

INTERNATIONAL STANDARD

**Adjustable speed electrical power drive systems –
Part 7-201: Generic interface and use of profiles for power drive systems –
Profile type 1 specification**

This document is a preview generated by EVS



THIS PUBLICATION IS COPYRIGHT PROTECTED

Copyright © 2007 IEC, Geneva, Switzerland

All rights reserved. Unless otherwise specified, no part of this publication may be reproduced or utilized in any form or by any means, electronic or mechanical, including photocopying and microfilm, without permission in writing from either IEC or IEC's member National Committee in the country of the requester.

If you have any questions about IEC copyright or have an enquiry about obtaining additional rights to this publication, please contact the address below or your local IEC member National Committee for further information.

IEC Central Office
3, rue de Varembe
CH-1211 Geneva 20
Switzerland
Email: inmail@iec.ch
Web: www.iec.ch

About the IEC

The International Electrotechnical Commission (IEC) is the leading global organization that prepares and publishes International Standards for all electrical, electronic and related technologies.

About IEC publications

The technical content of IEC publications is kept under constant review by the IEC. Please make sure that you have the latest edition, a corrigenda or an amendment might have been published.

- Catalogue of IEC publications: www.iec.ch/searchpub

The IEC on-line Catalogue enables you to search by a variety of criteria (reference number, text, technical committee,...). It also gives information on projects, withdrawn and replaced publications.

- IEC Just Published: www.iec.ch/online_news/justpub

Stay up to date on all new IEC publications. Just Published details twice a month all new publications released. Available on-line and also by email.

- Electropedia: www.electropedia.org

The world's leading online dictionary of electronic and electrical terms containing more than 20 000 terms and definitions in English and French, with equivalent terms in additional languages. Also known as the International Electrotechnical Vocabulary online.

- Customer Service Centre: www.iec.ch/webstore/custserv

If you wish to give us your feedback on this publication or need further assistance, please visit the Customer Service Centre FAQ or contact us:

Email: csc@iec.ch
Tel.: +41 22 919 02 11
Fax: +41 22 919 03 00

Document for Preview generated by EVS



INTERNATIONAL STANDARD

**Adjustable speed electrical power drive systems –
Part 7-201: Generic interface and use of profiles for power drive systems –
Profile type 1 specification**

INTERNATIONAL
ELECTROTECHNICAL
COMMISSION

PRICE CODE

CONTENTS

| | |
|---|----|
| FOREWORD..... | 14 |
| INTRODUCTION..... | 16 |
| 1 Scope..... | 19 |
| 2 Normative references..... | 19 |
| 3 Terms, definitions and abbreviated terms..... | 19 |
| 3.1 Terms and definitions..... | 19 |
| 3.2 Abbreviated terms..... | 23 |
| 4 General..... | 24 |
| 4.1 General considerations..... | 24 |
| 4.2 Communication interface..... | 24 |
| 4.3 Object dictionary..... | 25 |
| 5 Data types..... | 25 |
| 5.1 Standard data types..... | 25 |
| 5.2 Record definitions..... | 26 |
| 6 General object definitions..... | 27 |
| 6.1 General..... | 27 |
| 6.2 Communication parameter objects..... | 27 |
| 6.3 Additional identification and information objects..... | 28 |
| 6.3.1 Object 6402 _h : Motor type..... | 28 |
| 6.3.2 Object 6403 _h : Motor catalogue number..... | 29 |
| 6.3.3 Object 6404 _h : Motor manufacturer..... | 29 |
| 6.3.4 Object 6405 _h : http motor catalogue address..... | 30 |
| 6.3.5 Object 6406 _h : Motor calibration date..... | 30 |
| 6.3.6 Object 6407 _h : Motor service period..... | 31 |
| 6.3.7 Object 6503 _h : Drive catalogue number..... | 31 |
| 6.3.8 Object 6505 _h : http drive catalogue address..... | 32 |
| 7 Error codes and error behaviour..... | 32 |
| 7.1 Error codes..... | 32 |
| 7.2 Error behavior..... | 36 |
| 8 Controlling the power drive system..... | 37 |
| 8.1 General..... | 37 |
| 8.2 Finite state automaton..... | 37 |
| 8.3 Modes of operation..... | 40 |
| 8.4 Detailed object specifications..... | 41 |
| 8.4.1 Object 6040 _h : Controlword..... | 41 |
| 8.4.2 Object 6041 _h : Statusword..... | 42 |
| 8.4.3 Object 603F _h : Error code..... | 43 |
| 8.4.4 Object 6007 _h : Abort connection option code..... | 44 |
| 8.4.5 Object 605A _h : Quick stop option code..... | 45 |
| 8.4.6 Object 605B _h : Shutdown option code..... | 46 |
| 8.4.7 Object 605C _h : Disable operation option code..... | 46 |
| 8.4.8 Object 605D _h : Halt option code..... | 47 |
| 8.4.9 Object 605E _h : Fault reaction option code..... | 48 |
| 8.4.10 Object 6060 _h : Modes of operation..... | 49 |
| 8.4.11 Object 6061 _h : Modes of operation display..... | 50 |

| | | |
|---------|--|----|
| 8.4.12 | Object 6502 _h : Supported drive modes | 50 |
| 9 | Factor group | 51 |
| 9.1 | General | 51 |
| 9.2 | Detailed object definitions | 51 |
| 9.2.1 | Object 608F _h : Position encoder resolution | 51 |
| 9.2.2 | Object 6090 _h : Velocity encoder resolution | 52 |
| 9.2.3 | Object 6091 _h : Gear ratio | 53 |
| 9.2.4 | Object 6092 _h : Feed constant | 54 |
| 9.2.5 | Object 607E _h : Polarity | 55 |
| 10 | Profile position mode | 56 |
| 10.1 | General information | 56 |
| 10.2 | Functional description | 57 |
| 10.2.1 | General | 57 |
| 10.2.2 | Single set-point | 58 |
| 10.2.3 | Set of set-points | 59 |
| 10.3 | General definitions | 60 |
| 10.4 | Use of controlword and statusword | 60 |
| 10.5 | Detailed object definitions | 61 |
| 10.5.1 | Object 607A _h : Target position | 61 |
| 10.5.2 | Object 607B _h : Position range limit | 62 |
| 10.5.3 | Object 607D _h : Software position limit | 62 |
| 10.5.4 | Object 607F _h : Max profile velocity | 64 |
| 10.5.5 | Object 6080 _h : Max motor speed | 64 |
| 10.5.6 | Object 6081 _h : Profile velocity | 65 |
| 10.5.7 | Object 6082 _h : End velocity | 65 |
| 10.5.8 | Object 6083 _h : Profile acceleration | 66 |
| 10.5.9 | Object 6084 _h : Profile deceleration | 66 |
| 10.5.10 | Object 6085 _h : Quick stop deceleration | 67 |
| 10.5.11 | Object 6086 _h : Motion profile type | 67 |
| 10.5.12 | Object 60A3 _h : Profile jerk use | 68 |
| 10.5.13 | Object 60A4 _h : Profile jerk | 69 |
| 10.5.14 | Object 60C5 _h : Max acceleration | 70 |
| 10.5.15 | Object 60C6 _h : Max deceleration | 71 |
| 11 | Homing mode | 72 |
| 11.1 | General information | 72 |
| 11.2 | Functional description | 72 |
| 11.3 | General definitions | 73 |
| 11.3.1 | Method 1: Homing on negative limit switch and index pulse | 73 |
| 11.3.2 | Method 2: Homing on positive limit switch and index pulse | 73 |
| 11.3.3 | Method 3 and 4: Homing on positive home switch and index pulse | 73 |
| 11.3.4 | Method 5 and 6: Homing on negative home switch and index pulse | 74 |
| 11.3.5 | Method 7 to 14: Homing on home switch and index pulse | 74 |
| 11.3.6 | Method 15 and 16: Reserved | 75 |
| 11.3.7 | Method 17 to 30: Homing without index pulse | 75 |
| 11.3.8 | Method 31 and 32: Reserved | 76 |
| 11.3.9 | Method 33 and 34: Homing on index pulse | 76 |
| 11.3.10 | Method 35: Homing on index pulse | 76 |
| 11.3.11 | Method 36: Homing with touch-probe | 76 |
| 11.4 | Use of controlword and statusword | 76 |

| | | |
|---------|---|-----|
| 11.5 | Detailed object definitions | 77 |
| 11.5.1 | Object 607C _h : Home offset | 77 |
| 11.5.2 | Object 6098 _h : Homing method | 78 |
| 11.5.3 | Object 6099 _h : Homing speeds | 79 |
| 11.5.4 | Object 609A _h : Homing acceleration | 80 |
| 11.5.5 | Object 60B8 _h : Touch probe function | 80 |
| 11.5.6 | Object 60B9 _h : Touch probe status | 82 |
| 11.5.7 | Object 60BA _h : Touch probe pos1 pos value | 82 |
| 11.5.8 | Object 60BB _h : Touch probe pos1 neg value | 83 |
| 11.5.9 | Object 60BC _h : Touch probe pos2 pos value | 83 |
| 11.5.10 | Object 60BD _h : Touch probe pos2 neg value | 84 |
| 12 | Position control function | 84 |
| 12.1 | General information | 84 |
| 12.2 | Functional description | 85 |
| 12.3 | Detailed object definitions | 87 |
| 12.3.1 | Object 6062 _h : Position demand value | 87 |
| 12.3.2 | Object 6063 _h : Position actual internal value | 87 |
| 12.3.3 | Object 6064 _h : Position actual value | 88 |
| 12.3.4 | Object 6065 _h : Following error window | 88 |
| 12.3.5 | Object 6066 _h : Following error time out | 89 |
| 12.3.6 | Object 6067 _h : Position window | 90 |
| 12.3.7 | Object 6068 _h : Position window time | 90 |
| 12.3.8 | Object 60F4 _h : Following error actual value | 91 |
| 12.3.9 | Object 60FA _h : Control effort | 91 |
| 12.3.10 | Object 60FC _h : Position demand internal value | 92 |
| 12.3.11 | Object 60F2 _h : Positioning option code | 92 |
| 13 | Interpolated position mode | 94 |
| 13.1 | General information | 94 |
| 13.2 | Functional description | 95 |
| 13.2.1 | General | 95 |
| 13.2.2 | Linear interpolated position mode with several axes | 96 |
| 13.2.3 | Buffer strategies for the interpolated position mode | 97 |
| 13.2.4 | Interpolated position mode FSA | 98 |
| 13.3 | General definitions | 99 |
| 13.4 | Use of controlword and statusword | 99 |
| 13.5 | Detailed object definitions | 100 |
| 13.5.1 | Object 60C0 _h : Interpolation sub mode select | 100 |
| 13.5.2 | Object 60C1 _h : Interpolation data record | 101 |
| 13.5.3 | Object 60C2 _h : Interpolation time period | 102 |
| 13.5.4 | Object 60C4 _h : Interpolation data configuration | 103 |
| 14 | Profile velocity mode | 105 |
| 14.1 | General information | 105 |
| 14.2 | Functional description | 106 |
| 14.3 | General definitions | 107 |
| 14.4 | Use of controlword and statusword | 107 |
| 14.5 | Detailed object definitions | 108 |
| 14.5.1 | Object 6069 _h : Velocity sensor actual value | 108 |
| 14.5.2 | Object 606A _h : Sensor selection code | 108 |
| 14.5.3 | Object 606B _h : Velocity demand value | 109 |

| | | |
|---------|---|-----|
| 14.5.4 | Object 606C _h : Velocity actual value | 110 |
| 14.5.5 | Object 606D _h : Velocity window | 110 |
| 14.5.6 | Object 606E _h : Velocity window time | 111 |
| 14.5.7 | Object 606F _h : Velocity threshold | 111 |
| 14.5.8 | Object 6070 _h : Velocity threshold time | 112 |
| 14.5.9 | Object 60FF _h : Target velocity | 112 |
| 14.5.10 | Object 60F8 _h : Max slippage | 113 |
| 15 | Profile torque mode | 113 |
| 15.1 | General information | 113 |
| 15.2 | Functional description | 113 |
| 15.3 | General definitions | 114 |
| 15.4 | Use of controlword and statusword | 114 |
| 15.5 | Detailed object definitions | 115 |
| 15.5.1 | Object 6071 _h : Target torque | 115 |
| 15.5.2 | Object 6072 _h : Max torque | 116 |
| 15.5.3 | Object 6073 _h : Max current | 116 |
| 15.5.4 | Object 6074 _h : Torque demand | 117 |
| 15.5.5 | Object 6075 _h : Motor rated current | 117 |
| 15.5.6 | Object 6076 _h : Motor rated torque | 118 |
| 15.5.7 | Object 6077 _h : Torque actual value | 118 |
| 15.5.8 | Object 6078 _h : Current actual value | 119 |
| 15.5.9 | Object 6079 _h : DC link circuit voltage | 119 |
| 15.5.10 | Object 6087 _h : Torque slope | 120 |
| 15.5.11 | Object 6088 _h : Torque profile type | 120 |
| 16 | Velocity mode | 121 |
| 16.1 | General information | 121 |
| 16.2 | Functional description | 122 |
| 16.2.1 | Velocity limit function | 122 |
| 16.2.2 | Ramp function | 122 |
| 16.2.3 | Velocity control function | 122 |
| 16.2.4 | Factor function | 122 |
| 16.3 | General definitions | 123 |
| 16.4 | Use of controlword and statusword | 123 |
| 16.5 | Detailed object definitions | 124 |
| 16.5.1 | Object 6042 _h : vI target velocity | 124 |
| 16.5.2 | Object 6043 _h : vI velocity demand | 125 |
| 16.5.3 | Object 6044 _h : vI velocity actual value | 125 |
| 16.5.4 | Object 6046 _h : vI velocity min max amount | 126 |
| 16.5.5 | Object 6049 _h : vI velocity deceleration | 127 |
| 16.5.6 | Object 6048 _h : vI velocity acceleration | 128 |
| 16.5.7 | Object 604A _h : vI velocity quick stop | 130 |
| 16.5.8 | Object 604B _h : vI set-point factor | 131 |
| 16.5.9 | Object 604C _h : vI dimension factor | 132 |
| 17 | Cyclic synchronous position mode | 133 |
| 17.1 | General information | 133 |
| 17.2 | Functional description | 134 |
| 17.3 | Use of controlword and statusword | 135 |
| 17.4 | Detailed object definitions | 136 |
| 17.4.1 | Object 60B0 _h : Position offset | 136 |

| | | |
|--------|--|-----|
| 17.4.2 | Object 60B1 _h : Velocity offset..... | 136 |
| 17.4.3 | Object 60B2 _h : Torque offset..... | 137 |
| 18 | Cyclic synchronous velocity mode..... | 137 |
| 18.1 | General information..... | 137 |
| 18.2 | General definitions..... | 138 |
| 18.3 | Functional description..... | 138 |
| 18.4 | Use of controlword and statusword..... | 139 |
| 19 | Cyclic synchronous torque mode..... | 140 |
| 19.1 | General information..... | 140 |
| 19.2 | General definitions..... | 140 |
| 19.3 | Functional description..... | 140 |
| 19.4 | Use of controlword and statusword..... | 141 |
| 20 | Optional application FE..... | 141 |
| 20.1 | General..... | 141 |
| 20.2 | Object 60FD _h : Digital inputs..... | 141 |
| 20.3 | Object 60FE _h : Digital outputs..... | 142 |
| | Bibliography..... | 144 |
| | Figure 1 – Structure of IEC 61800-7..... | 18 |
| | Figure 2 – Value definition..... | 27 |
| | Figure 3 – Remote and local control..... | 37 |
| | Figure 4 – Power drive system finite state automaton..... | 38 |
| | Figure 5 – Relation between different value parameters..... | 41 |
| | Figure 6 – Value definition..... | 41 |
| | Figure 7 – Value definition..... | 42 |
| | Figure 8 – Value definition..... | 50 |
| | Figure 9 – Value definition..... | 56 |
| | Figure 10 – Trajectory generator and position control function..... | 56 |
| | Figure 11 – Trajectory generator for profile position mode..... | 57 |
| | Figure 12 – Set-point example..... | 58 |
| | Figure 13 – Handshaking procedure for the single set-point method..... | 58 |
| | Figure 14 – Handshaking procedure for the set of set-points method..... | 59 |
| | Figure 15 – Set-point handling for two set-points..... | 59 |
| | Figure 16 – Controlword for profile position (pp) mode..... | 60 |
| | Figure 17 – Statusword for profile position (pp) mode..... | 61 |
| | Figure 18 – Velocity/time diagram with jerk positions..... | 69 |
| | Figure 19 – Homing mode function..... | 72 |
| | Figure 20 – Homing on negative limit switch and index pulse..... | 73 |
| | Figure 21 – Homing on positive limit switch and index pulse..... | 73 |
| | Figure 22 – Homing on positive home switch and index pulse..... | 74 |
| | Figure 23 – Homing on negative home switch and index pulse..... | 74 |
| | Figure 24 – Homing on home switch and index pulse – positive initial motion..... | 75 |
| | Figure 25 – Homing on home switch and index pulse – negative initial motion..... | 75 |
| | Figure 26 – Homing on positive home switch..... | 76 |

| | |
|--|-----|
| Figure 27 – Homing on index pulse | 76 |
| Figure 28 – Controlword for homing mode | 76 |
| Figure 29 – Statusword for homing mode | 77 |
| Figure 30 – Home offset definition | 77 |
| Figure 31 – Position control function | 85 |
| Figure 32 – Following error (functional overview) | 85 |
| Figure 33 – Position reached (functional overview) | 86 |
| Figure 34 – Position reached (definitions) | 86 |
| Figure 35 – Following error (definitions) | 87 |
| Figure 36 – Object structure | 92 |
| Figure 37 – Interpolation controller | 95 |
| Figure 38 – Interpolated position mode for two axes | 96 |
| Figure 39 – Linear interpolation for one axis | 97 |
| Figure 40 – Input buffer organisation | 98 |
| Figure 41 – Input buffer examples | 98 |
| Figure 42 – Interpolated position mode FSA | 99 |
| Figure 43 – Controlword for interpolated position mode | 99 |
| Figure 44 – Statusword for interpolated position mode | 100 |
| Figure 45 – Profile velocity mode | 107 |
| Figure 46 – Controlword for profile velocity mode | 107 |
| Figure 47 – Statusword for profile velocity mode | 108 |
| Figure 48 – Structure of the profile torque mode | 114 |
| Figure 49 – Controlword for profile torque mode | 114 |
| Figure 50 – Statusword for profile torque mode | 115 |
| Figure 51 – Velocity mode with all objects | 121 |
| Figure 52 – Velocity mode with mandatory objects only | 121 |
| Figure 53 – Velocity profile | 122 |
| Figure 54 – Factor function | 122 |
| Figure 55 – Reverse factor function | 123 |
| Figure 56 – Controlword for profile velocity mode | 123 |
| Figure 57 – Usage of controlword bits in velocity mode | 124 |
| Figure 58 – Statusword for profile velocity mode | 124 |
| Figure 59 – Transfer characteristic of $v/ v $ velocity min max amount | 126 |
| Figure 60 – Transfer characteristic of the velocity deceleration | 127 |
| Figure 61 – Transfer characteristic of the velocity acceleration | 129 |
| Figure 62 – Transfer characteristic of the quick stop deceleration | 130 |
| Figure 63 – Cyclic synchronous position mode overview | 134 |
| Figure 64 – Cyclic synchronous position control function | 135 |
| Figure 65 – Statusword for profile cyclic synchronous position mode | 135 |
| Figure 66 – Cyclic synchronous velocity mode overview | 138 |
| Figure 67 – Cyclic synchronous velocity control function | 139 |
| Figure 68 – Statusword for profile cyclic synchronous velocity mode | 139 |
| Figure 69 – Cyclic synchronous torque mode overview | 140 |

| | |
|---|-----|
| Figure 70 – Cyclic synchronous torque control function..... | 141 |
| Figure 71 – Statusword for profile cyclic synchronous torque mode | 141 |
| Figure 72 – Object structure | 142 |
| Figure 73 – Object structure | 142 |
| Table 1 – List of used data types | 26 |
| Table 2 – Interpolated time period | 26 |
| Table 3 – Interpolated data configuration | 26 |
| Table 4 – vl velocity acceleration/deceleration | 26 |
| Table 5 – Object description | 27 |
| Table 6 – Entry description | 28 |
| Table 7 – Value definition | 28 |
| Table 8 – Object description | 29 |
| Table 9 – Entry description | 29 |
| Table 10 – Object description | 29 |
| Table 11 – Entry description | 29 |
| Table 12 – Object description | 30 |
| Table 13 – Entry description | 30 |
| Table 14 – Object description | 30 |
| Table 15 – Entry description | 30 |
| Table 16 – Object description | 31 |
| Table 17 – Entry description | 31 |
| Table 18 – Object description | 31 |
| Table 19 – Entry description | 31 |
| Table 20 – Object description | 32 |
| Table 21 – Entry description | 32 |
| Table 22 – Object description | 32 |
| Table 23 – Entry description | 32 |
| Table 24 – Error codes | 33 |
| Table 25 – FSA states and supported functions | 38 |
| Table 26 – Transition events and actions | 39 |
| Table 27 – Command coding | 41 |
| Table 28 – Object description | 42 |
| Table 29 – Entry description | 42 |
| Table 30 – State coding | 42 |
| Table 31 – Object description | 43 |
| Table 32 – Entry description | 43 |
| Table 33 – Object description | 44 |
| Table 34 – Entry description | 44 |
| Table 35 – Value definition | 44 |
| Table 36 – Object description | 44 |
| Table 37 – Entry description | 45 |
| Table 38 – Value definition | 45 |

| | |
|---|----|
| Table 39 – Object description | 45 |
| Table 40 – Entry description | 46 |
| Table 41 – Value definition | 46 |
| Table 42 – Object description | 46 |
| Table 43 – Entry description | 46 |
| Table 44 – Value definition | 47 |
| Table 45 – Object description | 47 |
| Table 46 – Entry description | 47 |
| Table 47 – Value definition | 47 |
| Table 48 – Object description | 48 |
| Table 49 – Entry description | 48 |
| Table 50 – Value definition | 48 |
| Table 51 – Object description | 48 |
| Table 52 – Entry description | 49 |
| Table 53 – Value definition | 49 |
| Table 54 – Object description | 49 |
| Table 55 – Entry description | 50 |
| Table 56 – Object description | 50 |
| Table 57 – Entry description | 50 |
| Table 58 – Object description | 51 |
| Table 59 – Entry description | 51 |
| Table 60 – Object description | 52 |
| Table 61 – Entry description | 52 |
| Table 62 – Object description | 53 |
| Table 63 – Entry description | 53 |
| Table 64 – Object description | 54 |
| Table 65 – Entry description | 54 |
| Table 66 – Object description | 55 |
| Table 67 – Entry description | 55 |
| Table 68 – Object description | 56 |
| Table 69 – Entry description | 56 |
| Table 70 – Definition of bit 4, bit 5, and bit 9 | 60 |
| Table 71 – Definition of bit 6 and bit 8 | 60 |
| Table 72 – Definition of bit 10, bit 12, and bit 13 | 61 |
| Table 73 – Object description | 61 |
| Table 74 – Entry description | 61 |
| Table 75 – Object description | 62 |
| Table 76 – Entry description | 62 |
| Table 77 – Object description | 63 |
| Table 78 – Entry description | 63 |
| Table 79 – Object description | 64 |
| Table 80 – Entry description | 64 |
| Table 81 – Object description | 64 |

| | |
|--|----|
| Table 82 – Entry description | 65 |
| Table 83 – Object description | 65 |
| Table 84 – Entry description | 65 |
| Table 85 – Object description | 66 |
| Table 86 – Entry description | 66 |
| Table 87 – Object description | 66 |
| Table 88 – Entry description | 66 |
| Table 89 – Object description | 67 |
| Table 90 – Entry description | 67 |
| Table 91 – Object description | 67 |
| Table 92 – Entry description | 67 |
| Table 93 – Value definition | 68 |
| Table 94 – Object description | 68 |
| Table 95 – Entry description | 68 |
| Table 96 – Object description | 68 |
| Table 97 – Entry description | 69 |
| Table 98 – Value assignments | 69 |
| Table 99 – Object description | 69 |
| Table 100 – Entry description | 70 |
| Table 101 – Object description | 71 |
| Table 102 – Entry description | 71 |
| Table 103 – Object description | 71 |
| Table 104 – Entry description | 71 |
| Table 105 – Definition of bit 4 and bit 8..... | 77 |
| Table 106 – Definition of bit 10, bit 12, and bit 13 | 77 |
| Table 107 – Object description | 78 |
| Table 108 – Entry description | 78 |
| Table 109 – Value definition | 78 |
| Table 110 – Object description | 78 |
| Table 111 – Entry description | 79 |
| Table 112 – Object description | 79 |
| Table 113 – Entry description | 79 |
| Table 114 – Object description | 80 |
| Table 115 – Entry description | 80 |
| Table 116 – Value definition | 81 |
| Table 117 – Object description | 81 |
| Table 118 – Entry description | 81 |
| Table 119 – Value definition | 82 |
| Table 120 – Object description | 82 |
| Table 121 – Entry description | 82 |
| Table 122 – Object description | 83 |
| Table 123 – Entry description | 83 |
| Table 124 – Object description | 83 |

| | |
|---|-----|
| Table 125 – Entry description | 83 |
| Table 126 – Object description | 84 |
| Table 127 – Entry description | 84 |
| Table 128 – Object description | 84 |
| Table 129 – Entry description | 84 |
| Table 130 – Object description | 87 |
| Table 131 – Entry description | 87 |
| Table 132 – Object description | 88 |
| Table 133 – Entry description | 88 |
| Table 134 – Object description | 88 |
| Table 135 – Entry description | 88 |
| Table 136 – Object description | 89 |
| Table 137 – Entry description | 89 |
| Table 138 – Object description | 89 |
| Table 139 – Entry description | 89 |
| Table 140 – Object description | 90 |
| Table 141 – Entry description | 90 |
| Table 142 – Object description | 90 |
| Table 143 – Entry description | 91 |
| Table 144 – Object description | 91 |
| Table 145 – Entry description | 91 |
| Table 146 – Object description | 91 |
| Table 147 – Entry description | 92 |
| Table 148 – Object description | 92 |
| Table 149 – Entry description | 92 |
| Table 150 – Value definition for bit 0 and bit 1 | 93 |
| Table 151 – Value definition for bit 2 and bit 3 | 93 |
| Table 152 – Value definition for bit 4 and bit 5 | 93 |
| Table 153 – Object description | 94 |
| Table 154 – Entry description | 94 |
| Table 155 – Position calculation in interpolated position mode for several axes | 96 |
| Table 156 – FSA states and supported functions | 99 |
| Table 157 – Transition events and actions | 99 |
| Table 158 – Definition of bit 4 and bit 8 | 100 |
| Table 159 – Definition of bit 10 and bit 12 | 100 |
| Table 160 – Value definition | 100 |
| Table 161 – Object description | 101 |
| Table 162 – Entry description | 101 |
| Table 163 – Object description | 101 |
| Table 164 – Entry description | 102 |
| Table 165 – Object description | 103 |
| Table 166 – Entry description | 103 |
| Table 167 – Object description | 104 |

| | |
|--|-----|
| Table 168 – Entry description | 104 |
| Table 169 – Definition of bit 8 | 107 |
| Table 170 – Definition of bit 10, bit 12, and bit 13 | 108 |
| Table 171 – Object description | 108 |
| Table 172 – Entry description | 108 |
| Table 173 – Value definition | 109 |
| Table 174 – Object description | 109 |
| Table 175 – Entry description | 109 |
| Table 176 – Object description | 109 |
| Table 177 – Entry description | 110 |
| Table 178 – Object description | 110 |
| Table 179 – Entry description | 110 |
| Table 180 – Object description | 110 |
| Table 181 – Entry description | 111 |
| Table 182 – Object description | 111 |
| Table 183 – Entry description | 111 |
| Table 184 – Object description | 111 |
| Table 185 – Entry description | 112 |
| Table 186 – Object description | 112 |
| Table 187 – Entry description | 112 |
| Table 188 – Object description | 112 |
| Table 189 – Entry description | 113 |
| Table 190 – Object description | 113 |
| Table 191 – Entry description | 113 |
| Table 192 – Definition of bit 8 | 115 |
| Table 193 – Definition of bit 10 | 115 |
| Table 194 – Object description | 115 |
| Table 195 – Entry description | 115 |
| Table 196 – Object description | 116 |
| Table 197 – Entry description | 116 |
| Table 198 – Object description | 116 |
| Table 199 – Entry description | 116 |
| Table 200 – Object description | 117 |
| Table 201 – Entry description | 117 |
| Table 202 – Object description | 117 |
| Table 203 – Entry description | 117 |
| Table 204 – Object description | 118 |
| Table 205 – Entry description | 118 |
| Table 206 – Object description | 118 |
| Table 207 – Entry description | 118 |
| Table 208 – Object description | 119 |
| Table 209 – Entry description | 119 |
| Table 210 – Object description | 119 |

| | |
|--|-----|
| Table 211 – Entry description | 119 |
| Table 212 – Object description | 120 |
| Table 213 – Entry description | 120 |
| Table 214 – Value definition | 120 |
| Table 215 – Object description | 120 |
| Table 216 – Entry description | 121 |
| Table 217 – Definition of bit 4, bit 5, bit 6, and bit 8 | 123 |
| Table 218 – Object description | 124 |
| Table 219 – Entry description | 124 |
| Table 220 – Object description | 125 |
| Table 221 – Entry description | 125 |
| Table 222 – Object description | 125 |
| Table 223 – Entry description | 126 |
| Table 224 – Object description | 126 |
| Table 225 – Entry description | 127 |
| Table 226 – Object description | 128 |
| Table 227 – Entry description | 128 |
| Table 228 – Object description | 129 |
| Table 229 – Entry description | 129 |
| Table 230 – Object description | 130 |
| Table 231 – Entry description | 131 |
| Table 232 – Object description | 131 |
| Table 233 – Entry description | 132 |
| Table 234 – Object description | 133 |
| Table 235 – Entry description | 133 |
| Table 236 – Definition of bit 10, bit 12, and bit 13 | 135 |
| Table 237 – Object description | 136 |
| Table 238 – Entry description | 136 |
| Table 239 – Object description | 136 |
| Table 240 – Entry description | 137 |
| Table 241 – Object description | 137 |
| Table 242 – Entry description | 137 |
| Table 243 – Definition of bit 10, bit 12, and bit 13 | 139 |
| Table 244 – Definition of bit 10, bit 12, and bit 13 | 141 |
| Table 245 – Value definition | 142 |
| Table 246 – Object description | 142 |
| Table 247 – Entry description | 142 |
| Table 248 – Value definition | 143 |
| Table 249 – Object description | 143 |
| Table 250 – Entry description | 143 |

INTERNATIONAL ELECTROTECHNICAL COMMISSION

ADJUSTABLE SPEED ELECTRICAL POWER DRIVE SYSTEMS –

**Part 7-201: Generic interface and use
of profiles for power drive systems –
Profile type 1 specification**

FOREWORD

- 1) The International Electrotechnical Commission (IEC) is a worldwide organization for standardization comprising all national electrotechnical committees (IEC National Committees). The object of IEC is to promote international co-operation on all questions concerning standardization in the electrical and electronic fields. To this end and in addition to other activities, IEC publishes International Standards, Technical Specifications, Technical Reports, Publicly Available Specifications (PAS) and Guides (hereafter referred to as "IEC Publication(s)"). Their preparation is entrusted to technical committees; any IEC National Committee interested in the subject dealt with may participate in this preparatory work. International, governmental and non-governmental organizations liaising with the IEC also participate in this preparation. IEC collaborates closely with the International Organization for Standardization (ISO) in accordance with conditions determined by agreement between the two organizations.
- 2) The formal decisions or agreements of IEC on technical matters express, as nearly as possible, an international consensus of opinion on the relevant subjects since each technical committee has representation from all interested IEC National Committees.
- 3) IEC Publications have the form of recommendations for international use and are accepted by IEC National Committees in that sense. While all reasonable efforts are made to ensure that the technical content of IEC Publications is accurate, IEC cannot be held responsible for the way in which they are used or for any misinterpretation by any end user.
- 4) In order to promote international uniformity, IEC National Committees undertake to apply IEC Publications transparently to the maximum extent possible in their national and regional publications. Any divergence between any IEC Publication and the corresponding national or regional publication shall be clearly indicated in the latter.
- 5) IEC provides no marking procedure to indicate its approval and cannot be rendered responsible for any equipment declared to be in conformity with an IEC Publication.
- 6) All users should ensure that they have the latest edition of this publication.
- 7) No liability shall attach to IEC or its directors, employees, servants or agents including individual experts and members of its technical committees and IEC National Committees for any personal injury, property damage or other damage of any nature whatsoever, whether direct or indirect, or for costs (including legal fees) and expenses arising out of the publication, use of, or reliance upon, this IEC Publication or any other IEC Publications.
- 8) Attention is drawn to the Normative references cited in this publication. Use of the referenced publications is indispensable for the correct application of this publication.
- 9) Attention is drawn to the possibility that some of the elements of this IEC Publication may be the subject of patent rights. IEC shall not be held responsible for identifying any or all such patent rights.

The International Standard IEC 61800-7-201 has been prepared by subcommittee SC 22G: Adjustable speed electric drive systems incorporating semiconductor power converters, of IEC technical committee TC 22: Power electronic systems and equipment.

The text of this standard is based on the following documents:

| | |
|--------------|------------------|
| FDIS | Report on voting |
| 22G/184/FDIS | 22G/192/RVD |

Full information on the voting for the approval of this standard can be found in the report on voting indicated in the above table.

This publication has been drafted in accordance with the ISO/IEC Directives, Part 2.

A list of all parts of the IEC 61800 series, under the general title *Adjustable speed electrical power drive systems*, can be found on the IEC website.

The committee has decided that the contents of this publication will remain unchanged until the maintenance result date indicated on the IEC web site under "<http://webstore.iec.ch>" in the data related to the specific publication. At this date, the publication will be

- reconfirmed;
- withdrawn;
- replaced by a revised edition, or
- amended.

A bilingual version of this publication may be issued at a later date.

This document is a preview generated by EVS

INTRODUCTION

The IEC 61800 series is intended to provide a common set of specifications for adjustable speed electrical power drive systems.

IEC 61800-7 describes a generic interface between control systems and power drive systems. This interface can be embedded in the control system. The control system itself can also be located in the drive (sometimes known as "smart drive" or "intelligent drive").

A variety of physical interfaces is available (analogue and digital inputs and outputs, serial and parallel interfaces, fieldbuses and networks). Profiles based on specific physical interfaces are already defined for some application areas (e.g. motion control) and some device classes (e.g. standard drives, positioner). The implementations of the associated drivers and application programmers interfaces are proprietary and vary widely.

IEC 61800-7 defines a set of common drive control functions, parameters, and state machines or description of sequences of operation to be mapped to the profiles.

IEC 61800-7 provides a way to access functions and data of a drive that is independent of the used drive profile and communication interface. The objective is a common drive model with generic functions and objects suitable to be mapped on different communication interfaces. This makes it possible to provide common implementations of motion control (or velocity control or drive control applications) in controllers without any specific knowledge of the drive implementation.

There are several reasons to define a generic interface:

For a drive device manufacturer

- Less effort to support system integrators
- Less effort to describe drive functions because of common terminology
- The selection of drives does not depend on availability of specific support

For a control device manufacturer

- No influence of bus technology
- Easy device integration
- Independent of a drive supplier

For a system integrator (builds modules, machines, plants etc.)

- Less integration effort for devices
- Only one understandable way of modeling
- Independent of bus technology

Much effort is needed to design a motion control application with several different drives and a specific control system. The tasks to implement the system software and to understand the functional description of the individual components may exhaust the project resources. In some cases, the drives do not share the same physical interface. Some control devices just support a single interface which will not be supported by a specific drive. On the other hand, the functions and data structures are specified with incompatibilities. It is up to the systems integrator to write interfaces to the application software to handle that which should not be his responsibility.

Some applications need device exchangeability or integration of new devices in an existing configuration. They are faced with different incompatible solutions. The efforts to adopt a solution to a drive profile and to manufacturer specific extensions may be unacceptable. This will reduce the degree of freedom to select a device best suited for this application to the selection of the unit which will be available for a specific physical interface and supported by the controller.

IEC 61800-7-1 is divided into a generic part and several annexes as shown in Figure 1. The drive profile types for CiA 402¹, CIP Motion^{TM2}, PROFIdrive³ and SERCOS Interface^{TM4} are mapped to the generic interface in the corresponding annex. The annexes have been submitted by open international network or fieldbus organizations which are responsible for the content of the related annex and use of the related trademarks.

This part of IEC 61800-7 specifies the profile type 1 (CiA 402).

The profile types 2, 3 and 4 are specified in IEC 61800-7-202, IEC 61800-7-203 and IEC 61800-7-204.

IEC 61800-7-301, IEC 61800-7-302, IEC 61800-7-303 and IEC 61800-7-304 specify how the profile types 1, 2, 3 and 4 are mapped to different network technologies (such as CANopen⁵, EtherCAT^{TM6}, Ethernet Powerlink^{TM7}, DeviceNet^{TM8}, ControlNet^{TM9}, EtherNet/IP^{TM10}, PROFIBUS¹¹, PROFINET¹² and SERCOS Interface).

-
- 1 CiA 402 is a trade name of CAN in Automation, e.V. This information is given for the convenience of users of this International Standard and does not constitute an endorsement by IEC of the trade name holder or any of its products. Compliance to this profile does not require use of the trade name CiA 402.
 - 2 CIP MotionTM is a trade name of Open DeviceNet Vendor Association, Inc. This information is given for the convenience of users of this International Standard and does not constitute an endorsement by IEC of the trademark holder or any of its products. Compliance to this profile does not require use of the trade name CIP MotionTM. Use of the trade name CIP MotionTM requires permission of Open DeviceNet Vendor Association, Inc.
 - 3 PROFIdrive is a trade name of PROFIBUS International. This information is given for the convenience of users of this International Standard and does not constitute an endorsement by IEC of the trade name holder or any of its products. Compliance to this profile does not require use of the trade name PROFIdrive. Use of the trade name PROFIdrive requires permission of PROFIBUS International.
 - 4 SERCOSTM and SERCOS InterfaceTM are trade names of SERCOS International e.V. This information is given for the convenience of users of this International Standard and does not constitute an endorsement by IEC of the trade name holder or any of its products. Compliance to this profile does not require use of the trade name SERCOS and SERCOS interface. Use of the trade name SERCOS and SERCOS interface requires permission of the trade name holder.
 - 5 CANopen is an acronym for Controller Area Network *open* and is used to refer to EN 50325-4.
 - 6 EtherCATTM is a trade name of Beckhoff, Verl. This information is given for the convenience of users of this International Standard and does not constitute an endorsement by IEC of the trademark holder or any of its products. Compliance to this profile does not require use of the trade name EtherCATTM. Use of the trade name EtherCATTM requires permission of the trade name holder.
 - 7 Ethernet PowerlinkTM is a trade name of B&R, control of trade name use is given to the non profit organisation EPSG. This information is given for the convenience of users of this International Standard and does not constitute an endorsement by IEC of the trademark holder or any of its products. Compliance to this profile does not require use of the trade name Ethernet PowerlinkTM. Use of the trade name Ethernet PowerlinkTM requires permission of the trade name holder.
 - 8 DeviceNetTM is a trade name of Open DeviceNet Vendor Association, Inc. This information is given for the convenience of users of this International Standard and does not constitute an endorsement by IEC of the trademark holder or any of its products. Compliance to this profile does not require use of the trade name DeviceNetTM. Use of the trade name DeviceNetTM requires permission of Open DeviceNet Vendor Association, Inc.
 - 9 ControlNetTM is a trade name of ControlNet International, Ltd. This information is given for the convenience of users of this International Standard and does not constitute an endorsement by IEC of the trademark holder or any of its products. Compliance to this profile does not require use of the trade name ControlNetTM. Use of the trade name ControlNetTM requires permission of ControlNet International, Ltd.
 - 10 EtherNet/IPTM is a trade name of ControlNet International, Ltd. and Open DeviceNet Vendor Association, Inc. This information is given for the convenience of users of this International Standard and does not constitute an endorsement by IEC of the trademark holder or any of its products. Compliance to this profile does not require use of the trade name EtherNet/IPTM. Use of the trade name EtherNet/IPTM requires permission of either ControlNet International, Ltd. or Open DeviceNet Vendor Association, Inc.
 - 11 PROFIBUS is a trade name of PROFIBUS International. This information is given for the convenience of users of this International Standard and does not constitute an endorsement by IEC of the trade name holder or any of its products. Compliance to this profile does not require use of the trade name PROFIBUS. Use of the trade name PROFIBUS requires permission of PROFIBUS International.
 - 12 PROFINET is a trade name of PROFIBUS International. This information is given for the convenience of users of this International Standard and does not constitute an endorsement by IEC of the trade name holder or any of its products. Compliance to this profile does not require use of the trade name PROFINET. Use of the trade name PROFINET requires permission of PROFIBUS International.

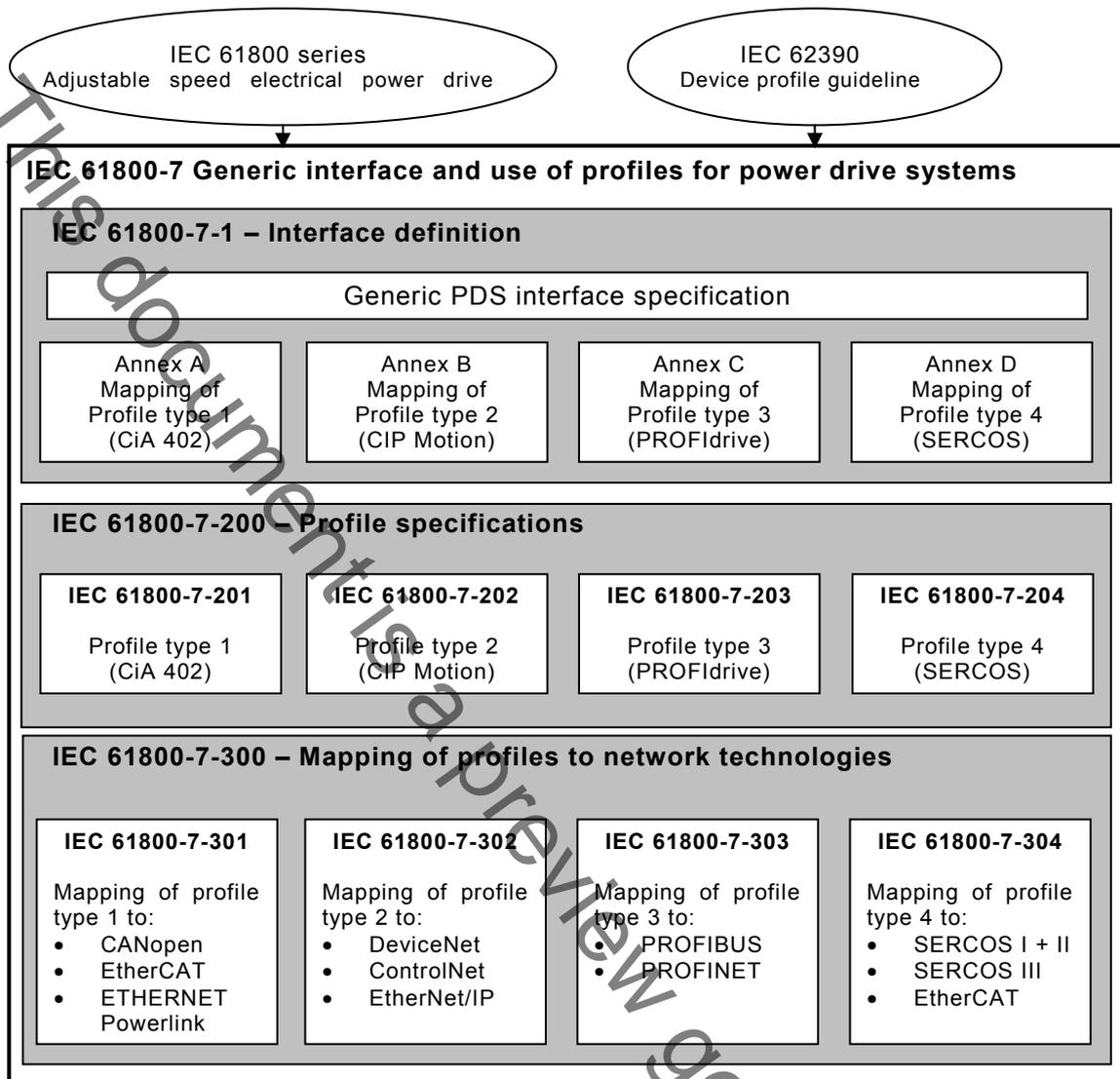


Figure 1 – Structure of IEC 61800-7

Generated by EVS

ADJUSTABLE SPEED ELECTRICAL POWER DRIVE SYSTEMS –

Part 7-201: Generic interface and use of profiles for power drive systems – Profile type 1 specification

1 Scope

IEC 61800-7 specifies profiles for Power Drive Systems (PDS) and their mapping to existing communication systems by use of a generic interface model.

The functions specified in this part of IEC 61800-7 are not intended to ensure functional safety. This requires additional measures according to the relevant standards, agreements and laws.

This part of IEC 61800-7 specifies profile type 1 for Power Drive Systems (PDS). Profile type 1 can be mapped onto different communication network technologies.

2 Normative references

The following referenced documents are indispensable for the application of this document. For dated references, only the edition cited applies. For undated references, the latest edition of the referenced document (including any amendments) applies.

IEC 61800-7 (all parts), *Adjustable speed electrical power drive systems – Generic interface and use of profiles for power drive systems*

IEC 61800-7-301, *Adjustable speed electrical power drive systems – Part 7-301: Generic interface and use of profiles for power drive systems – Mapping of profile type 1 to network technologies*

EN 50325-4, *Industrial communications subsystem based on ISO 11898 (CAN) for controller-device interfaces – Part 4: CANopen*

3 Terms, definitions and abbreviated terms

3.1 Terms and definitions

For the purposes of this document, the following terms and definitions apply.

3.1.1

actual value

value of a variable at a given instant

[IEV 351-21-02]

NOTE Actual value or actual variable are used in this part of the IEC 61800-7 series as input data of the application control program to monitor feedback variables or other process variables of the PDS.

3.1.2

algorithm

completely determined finite sequence of operations by which the values of the output data can be calculated from the values of the input data