSAFETY_BuR_Motion_SF can only be used to control ACOPOS P3 SafeMOTION servo drives.

Information:

It is mandatory for function block SF_oS_MOTION_Basic_BR to be applied to each axis being used in the safety application. Otherwise, the internal state machine of the axis remains in state IDLE, and pulse disabling and the holding brake output cannot be enabled.
Alternatively, function block SF_oS_MOTION_BR can be used; it represents the combination of all available function sets.

8.9.1 Formal parameters of the function block

In the following, the term "variable" refers to both a variable as well as a graphic connection.

Name	Type	Connection	Signal type [1]	Initial value	Description / General function
Activate	BOOL	Variable/ Constant	State	FALSE	Enables the function block (= TRUE) Input "Activate" according to the PLCopen standard
S_AxisID	SAFEINT	Constant	State	-1	Assigns an axis to the function block

Table 624: SF_oS_MOTION_ScaledSpeed_BR: Overview of input parameters

1) Evaluation of the input parameter signals in the function block. You must control the signals accordingly.

Name	Type	Connection	Signal type [1]	Initial value	Description / General function
Ready	BOOL	Variable	State	FALSE	Indicates that the function block is enabled Output **"Ready"** according to the PLCopen standard
S_ScaledSpeed_2Byte	SAFEINT	Variable	Value	-	Scaled safe speed
S_Status_EncStatus	SAFEBOOL	Variable	State	SAFEFALSE	No encoder error has been detected (i.e. SAFETRUE), signal "S_ScaledSpeed" is valid.
Error	BOOL	Variable	State	FALSE	Function block error message
DiagCode	WORD	Variable	State	16#0000	Function block diagnostic message

Table 625: SF_oS_MOTION_ScaledSpeed_BR: Overview of output parameters

1) Output of the output parameter signals. You must evaluate and/or further process the signals accordingly.

Type	Description	Size in bits	Format option
BOOL	Bit	1	Bit string
WORD	Word	16	Bit string
DINT	Double integer	32	Binary number, hexadecimal number, signed decimal number
SAFEBOOL	Bit	1	Bit string (signal source: safe device)
SAFEDWORD	Double word	32	Bit string (signal source: safe device)
SAFEDINT	Double integer	32	Binary number, hexadecimal number, signed decimal number (signal source: safe device)
SAFEINT	Integer	16	Binary number, hexadecimal number, signed decimal number (signal source: safe device)

Table 626: Format description of the data types

8.9.2 Function

The primary purpose of function block SF_oS_MOTION_ScaledSpeed_BR is to establish a connection between the safe speed of an axis and the associated encoder error status. An assignment is then made to a defined safe axis.

Function block SF_oS_MOTION_ScaledSpeed_BR can be used to process the current safe speed of an axis in the safety application.

> ## Danger!
>
> **Make sure that the correct "AxisID" is always used on the input!**
> **Each assignment must be validated separately.**

To ensure valid evaluation of the speed signal, the corresponding encoder error status bit must also always be checked.
The speed signal itself is only considered valid if this output parameter is set to SAFETRUE.

> ## Danger!
>
> **If the speed signal is not validated, then an invalid speed value could be used in the safety application.**
> **This can result in hazardous situations!**

8.9.3 Safe encoder connection

See 6.2.3.3 "Safe encoder connection" on page 307.

8.9.4 Fault avoidance

See 7.3.4 "Fault avoidance" on page 503.

8.9.5 Input parameters

Information:

For detailed information about individual safety functions, see "SafeMOTION user's manual / chapter "Safety technology" / Integrated safety functions"!

8.9.5.1 Activate

General function

- Enables the function block

Data type

- BOOL

Connection

- Constant or variable

Function description

This input parameter is used to activate the function block.

- When enabling or disabling safe devices, "Activate" must be linked to a variable that indicates the state (enabled or disabled) of the corresponding safe devices. This ensures that the function block does not output a triggered safety function as diagnostic information when a device is switched off.
- It is also possible to connect "Activate" to a constant (TRUE) in order to enable the function block.

TRUE

The function block is enabled.

FALSE

The function block is not enabled.
All binary output parameters are set to FALSE.
Sets the DiagCode diagnostic parameter to WORD#16#0000.

If you want to control function block diagnostics as needed in your diagnostic concept whenever error messages from safe devices and/or deactivated safe devices occur, connect "Activate" to a signal that indicates the status of the safe devices that are involved with the safety function supported by the function block. Form this signal using only safe devices whose I/O signals are connected to the function block via actual parameters. In this way, you prevent triggered safety functions from being reported by active safe devices. This measure is only used to control the diagnostic information from inactive safe devices in a defined manner.

8.9.5.2 S_AxisID

General function

- This input parameter assigns a real axis to the function block.

Data type

- SAFEINT

Connection

- Constant

Function description

The corresponding axis can be connected to the input in SafeDESIGNER using drag-and-drop.

> ## Information:
> **There is only permitted to be one combination of AxisID and function block SF_oS_MOTION_ScaledSpeed_BR in the safety application. Otherwise, it will not be possible to compile the safety application.**

8.9.6 Output parameters

Output parameters provide information about the state of the SafeMOTION module and the individual safety functions.

8.9.6.1 Ready

General function

- Message: Function block is enabled/disabled.

Data type

- BOOL

Connection

- Variable

Function description

This output parameter indicates whether the function block is enabled or not.

TRUE

The function block is enabled ("Activate" = TRUE). The output parameters indicate the current state of the safety function.

FALSE

The function block is not enabled ("Activate" = FALSE). The function block outputs are set to FALSE.

8.9.6.2 S_ScaledSpeed_2Byte

General function

- Indicates the current value of the scaled safe speed

Data type

- SAFEINT

Connection

- Variable

Function description

This output parameter indicates the current value of the scaled safe speed for a real axis.

> **Danger!**
>
> **The value of output parameter "S_ScaledSpeed_2BYTE" is valid if output parameter "S_Status_EncS-taus" is SAFETRUE. Otherwise, it is invalid and not permitted to be used further!**

8.9.6.3 S_Status_EncStatus

General function

- Information about the error state of the safe encoder signal

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the error state of the signal for a defined safe encoder.
If an encoder error is detected or the SafeMOTION module is in an error state, then the output is set to SAFEFALSE. This state is maintained until the error has been corrected.

SAFETRUE

An error was not detected on the encoder signal. The value of the safe speed on output "S_ScaledSpeed_2Byte" is valid.

SAFEFALSE

The encoder signal from a defined safe axis is faulty, or the axis itself is in an error state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled. For more information about the error, see the Safety Logger in Automation Studio.

> ## Danger!
>
> **The purpose of this signal is only to provide additional information. It only provides information in connection with the requested safety functions.**
> **S_Status_EncStatus does not represent the functional safe state of the SafeMOTION module!**

> ## Danger!
>
> **The value of output S_ScaledSpeed_2Byte is valid if output S_ Status_EncStatus is SAFETRUE. Otherwise, it is invalid and not permitted to be used further!**

8.9.6.4 Error

General function

- Function block error message

Data type

- BOOL

Connection

- Variable

Function description

This formal parameter indicates a pending function block error message.

TRUE

The enabled function block detected an error. "DiagCode" indicates the error code.

FALSE

The function block is not enabled, or the enabled function block did not detect an error. "DiagCode" indicates the status.

> ## Danger!
>
> **It is your responsibility to ensure that all necessary corrective measures are initiated after an error occurs since subsequent errors can result in a hazard!**

In order to exit an error state ("Error" = TRUE), the signal on input "S_Control_Reset" must change from SAFEFALSE to SAFETRUE (positive edge).

8.9.6.5 DiagCode

General function

- Function block diagnostic message

Data type

- WORD

Connection

- Variable

Function description

This output parameter is used to output diagnostic and status messages specific to the function block and make them available automatically to diagnostic tools.

These diagnostic tools cannot acknowledge diagnostic messages from function blocks. This is done exclusively in the **safety** application.

The function block indicates the presence of an error message on the "DiagCode" output via the "Error" output parameter.

Diagnostic code

The diagnostic code is specified as data type WORD. The values and meanings of these diagnostic codes are listed below.

In the event of status messages ($0xxx_{hex}$, $8xxx_{hex}$), the function block sets "Error" to FALSE.

In the event of error messages ($Cxxx_{hex}$), the function block sets "Error" to TRUE.

8.9.6.6 Overview of diagnostic codes

Diagnostic codes

Code (hex)	Description	Corrective measures
0000	The function block is not enabled. If "Activate" is connected to a variable that indicates the state of the connected safe device (active, inactive or peripheral fault detected), then the safe device is not active or has detected a fault in the connected peripheral.	• Enable the function block by setting "Activate" to SAFETRUE. • Enable the safe device if "Activate" is connected to a variable that indicates the state of a connected safe device (active, inactive or peripheral fault detected), or correct the fault in the peripheral according to the device description.
8000	The function block detected neither a status nor an error to set the enable output to SAFEFALSE.	• If this is a desired signal combination at the signal inputs, no action is required. • If the signal combination on the signal inputs is unintended, check the connected peripheral and correct any faults.
8001	There is no function set for this instance ID. 2 or 4 bytes not read.	Check whether the required safety function is supported by the connected axis.
C001	Could not read back position value properly from axis.	Check whether the required safety function is supported by the connected axis.
C003	The function set ID that was read does not match.	Check whether the required safety function is supported by the connected axis.
C004	The data length of the function set that was read is invalid.	Check whether the required safety function is supported by the connected axis.
C005	Could not read 2 or 4 bytes.	Check whether the required safety function is supported by the connected axis.

Table 627: SF_oS_MOTION_ScaledSpeed_BR: Diagnostic codes

8.9.7 Signal sequence diagram of function block

A signal sequence diagram cannot be specified for this function block.

8.10 SF_oS_MOTION_Position_BR

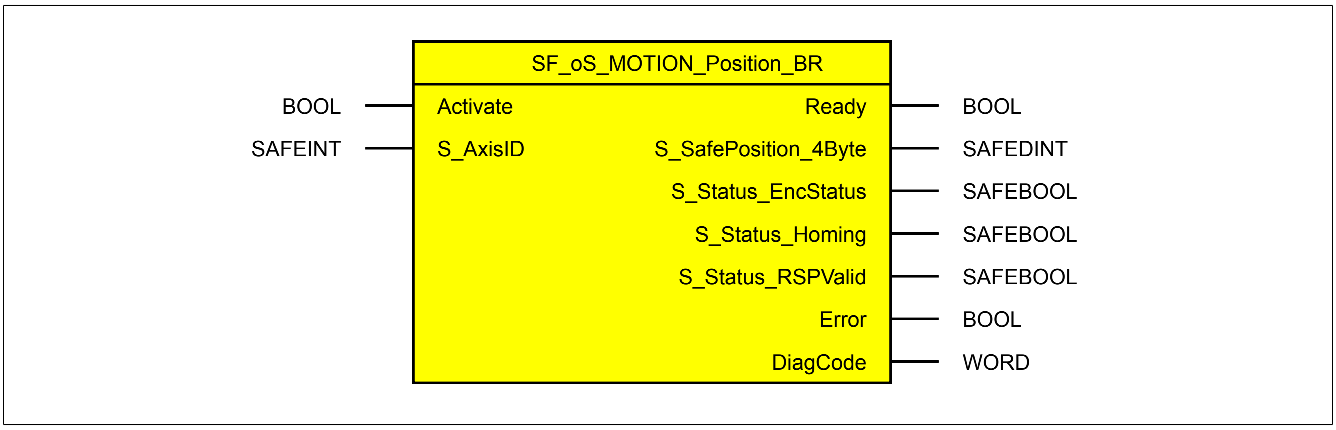


Figure 130: Function block SF_oS_MOTION_Position_BR

Information:

Library openSAFETY_BuR_Motion_SF can only be used to control ACOPOS P3 SafeMOTION servo drives.

Information:

It is mandatory for function block SF_oS_MOTION_Basic_BR to be applied to each axis being used in the safety application. Otherwise, the internal state machine of the axis remains in state IDLE, and pulse disabling and the holding brake output cannot be enabled.
Alternatively, function block SF_oS_MOTION_BR can be used; it represents the combination of all available function sets.

8.10.1 Formal parameters of the function block

In the following, the term "variable" refers to both a variable as well as a graphic connection.

Name	Type	Connection	Signal type [1)]	Initial value	Description / General function
Activate	BOOL	Variable/ Constant	State	FALSE	Enables the function block (= TRUE) Input "Activate" according to the PLCopen standard
S_AxisID	SAFEINT	Constant	State	-1	Assigns an axis to the function block

Table 628: SF_oS_MOTION_Position_BR: Overview of input parameters

1) Evaluation of the input parameter signals in the function block. You must control the signals accordingly.

Name	Type	Connection	Signal type [1)]	Initial value	Description / General function
Ready	BOOL	Variable	State	FALSE	Indicates that the function block is enabled Output "Ready" according to the PLCopen standard
S_SafePosition_4Byte	SAFEDINT	Variable	Value	-	Safe position in units
S_Status_EncStatus	SAFEBOOL	Variable	State	SAFEFALSE	No encoder error has been detected (i.e. SAFETRUE), signal "S_ScaledSpeed_2Byte" is valid.
S_Status_Homing	SAFEBOOL	Variable	State	SAFEFALSE	Specifies whether the safe position is valid (i.e. SAFETRUE, homing procedure has completed successfully and there are no encoder errors)
S_Status_RSPValid	SAFEBOOL	Variable	State	SAFEFALSE	Validates and stores the remanent safe position (RSP) (TRUE = safe position is stored, power off for homing with RSP is now possible)
Error	BOOL	Variable	State	FALSE	Function block error message
DiagCode	WORD	Variable	State	16#0000	Function block diagnostic message

Table 629: SF_oS_MOTION_Position_BR: Overview of output parameters

1) Output of the output parameter signals. You must evaluate and/or further process the signals accordingly.

Type	Description	Size in bits	Format option
BOOL	Bit	1	Bit string
WORD	Word	16	Bit string
DINT	Double integer	32	Binary number, hexadecimal number, signed decimal number

Table 630: Format description of the data types

Type	Description	Size in bits	Format option
SAFEBOOL	Bit	1	Bit string (signal source: safe device)
SAFEDWORD	Double word	32	Bit string (signal source: safe device)
SAFEDINT	Double integer	32	Binary number, hexadecimal number, signed decimal number (signal source: safe device)
SAFEINT	Integer	16	Binary number, hexadecimal number, signed decimal number (signal source: safe device)

Table 630: Format description of the data types

8.10.2 Function

The primary purpose of function block SF_oS_MOTION_Position_BR is to establish a connection between the safe position of an axis and the associated status. An assignment is then made to a defined safe axis.

Function block SF_oS_MOTION_Position_BR can be used to process the current safe position of an axis in the safety application.

> ## Danger!
>
> **Make sure that the correct AxisID is always used on the input!**
> **Each assignment must be validated separately.**

To ensure valid evaluation of the position signal, the corresponding status bit "S_Status_Homing" must also always be checked.
The position itself is only considered homed and valid if this output parameter is set to SAFETRUE.

> ## Danger!
>
> **If the position signal is not validated, then an invalid position could be used in the safety application.**
> **This can result in hazardous situations!**

8.10.3 Safe encoder connection

See 6.2.3.3 "Safe encoder connection" on page 307.

8.10.4 Fault avoidance

See 7.3.4 "Fault avoidance" on page 503.

8.10.5 Input parameters

Information:

For detailed information about individual safety functions, see "SafeMOTION user's manual / chapter "Safety technology" / Integrated safety functions"!

8.10.5.1 Activate

General function

- Enables the function block

Data type

- BOOL

Connection

- Constant or variable

Function description

This input parameter is used to activate the function block.

- When enabling or disabling safe devices, "Activate" must be linked to a variable that indicates the state (enabled or disabled) of the corresponding safe devices. This ensures that the function block does not output a triggered safety function as diagnostic information when a device is switched off.
- It is also possible to connect "Activate" to a constant (TRUE) in order to enable the function block.

TRUE

The function block is enabled.

FALSE

The function block is not enabled.
All binary output parameters are set to FALSE.
Sets the DiagCode diagnostic parameter to WORD#16#0000.

If you want to control function block diagnostics as needed in your diagnostic concept whenever error messages from safe devices and/or deactivated safe devices occur, connect "Activate" to a signal that indicates the status of the safe devices that are involved with the safety function supported by the function block. Form this signal using only safe devices whose I/O signals are connected to the function block via actual parameters. In this way, you prevent triggered safety functions from being reported by active safe devices. This measure is only used to control the diagnostic information from inactive safe devices in a defined manner.

8.10.5.2 S_AxisID

General function

- This input parameter assigns a real axis to the function block.

Data type

- SAFEINT

Connection

- Constant

Function description

The corresponding axis can be connected to the input in SafeDESIGNER using drag-and-drop.

> ## Information:
> **There is only permitted to be one combination of AxisID and SF_oS_MOTION_Position_BR in the safety application. Otherwise, it will not be possible to compile the safety application.**

8.10.6 Output parameters

Output parameters provide information about the state of the SafeMOTION module and the individual safety functions.

8.10.6.1 Ready

General function

- Message: Function block is enabled/disabled.

Data type

- BOOL

Connection

- Variable

Function description

This output parameter indicates whether the function block is enabled or not.

TRUE

The function block is enabled ("Activate" = TRUE). The output parameters indicate the current state of the safety function.

FALSE

The function block is not enabled ("Activate" = FALSE). The function block outputs are set to FALSE.

8.10.6.2 S_SafePosition_4Byte

General function

- Indicates the current safe position in units

Data type

- SAFEDINT

Connection

- Variable

Function description

This output parameter indicates the current value of the safe position for a real axis in units.

> **Danger!**
>
> **The value of output parameter "S_SafePosition_4Byte" is valid if output parameter "S_Status_EncStaus" is SAFETRUE. Otherwise, it is invalid and not permitted to be used further!**

8.10.6.3 S_Status_EncStatus

General function

- Information about the error state of the safe encoder signal

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the error state of the signal for a defined safe encoder.
If an encoder error is detected or the SafeMOTION module is in an error state, then the output is set to SAFEFALSE. This state is maintained until the error has been corrected.

SAFETRUE

An error was not detected on the encoder signal.

SAFEFALSE

The encoder signal from a defined safe axis is faulty, or the axis itself is in an error state. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled. For more information about the error, see the Safety Logger in Automation Studio.

> **Danger!**
>
> **The purpose of this signal is only to provide additional information. It only provides information in connection with the requested safety functions.**
> **"S_Status_EncStatus" does not represent the functional safe state of the SafeMOTION module!**

8.10.6.4 S_Status_Homing

General function

- Status information for safety function "Safe Homing" and the safe position

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter specifies whether or not safe homing of the axis has been completed and whether or not the position signal is valid.

SAFETRUE

The axis has been safely homed, and the safe position is valid.

SAFEFALSE

The axis has not yet been successfully homed; the encoder signal of the axis is faulty. The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.
The safe position is invalid!

> **Danger!**
>
> **The purpose of this signal is only to provide additional information.**
>
> **"S_Status_Homing" does not represent the functional safe state of the SafeMOTION module!**

> **Danger!**
>
> **The value of output parameter "S_SafePosition_4Byte" is only valid if output parameter S_SafePositionValid is SAFETRUE. Otherwise, it is invalid and is not permitted to be used further.**

8.10.6.5 S_Status_RSPValid

General function

- Status information for the "Remanent safe position" safety function

Data type

- SAFEBOOL

Connection

- Variable

Function description

This output parameter indicates the following:

- The current safe position has been homed, validated and saved.
- Changes to the safe position are prevented by the active STO and SOS safety functions.
- Powering off the module does not result in loss of the safe remanent position.

SAFETRUE

The safe position has been saved successfully. Power off for homing with RSP is possible in this state.

SAFEFALSE

One or more of the following is true:

- The axis was not successfully homed. (The state of "S_Status_Homing" is not TRUE.)
- The STO safety function is not selected/active.
- The SOS safety function is not selected/active.
- The SafeMOTION module is in an error state or the state machine of the safe axis or the function block itself was not enabled.

8.10.6.6 Error

General function

- Function block error message

Data type

- BOOL

Connection

- Variable

Function description

This formal parameter indicates a pending function block error message.

TRUE

The enabled function block detected an error. "DiagCode" indicates the error code.

FALSE

The function block is not enabled, or the enabled function block did not detect an error. "DiagCode" indicates the status.

> ## Danger!
>
> **It is your responsibility to ensure that all necessary corrective measures are initiated after an error occurs since subsequent errors can result in a hazard!**

In order to exit an error state ("Error" = TRUE), the signal on input "S_Control_Reset" must change from SAFEFALSE to SAFETRUE (positive edge).

8.10.6.7 DiagCode

General function

- Function block diagnostic message

Data type

- WORD

Connection

- Variable

Function description

This output parameter is used to output diagnostic and status messages specific to the function block and make them available automatically to diagnostic tools.

These diagnostic tools cannot acknowledge diagnostic messages from function blocks. This is done exclusively in the **safety** application.

The function block indicates the presence of an error message on the "DiagCode" output via the "Error" output parameter.

Diagnostic code

The diagnostic code is specified as data type WORD. The values and meanings of these diagnostic codes are listed below.

In the event of status messages ($0xxx_{hex}$, $8xxx_{hex}$), the function block sets "Error" to FALSE.

In the event of error messages ($Cxxx_{hex}$), the function block sets "Error" to TRUE.

8.10.6.8 Overview of diagnostic codes

Diagnostic codes

Code (hex)	Description	Corrective measures
0000	The function block is not enabled. If "Activate" is connected to a variable that indicates the state of the connected safe device (active, inactive or peripheral fault detected), then the safe device is not active or has detected a fault in the connected peripheral.	• Enable the function block by setting "Activate" to TRUE. • Enable the safe device if "Activate" is connected to a variable that indicates the state of a connected safe device (active, inactive or peripheral fault detected), or correct the fault in the peripheral according to the device description.
8000	The function block detected neither a status nor an error to set the enable output to SAFEFALSE.	• If this is a desired signal combination at the signal inputs, no action is required. • If the signal combination on the signal inputs is unintended, check the connected peripheral and correct any faults.
8001	There is no function set for this instance ID. 2 or 4 bytes not read.	Check whether the required safety function is supported by the connected axis.
C001	Could not read back position value properly from axis.	Check whether the required safety function is supported by the connected axis.
C003	The function set ID that was read does not match.	Check whether the required safety function is supported by the connected axis.
C004	The data length of the function set that was read is invalid.	Check whether the required safety function is supported by the connected axis.
C005	Could not read 2 or 4 bytes.	Check whether the required safety function is supported by the connected axis.

Table 631: SF_oS_MOTION_Position_BR: Diagnostic codes

8.10.7 Signal sequence diagram of function block

A signal sequence diagram cannot be specified for this function block.

8.11 Version history

Version	Date	Comment
1.00	October 2016	First edition

Table 632: Version history

9 SafeDESIGNER

See Integrated Safety user's manual (MASAFETY-ENG), Chapter "SafeDESIGNER".

10 Standards and certifications

10.1 Relevant European directives

- EMC Directive 2014/30/EU
- Low Voltage Directive 2014/35/EU
- Machinery Directive 2006/42/EC[36)]

10.2 Applicable standards

Standard	Description	Valid for		
		ACOPOS-multi SafeMOTION	ACOPOS-motor SafeMOTION	ACOPOS P3 SafeMOTION
EN 61800-2:2015	Adjustable speed electrical power drive systems • Part 2: General requirements; Rating specifications for low voltage adjustable frequency AC power drive systems	X	X	X
EN 61800-3:2004 +A1:2012	Adjustable speed electrical power drive systems • Part 3: EMC requirements and specific test methods	X	X	X
EN 61800-5-1:2007 +A1:2017	Adjustable speed electrical power drive systems • Part 5-1: Safety requirements - Electrical, thermal and energy	X	X	X
EN 61800-5-2:2017	Adjustable speed electrical power drive systems • Part 5-2: Safety requirements - Functional	X	X	X
EN 60204-1:2006 +AC:2010	Safety of machinery - Electrical equipment of machines • Part 1: General requirements	X	X	X
EN 61508:2010	Functional safety of electrical / electronic / programmable electronic safety-related systems	X	X	X
EN 1037:1995 +A1:2008	Safety of machinery - Prevention of unexpected startup	X	X	X
EN ISO 13849-1:2015	Safety of machinery - Safety-related parts of control systems • Part 1: General principles for design	X	X	X
EN 62061:2005 +Cor.:2010 +A1:2013 +A2:2015	Safety of machinery - Functional safety of safety-related electrical, electronic and programmable electronic control systems	X	X	X
EN 60034-1:2010 +AC:2010	Rotating electrical machines • Part 1: Rating and performance		X	
EN 60034-5:2001 +A1:2007	Rotating electrical machines • Part 5: Degrees of protection provided by the integral design of rotating electrical machines (IP code) - Classification		X	
EN 60034-6:1993	Rotating electrical machines • Part 6: Methods of cooling (IC code)		X	
EN 60034-7:1993 +A1:2001	Rotating electrical machines • Part 7: Classification of types of construction, mounting arrangements and terminal box position (IM code)		X	
EN 60034-11:2004	Rotating electrical machines • Part 11: Thermal protection		X	
EN 60034-14:2004 +A1:2007	Rotating electrical machines • Part 14: Mechanical vibration of certain machines with shaft heights 56 mm and higher – Measurement, evaluation and limits of vibration severity		X	
DIN ISO 281:2010-10	Rolling bearings – Dynamic load ratings and rating life (ISO 281:2007)		X	
DIN 580:2010-09	Lifting eye bolts		X	
DIN 3760:1996-09	Radial shaft seals		X	
DIN 6885-1:1968-08	Drive type fastenings without taper action – Parallel keys, keyways, deep pattern		X	
UL 508c Ed.3:2002 +Rev.:2013	Power conversion equipment	X	X	
UL 61800-5-1 Ed.1:2012	Power conversion equipment			X
UL 1004-1 Ed.2:2012 +Rev.:2013	Rotating electrical machines – General requirements		X	
CSA-C22.2 No. 274 Ed.2:2017	Adjustable speed drives	X	X	X

Table 633: Applicable standards

36) This machinery directive only applies to logic units for safety functions that are initially made available by B&R for sale or use.

10.2.1 Limit values

The limit values specified from section Mechanical conditions during operation to section Additional environmental limit values are taken from the product standard EN 61800 (or IEC 61800) for servo drives in industrial environments (Category C3[37]).

10.3 Environmental limits

10.3.1 Mechanical conditions in accordance with EN 61800-2

Operation

ACOPOSmulti SafeMOTION

IEC 60721-3-3, class 3M1	
	EN 61800-2
Vibration during operation 2 ≤ f < 9 Hz 9 ≤ f < 200 Hz	 0.3 mm amplitude 1 m/s² acceleration

Table 634: Mechanical conditions during operation

ACOPOSmotor SafeMOTION

IEC 60721-3-3, class 3M7	
	EN 61800-2
Vibration during operation 2 ≤ f < 9 Hz 9 ≤ f < 200 Hz	 10 mm amplitude 30 m/s² acceleration

Table 635: Mechanical conditions during operation

ACOPOS P3 SafeMOTION

IEC 60721-3-3, class 3M4	
	EN 61800-2
Vibration during operation 2 ≤ f < 9 Hz 9 ≤ f < 200 Hz	 3 mm amplitude 10 m/s² acceleration

Table 636: Mechanical conditions during operation

Transport

ACOPOSmulti SafeMOTION, ACOPOSmotor SafeMOTION

IEC 60721-3-2, class 2M1	
	EN 61800-2
Vibration during transport [1)2)] 2 ≤ f < 9 Hz 9 ≤ f < 200 Hz 200 ≤ f < 500 Hz	 3.5 mm amplitude 10 m/s² acceleration 15 m/s² acceleration
Drop height in free fall [1)] Weight < 100 kg	 0.25 m

Table 637: Mechanical conditions during transport

1) Only valid for components in original packaging.
2) The values for "Vibration during operation" apply to components that are not in their original packaging.

ACOPOS P3 SafeMOTION

IEC 60721-3-2, class 2M2	
	EN 61800-2
Vibration during transport [1) 2)] 2 ≤ f < 9 Hz 9 ≤ f < 200 Hz 200 ≤ f < 500 Hz	 3.5 mm amplitude 10 m/s² acceleration 15 m/s² acceleration
Drop height in free fall [1)] Weight <10 kg	 0.8 m [3)]

Table 638: Mechanical conditions during transport

1) Only valid for components in original packaging.
2) The values for "Vibration during operation" apply to components that are not in their original packaging.
3) Fall height in accordance with EN ISO 4180

[37)] EN 61800-3 C3 (second environment).

10.3.2 Climate conditions in accordance with EN 61800-2

Operation

IEC 60721-3-3, class 3K3	
	EN 61800-2
Ambient temperature during operation	5 to 55°C
Relative humidity during operation	5 - 85%, non-condensing

Table 639: Climate conditions during operation

Storage

IEC 60721-3-1, class 1K4	
	EN 61800-2
Storage temperature	-25 to 55°C

Table 640: Climate conditions during storage (temperature)

IEC 60721-3-1, class 1K3	
	EN 61800-2
Relative humidity during storage	5 to 95%, non-condensing

Table 641: Climate conditions during storage (relative humidity)

Transport

IEC 60721-3-2, class 2K3	
	EN 61800-2
Transport temperature	-25 to 70°C
Relative humidity during transport	Max. 95% at 40°C

Table 642: Climate conditions during transport

10.4 Requirements for immunity to disturbances (EMC)

- EN 61800-3 requirements apply.
- For all modules that have certified safety functions, stricter requirements apply for section 4.3 "High-frequency disturbances per EN 61800-3" per IEC 61800-5-2.

10.4.1 Evaluation criteria (performance criteria)

Performance criteria (PC)	Description
A	The test object is not interfered with during testing.
B	The test object is only interfered with temporarily during testing.
C	The system does not reboot itself automatically (reset required).
FS	Functional safety - Behavior of test object per EN 61800-5-2, item 6.2.5.3

Table 643: Evaluation criteria (performance criteria) for immunity to disturbances

10.4.2 Low-frequency disturbances in accordance with EN 61800-3

The following limit values are applicable for industrial environments (category C3).

Power mains harmonics and commutation notches / voltage distortions

IEC 61000-2-4, class 3		
	EN 61800-3	**Performance criteria**
Harmonics	THD = 12%	A

Table 644: Limit values for power mains harmonics

IEC 60146-1-1, class B		
	EN 61800-3	**Performance criteria**
Commutation notches	Depth = 40%, Total area = 250% in % degrees	A

Table 645: Limit values for commutation notches / voltage distortions

Voltage deviations, voltage dips and short-term interruptions

IEC 61000-2-4, class 2		
	EN 61800-3	**Performance criteria**
Voltage deviations (>60 s)	±10%	A

Table 646: Limit values for voltage deviations

IEC 61000-4-34, class 3			
	EN 61800-3		**Performance criteria**
	Remaining voltage	Periods	
Voltage dips	0% 40% 70% 80%	1 10/12 1) 25/30 1) 250/300 1)	C
Short-term interruptions	0%	250/300 1)	

Table 647: Limit values for voltage dips and short-term interruptions

1) "x/y periods" means "x periods for 50 Hz test" and "y periods for 60 Hz test".

Voltage unbalance and frequency changes

IEC 61000-2-4, class 3		
	EN 61800-3	**Performance criteria**
Voltage unbalance	3% of negative component	A

Table 648: Limit values for voltage unbalance

IEC 61000-2-4		
	EN 61800-3	**Performance criteria**
Frequency changes	±2% (±4% if the power supply is isolated from public power supply networks)	A
Speed of frequency change	1%/s (2%/s if the power supply is isolated from public power supply networks)	

Table 649: Limit values for frequency changes

10.4.3 High-frequency disturbances in accordance with EN 61800-3

These immunity tests are applicable for industrial environments (category C3).

Electrostatic discharge

Tests in accordance with EN 61000-4-2				
	EN 61800-3		**Increased immunity to disturbances**	
	Requirement	**PC**	**Requirement** [1)]	**PC**
Contact discharge to powder-coated and bare metal housing parts	4 kV	B	6 kV	FS
Discharge through the air to plastic housing parts	8 kV		15 kV	

Table 650: Limit values for electrostatic discharge

1) The total number of discharges depends on the required safety integrity level (SIL) and can be found in IFA (formerly BGIA): EMC and functional safety for power drive systems 2/2012.

Electromagnetic fields

Tests in accordance with EN 61000-4-3				
	EN 61800-3		**Increased immunity to disturbances**	
	Requirement	**PC**	**Requirement**	**PC**
Housing	80 MHz to 1000 MHz 10 V/m 80% amplitude modulation (1 kHz)	A	80 MHz to 1000 MHz 20 V/m 80% amplitude modulation (1 kHz)	FS
	1.4 GHz to 2.0 GHz 3 V/m 80% amplitude modulation (1 kHz)		1.4 GHz to 2.0 GHz 10 V/m 80% amplitude modulation (1 kHz)	
	2.0 GHz to 2.7 GHz 1 V/m 80% amplitude modulation (1 kHz)		2.0 GHz to 2.7 GHz 3 V/m 80% amplitude modulation (1 kHz)	

Table 651: Limit values for electromagnetic fields

Burst

Tests in accordance with EN 61000-4-4				
	EN 61800-3		**Increased immunity to disturbances**	
	Requirement	**PC**	**Requirement** [1)]	**PC**
Power supply connections	2 kV, 1 min, direct coupling	B	4 kV, direct coupling	FS
Connections for process measurement, open-loop and closed-loop process control	2 kV, 1 min		4 kV	
Signal interfaces	1 kV, 1 min		2 kV	

Table 652: Limit values for burst

1) The duration of the effect depends on the required safety integrity level (SIL) and can be found in IFA (formerly BGIA): EMC and functional safety for power drive systems 2/2012.

Surge

Tests in accordance with EN 61000-4-5				
	EN 61800-3		**Increased immunity to disturbances**	
	Requirement	**PC**	**Requirement** [1)]	**PC**
Power supply connections	1 kV, DM, symmetrical 2 kV, CM, asymmetrical	B	2 kV, DM, symmetrical 4 kV, CM, asymmetrical	FS
Connections for process measurement, open-loop and closed-loop process control	1 kV, CM, asymmetrical		2 kV, CM, asymmetrical	
Signal interfaces	---		0.5 kV, CM, asymmetrical	

Table 653: Limit values for surge

1) The number of pulses depends on the required safety integrity level (SIL) and can be found in IFA (formerly BGIA): EMC and functional safety for power drive systems 2/2012.

High-frequency conducted disturbances

Tests in accordance with EN 61000-4-6				
	EN 61800-3		**Increased immunity to disturbances**	
	Requirement	**PC**	**Requirement**	**PC**
Power supply connections	0.15 MHz to 80 MHz 10 V 80% amplitude modulation (1 kHz)	A	0.15 MHz to 80 MHz 20 V 80% amplitude modulation (1 kHz)	FS
Connections for process measurement, open-loop and closed-loop process control				
Signal interfaces				

Table 654: Limit values for high-frequency conducted disturbances

10.5 Requirements for emissions (EMC)

10.5.1 High-frequency emissions in accordance with EN 61800-3

These emission tests are applicable for industrial environments (category C3).

Disturbance voltages on the mains connections

Tests in accordance with EN 55011			
Continuous current I	**Frequency band [MHz]**	**Quasi-peak value [dB (µV)]**	**Average value [dB (µV)]**
I ≤ 100 A	0.15 ≤ f < 0.5	100	90
	0.5 ≤ f < 5	86	76
	5 ≤ f < 30	90 Decreases with the logarithm of the frequency to 70	80 Decreases with the logarithm of the frequency to 60
100 A < I	0.15 ≤ f < 0.5	130	120
	0.5 ≤ f < 5	125	115
	5 ≤ f < 30	115	105

Table 655: Limit values for disturbance voltages on power mains connection

Radiated emissions

Tests in accordance with EN 55011	
Frequency band [MHz]	**Limit values of the quasi-peak value [dB (µV/m)]**
30 ≤ f ≤ 230	50 [1)]
230 < f < 1000	60 [1)]

Table 656: Limit values for radiated emissions

1) Test distance 10 m.

10.6 Additional environmental limit values in accordance with EN 61800-2

ACOPOSmulti SafeMOTION, ACOPOS P3 SafeMOTION

	EN 61800-2
Pollution degree in accordance with EN 61800-5-1	2 (non-conductive pollution)
Overvoltage category in accordance with EN 61800-5-1	III
EN 60529 protection	IP20
Reduction of the continuous current at installation elevations over 500 m above sea level	10% per 1000 m
Maximum installation elevation	4000 m [1)]

Table 657: Additional environmental limit values

1) Requirements that go beyond this must be arranged with B&R.

ACOPOSmotor SafeMOTION

	EN 61800-2
Pollution degree in accordance with EN 61800-5-1	2 (non-conductive pollution)
Overvoltage category in accordance with EN 61800-5-1	III
EN 60529 protection	IP65
Reduction of the continuous current at installation elevations over 500 m above sea level	10% per 1000 m
Maximum installation elevation	4000 m [1)]

Table 658: Additional environmental limit values

1) Requirements that go beyond this must be arranged with B&R.

10.7 International certifications

B&R products and services comply with applicable standards. This includes international standards from organizations such as ISO, IEC and CENELEC, as well as national standards from organizations such as UL, CSA, FCC, VDE, ÖVE, etc. We are committed to ensuring the reliability of our products in an industrial environment.

Certifications	
Europe	B&R products with this mark satisfy all harmonized EN standards for the applicable guidelines.
USA and Canada E225616	B&R products with this mark are tested and listed by Underwriters Laboratories and checked quarterly by a UL inspector. This mark is valid for the USA and Canada and simplifies the certification of your machines and systems in these regions.
	Products with this mark have been tested by an accredited testing laboratory and approved for import to the Russian Federation.
	Products with this mark have been tested by an accredited testing laboratory and approved for import to the Eurasian Economic Union.
	Products with this mark have been tested by an accredited testing laboratory and approved for import to the Korean market.
open SAFETY certified product	Products with this mark were designed, developed and manufactured for special applications for machine and personnel protection. The products are certified by the recognized authorities (TÜV Rheinland, TÜV Süd).

Table 659: International certifications

10.8 Standards and definitions for safety technology

Stop functions per EN 60204-1 (Electrical equipment of machines, Part 1: General requirements)

There are three categories of stop functions:

Category	Description
0	Stopping by immediate removal of power to the machine actuators (i.e. an uncontrolled stop).
1	A controlled stop with power left available to the machine actuators to allow for stopping. Power is only interrupted when standstill is achieved.
2	A controlled stop with power left available to the machine actuators.

Table 660: Overview of stop function categories

The necessary stop functions must be determined based on a risk assessment of the machine. Category 0 and category 1 stop functions must be functional regardless of operating mode. A category 0 stop must have priority. Stop functions must have priority over assigned start functions. Resetting the stop function is not permitted to trigger a dangerous state.

Emergency stops per IEC 60204-1:2006 (Electrical equipment of machines, Part 1: General requirements)

In addition to the requirements for stop functions, the emergency stop function has the following requirements:

- It shall override all other functions and operations in all modes.
- Power to the machine actuators that can cause a hazardous situation shall be removed as quickly as possible without creating other hazards.
- A reset is not permitted to initiate a restart.

Emergency stops must be category 0 or category 1 stop functions. The necessary stop function must be determined based on a risk assessment of the machine.

Performance levels (PL) per EN ISO 13849-1 (Safety of machinery - Safety-related parts of control systems, Part 1: General principles for design)

The safety-related parts of control systems must meet one or more of the requirements for five defined performance levels. These performance levels define the required behavior of safety-related controller parts with regard to their resistance to errors.

Performance level (per EN ISO 13849-1)	Safety integrity level - SIL (per IEC 61508-2)	Short description	System behavior
a	---	Safety-related components must be designed and built in such away that they can meet the expected operational requirements (no specific safety measures are implemented).	**Caution!** **The occurrence of a fault can lead to the loss of safety functionality.**
b	1	Safety-related components must be designed and built in such a way that only reliable components and safety principles are used (e.g. preventing short circuits by using sufficient distances, reducing the probability of errors by using oversized components, defining the failure route, idle current principle, etc.).	**Caution!** **The occurrence of a fault can lead to the loss of safety functionality.**
c	1	Safety related parts shall be designed so that their safety functions shall be checked at suitable intervals by the machine control system. (e.g. automatic or manual check during start-up)	**Caution!** **An error between checks can cause the loss of safety functionality. The loss of safety functionality will be detected during the check.**
d	2	Safety-related parts shall be designed so that a single fault does not lead to the loss of the safety function. Individual errors should – if possible – be detected the next time (or before) the safety function is required.	**Caution!** **Safety functionality remains active when an error occurs. Some but not all errors are detected. A buildup of undetected errors can cause safety functionality to fail.**
e	3	Safety-related parts shall be designed so that a single fault does not lead to the loss of the safety function. Individual errors must be detected the next time (or before) the safety function is required. If this type of detection is not possible, a buildup of errors is not permitted to cause safety functionality to fail.	**Information:** **Safety functionality remains active when an error occurs. Errors are detected in time to prevent safety functionality from failing.**

Table 661: Overview of performance levels (PL)

A suitable performance level must be selected separately for each drive system (or for each axis) based on a risk assessment. This risk assessment is a part of the total risk assessment for the machine.

The following risk graph (per EN ISO 13849-1, appendix A) provides a simplified procedure for risk assessment:

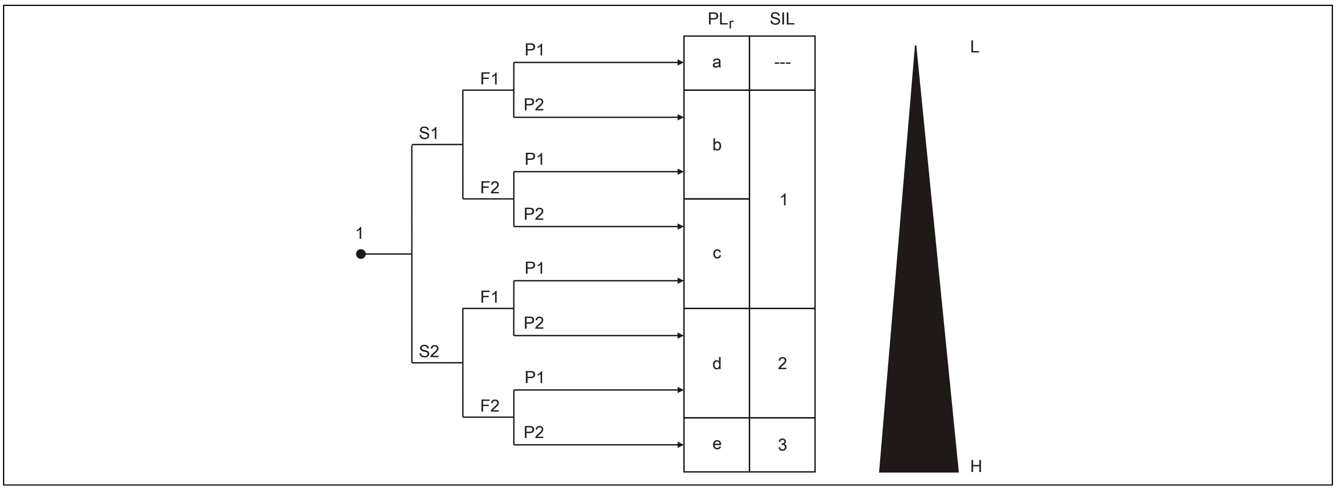


Figure 131: Risk diagram for determining the PL_r for each safety function per EN ISO 13849-1, appendix A

Legend:

1	Starting point for assessing the impact on risk reduction
L	Low contribution to risk reduction
H	High contribution to risk reduction
PL_r	Required performance level
SIL	Safety Integrity Level per IEC 61508-2

Risk parameters

S	Severity of injury
S1	Slight (normally reversible injury)
S2	Serious (normally irreversible injury or death)
F	Frequency and/or duration of the exposure to the hazard
F1	Seldom to less often and/or exposure time is short.
F2	Frequent to continuous and/or exposure time is long.
P	Possibility of avoiding hazard or limiting harm
P1	Possible under specific conditions
P2	Scarcely possible

The performance level to be used is determined by starting at the specified starting point and taking the risk parameters S, F and P into consideration.

Appendix A EC declaration of conformity

This document was originally written in the German language. The German edition therefore represents the original documentation in accordance with the 2006/42/EC Machinery Directive. Documents in other languages are to be interpreted as translations of the original documentation.

Product manufacturer:

B&R Industrial Automation GmbH

B&R Strasse 1

5142 Eggelsberg

Austria

Telephone: +43 7748 6586-0

Fax: +43 7748 6586-26

office@br-automation.com

The place of jurisdiction, in accordance with article 17 of the European Convention on Courts of Jurisdiction and Enforcement, is A-4910

Ried im Innkreis, Austria, commercial register court: Ried im Innkreis, Austria

Commercial register number: FN 111651 v.

The place of fulfillment in accordance with article 5 of the European Convention on Courts of Jurisdiction and Enforcement is A-5142 Eggelsberg, Austria

VATIN: ATU62367156

The EC declarations of conformity for B&R products can be downloaded from the B&R website www.br-automation.com.

Appendix B Safety level overview for ACOPOS product family safety functions

Standard safety technology ("hardwired safety technology")

Safety function	ACOPOS	ACOPOSmulti	ACOPOS P3	ACOPOSmotor	ACOPOSremote	ACOPOSmicro
Enable (STO)	Cat. 3 / PL d / SIL 2	Cat. 4 / PL e / SIL 3	Cat. 4 / PL e / SIL 3	Cat. 4 / PL e / SIL 3	Cat. 4 / PL e / SIL 3	Cat. 3 / PL d / SIL 2
SS1, SS2 With corresponding external wiring	Cat. 3 / PL d / SIL 2[1]	Cat. 4 / PL e / SIL 3[1]	Cat. 4 / PL e / SIL 3[1]	Cat. 4 / PL e / SIL 3[1]	Cat. 4 / PL e / SIL 3[1]	Cat. 3 / PL d / SIL 2[1]
SOS and SLS With corresponding external wiring	Cat. 3 / PL d / SIL 2[1]	Cat. 4 / PL e / SIL 3[1]	Cat. 4 / PL e / SIL 3[1]	Cat. 4 / PL e / SIL 3[1]	Cat. 4 / PL e / SIL 3[1]	Cat. 3 / PL d / SIL 2[1]

Table 662: Safety level for standard safety technology

1) The actual safety level that can be achieved depends on the external wiring!

SafeMOTION integrated safety technology ("network-based safety technology")

Safety function[2]	ACOPOSmulti SafeMOTION		ACOPOSmotor SafeMOTION	ACOPOS P3 SafeMOTION
	EnDat 2.2	SinCos[1]		
STO	Cat. 4 / PL e / SIL 3	Cat. 4 / PL e / SIL 3	Cat. 4 / PL e / SIL 3	Cat. 4 / PL e / SIL 3
STO, single-channel	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
SBC	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
SOS	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
SS1 with time monitoring	Cat. 4 / PL e / SIL 3	Cat. 4 / PL e / SIL 3	Cat. 4 / PL e / SIL 3	Cat. 4 / PL e / SIL 3
SS1 with ramp monitoring	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
SS2	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
SLS	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
SDI	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
SLI	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
SLA	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
SMS	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
SLP	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
SMP	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
Safe Homing	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
SBT	No	Cat. 3 / PL d / SIL 2	No	Cat. 3 / PL d / SIL 2
RSP	Cat. 3 / PL d / SIL 2	No	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
SLT	No	No	No	Cat. 3 / PL d / SIL 2

Table 663: Safety level for SafeMOTION integrated safety technology

1) In order to achieve Cat. 4 / PL e / SIL 3, special certified encoders are needed that meet B&R's catalog of requirements.
Only 1-axis modules are available for ACOPOSmulti SafeMOTION SinCos inverter modules due to the amount of space inside the device.
2) The safety functions are configured using SafeDESIGNER.

B&R motors for applications with SafeMOTION integrated safety technology

Safety function	B&R motor options				
	S0, S1 [2] SA, SB [2] DA, DB [2] D4, D5 [2] D8, D9 [2] Z8, Z9 [2]	D0, D1 [1)2)] B8, B9 [1)2)]	E0, E1, E4, E5, E6, E7 [1)2)]	E2, E3, E8, E9, EA, EB	Resolver
STO	Cat. 4 / PL e / SIL 3				
STO, single-channel	Cat. 3 / PL d / SIL 2				
SBC[3]	No				
SOS	Cat. 3 / PL d / SIL 2		Cat. 2 / PL d / SIL 2	No	No
SS1 with time monitoring	Cat. 4 / PL e / SIL 3				
SS1 with ramp monitoring	Cat. 3 / PL d / SIL 2		Cat. 2 / PL d / SIL 2	No	No
SS2	Cat. 3 / PL d / SIL 2		Cat. 2 / PL d / SIL 2	No	No
SLS	Cat. 3 / PL d / SIL 2		Cat. 2 / PL d / SIL 2	No	No
SDI	Cat. 3 / PL d / SIL 2		Cat. 2 / PL d / SIL 2	No	No
SLI	Cat. 3 / PL d / SIL 2		Cat. 2 / PL d / SIL 2	No	No
SLA	Cat. 3 / PL d / SIL 2		Cat. 2 / PL d / SIL 2	No	No
SMS	Cat. 3 / PL d / SIL 2		Cat. 2 / PL d / SIL 2	No	No
SLP	Cat. 3 / PL d / SIL 2	No	No	No	No
SMP	Cat. 3 / PL d / SIL 2	No	No	No	No

Table 664: Safety level for SafeMOTION integrated safety technology with B&R motors

Safety function	B&R motor options				
	S0, S1 [2] **SA, SB** [2] **DA, DB** [2] **D4, D5** [2] **D8, D9** [2] **Z8, Z9** [2]	**D0, D1** [1,2] **B8, B9** [1,2]	**E0, E1, E4, E5, E6, E7** [1,2]	**E2, E3, E8, E9, EA, EB**	**Resolver**
Safe Homing	Cat. 3 / PL d / SIL 2	No	No	No	No
SBT[4]	Cat. 3 / PL d / SIL 2		Cat. 2 / PL d / SIL 2	No	No
RSP	Cat. 3 / PL d / SIL 2		No	No	No
SLT[4]	Cat. 3 / PL d / SIL 2				

Table 664: Safety level for SafeMOTION integrated safety technology with B&R motors

1) Motors with a B8, B9, D0, D1, E0, E1, E4, E5, E6 or E7 encoder option do not have a safety-oriented encoder mount. For information regarding their limited use, see chapter "Safety technology - Safe monitoring without fault exclusion" of the SafeMOTION user's manual.
2) B&R motor and encoder cables must be used (see SafeMOTION user's manual).
3) Safety function SBC for safety-oriented control of a safe motor holding brake achieves a maximum safety level of Cat. 3 / PL d / SIL 2 depending on the safety level of the motor holding brake being controlled.
4) Only for synchronous motors.

Third-party motors for applications with SafeMOTION integrated safety technology

Safety function	EnDat22[6] 3rd-party motors[3]	EnDat01[6] 3rd-party motors[3]	SinCos 3rd-party motors[2,3]
STO	Cat. 4 / PL e / SIL 3	Cat. 4 / PL e / SIL 3	Cat. 4 / PL e / SIL 3
STO, single-channel	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
SBC[4]	No		
SOS	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3
SS1 with time monitoring	Cat. 4 / PL e / SIL 3	Cat. 4 / PL e / SIL 3	Cat. 4 / PL e / SIL 3
SS1 with ramp monitoring	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3
SS2	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3
SLS	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3
SDI	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3
SLI	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3
SLA	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3
SMS	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3
SLP[1]	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3
SMP[1]	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Max. Cat. 4 / PL e / SIL 3
Safe Homing[1]	Cat. 3 / PL d / SIL 2	No	Max. Cat. 4 / PL e / SIL 3
SBT[5]	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2	Cat. 3 / PL d / SIL 2
RSP	Cat. 3 / PL d / SIL 2	No	No
SLT[5]	Cat. 3 / PL d / SIL 2		

Table 665: Safety level for SafeMOTION integrated safety technology with 3rd-party motors

1) This safety function can only be used if a third-party motor is demonstrably equipped with a safe encoder mounting.
2) ACOPOSmulti SafeMOTION SinCos inverter modules are certified up to Cat. 4 / PL e / SIL 3. In order to achieve this level, special certified encoders are needed that meet B&R's catalog of requirements.
3) When using third-party motors for applications with FS (functional safety), other measures may need to be taken (e.g. using B&R motor and encoder cables). In addition, the catalog of measures from manufacturers of products (e.g. encoder manufacturer) used throughout the entire safety system must be taken into consideration. For details, see the SafeMOTION user's manual.
4) Safety function SBC for safety-oriented control of a safe motor holding brake achieves a maximum safety level of Cat. 3 / PL d / SIL 2 depending on the safety level of the motor holding brake being controlled.
5) Only for synchronous motors.
6) Model number (with regard to incremental signals) of manufacturer DR. JOHANNES HEIDENHAIN GmbH (www.heidenhain.de)

Danger!

The safety functions used are only permitted to be configured and used as described in 6.4 "Integrated safety functions" on page 325.

Danger!

The steps listed under 6.7.5 "Maintenance scenarios" on page 491 must be observed.

3

A

C

D

E

G

H

I

M

O

P

Q

R

S

T

W

Publishing information

B&R Industrial Automation GmbH

B&R Strasse 1

5142 Eggelsberg

Austria

Telephone: +43 7748 6586-0

Fax: +43 7748 6586-26

office@br-automation.com