

SERVOSTAR® S600 Profibus Communication with Allen-Bradley SLC-500

The SERVOSTAR® S600 servo amplifier is capable of Profibus communication with the addition of an optional Profibus expansion card (OPT-PB). Configured this way, the SERVOSTAR S600 operates as a Profibus DP slave with communication rates of up to 12 Mbits per second. One or more slaves may be controlled on a network by a Profibus DP master such as the SST-PFB-SLC Profibus scanner from SST™. Residing in an Allen-Bradley SLC-500 PLC backplane, the Profibus scanner module enables communication between the processor (SLC-500 or greater) and a network of Profibus DP slave devices.

Overview

An understanding of SERVOSTAR S600 operation and, in particular, its motion capability is a necessary prerequisite to understanding the operation and motion over Profibus.

High-level information transfer with the SERVOSTAR S600 is possible over one of three communication interfaces: RS-232, CAN-Bus, or Profibus (with optional board installed). The communication interface provides access to the commands and variables that control the behavior of the SERVOSTAR S600. The RS-232 (connector X6) interface is quite useful during development and startup of a Profibus system. RS-232 communication is ASCII text-based and easily established with a terminal (typically a PC running a program such as HyperTerminal) or, preferably, a PC running Danaher Motion's User Software Interface software designed specifically for the SERVOSTAR S600. The User Software Interface provides a user-friendly graphical interface and terminal for the setup, monitoring, and troubleshooting of the SERVOSTAR S600. It also provides a Profibus screen to view telegram data received by and sent from the drive.

Motion is commanded by executing motion tasks. A motion task is a group of related motion data (acceleration, position, etc.) identified by number (1, 2, 3, etc.) that is stored either in VRAM (Volatile Random Access Memory) or flash NVROM (Non-volatile Random Read-Only Memory). Once created, motion tasks are executed in a variety of ways: ASCII command, hardware input, another motion task, or Profibus.

To create a motion task with a number, first load the desired move parameters into a particular motion task either directly or indirectly. A task's nine parameters are entered directly using the ORDER command. All nine parameters must be included, even if only one has changed.

Alternatively, the motion task parameters are first entered into a special buffer area, motion task 0, where parameters can be individually edited with the O_xxxxxx commands. Then, motion task 0 is copied into the desired motion task number. An existing motion task may be edited by copying it into motion task 0, making the desired changes, and copying it back. Task numbering works like this: motion tasks 1 through 180 are stored in flash NVROM and tasks numbered 192 through 255 are stored in VRAM. When control power is turned off, all VRAM motion task contents are lost. At power up, NVROM tasks 1 through 64 are automatically copied into VRAM tasks 192 through 255.

Below are a few examples of motion task commands:

OLIST x y (lists y number of motion tasks starting from x)
ORDER # (displays or changes a task)
OCOPY x y (copies motion tasks between various memory sites)
O_P (view or change position in MT 0)

Before motion can be commanded, the drive must first be referenced or "homed". If it is in linear mode, POSCFG selects either linear or rotary mode. NREF identifies which one of the variety of homing types to use. For example, NREF=5 specifies homing to the resolver null. (Refer to the ASCII Reference document for additional information.)

Homing speed is determined by VREF when the home command is issued via the ASCII channel, but it is given in the PZD (Process Data Channel) when homing is via Profibus. The direction is determined by DREF. Homing acceleration and deceleration are controlled by ACCR and DECR. These variables are accessed through both the ASCII and Profibus parameter channels.

System Setup and Configuration

Setup of the SERVOSTAR S600 is mostly application-dependent and unrelated to the operation of Profibus. Of importance to Profibus operation is the setting of the drive's address using ADDR. Each drive must be correctly addressed via the keypad or RS-232 port prior to operation over the Profibus network (slave addresses are assigned during master configuration). It is recommended to set AENA=0. This causes the drive to power up with the power stage in a disabled state. In addition, set the external watchdog time variable EXTWD=1000 to prevent n04 (node guarding) warnings. This variable defaults to 100 for non-fieldbus use. A modified variable must be saved to the EEPROM (non-volatile memory) in order to retain its new value.

SST Profibus Scanner

The SST-PFB-SLC master must be configured before it will communicate with the DP slave network. Software supplied by the manufacturer is used to generate a configuration file that is then downloaded to the module. A "GSD" file supplied information about each manufacturer's slave device needed to generate the configuration file. Kollmorgen supplies this file (koll045.gsd) with the Profibus option card. This file is also available on the Product Support Package CD-ROM or can be downloaded from the website (www.danahermotion.com). The Profibus scanner's LEDs provide a quick, overall status of the system. An operational system is indicated by green "COMM" and "SYS" LEDs.

SYS LED*	
COLOR	INDICATION
Red	One or more slaves is reporting a fault condition.
Amber	The module is in program or test mode.
Green	The module is scanning in Run mode.

*At system startup, the SYS LED flashes green for two seconds.

COMM LED	
COLOR	INDICATION
Red	A network error has occurred.
Green	No network errors exist.

Allen-Bradley SLC-500

Controller I/O configuration for the Profibus scanner is covered in the manufacturer's documentation. Once this has been completed, the scanner automatically maps the Profibus network data into the processor's data table. Master-to-slave data is written to the output data table and slave-to-master data is read from the input data table. The M0 and M1 files contain status and other information detailed in the scanner's documentation. Since the Profibus telegrams are mapped into the data table, the drive can be operated from the programming software by reading and writing the input and output data files while on-line.

Profibus Telegram

This discussion only applies to the SERVOSTAR S600, which is a Profibus DP slave using PPO-type 2. Profibus data is sent in telegrams. The master constantly sends and receives telegrams from each node (device) on the network. In general, the size of the telegram can vary from none to node, but with the SERVOSTAR S600, the telegram is always 20 bytes (10 words) long. The telegram consists of two parts: a four word PKW and a six word PZD. The PKW is the parameter or service channel. It has no realtime capability, but does provide confirmed communication to the host. The PZD is the process data channel and transmits data in realtime. PKW sends and receives information in response to parameter numbers, called PNUs. The standard PNUs are in the range from 904 to 1551. Parameter object channel PNUs are in the range of 1600 to 2000. Through the use of the parameter sub index (IND), a large amount of information is available from the parameter object channel. Access to all commands and variable information (minimum, maximum, and default values along with data format) is possible.

The PZD transfers process data in realtime. The functionality of the PZD is OPMODE-dependent and determined by PNU 930. Profibus OPMODE is different from the OPMODE accessed through the ASCII channel. The first of the six process data channel words, PZD1, is a control word (master-to-slave) or status word (slave-to-master). The remaining words contain data specific to the OPMODE and state of the control word.

The SST-PFB-SLC Profibus master maps telegrams (slave data) into the PLC's data table. The PLC program reads and writes to each slave's telegram. The module handles all communication details. Consider a system with a Profibus scanner in slot three and a single SERVOSTAR S600 slave. The telegram maps into the PLC like this:

Word	1	2	3	4	5	6	7	8	9	10
Bytes	1,2	3,4	5,6	7,8	9,10	11,12	13,14	15,16	17,18	19,20
Section	PKW	PKW	PKW	PKW	PZD	PZD	PZD	PZD	PZD	PZD
Function	PKE	IND	PWE	PWE	PZD1	PZD2	PZD3	PZD4	PZD5	PZD6
SLC inputs	I:3.1	I:3.1	I:3.2	I:3.3	I:3.4	I:3.5	I:3.6	I:3.7	I:3.8	I:3.9
SLC outputs	O:3.0	O:3.1	O:3.2	O:3.3	O:3.4	O:3.5	O:3.6	O:3.7	O:3.8	O:3.9

The byte ordering for the 32-bit PKW is:

Word	3		4	
Bytes	5	6	7	8
Weighing	MSB, MSW	LSB, MSW	MSB, LSW	LSB, LSW

MSB = Most Significant Byte, MSW = Most Significant Word

The PKW contains three parts: PWE, IND, and PKE (consisting of AK, a four-bit task and an 11-bit PNU).

AK	Master-to-Slave Function
0	No task
1	Request a parameter value
3	Set parameter to a new value

AK	Slave-to-Master Function
0	No task
2	Parameter value transmitted
7	Task not possible with error #



If an error occurs (AK=7), PWE reports an error code identifying the nature of the error.

The sub-index determines the functionality of the parameter object channel (PNU >=1600). The sub-index is byte 3 of the telegram (MSW of word 2). For example, to read the default value of a parameter, set IDN=400 HEX (1024 decimal).

Sub-Index	Description
0	Number of subindices
1	Read/write a parameter
2	Read the low limit of a parameter
3	Read the high limit of a parameter
4	Read the default value of a parameter
5	Read the data format of a parameter
6	Read the control data of a parameter
7	Reserved
8	Reserved

Motion Task Examples

Below is a sample program listing containing multiple simulated motion tasks. The main ladder program calls one of ten subroutines, depending on the states of switches 1, 2, 3, and 4. Switches 5, 6, 7, and 8 take on different functions in each of the subroutines. Also included are graphic representations for each subroutine containing paameter object channel information. The motion tasks performed in this section were constructed using the following system configuration:

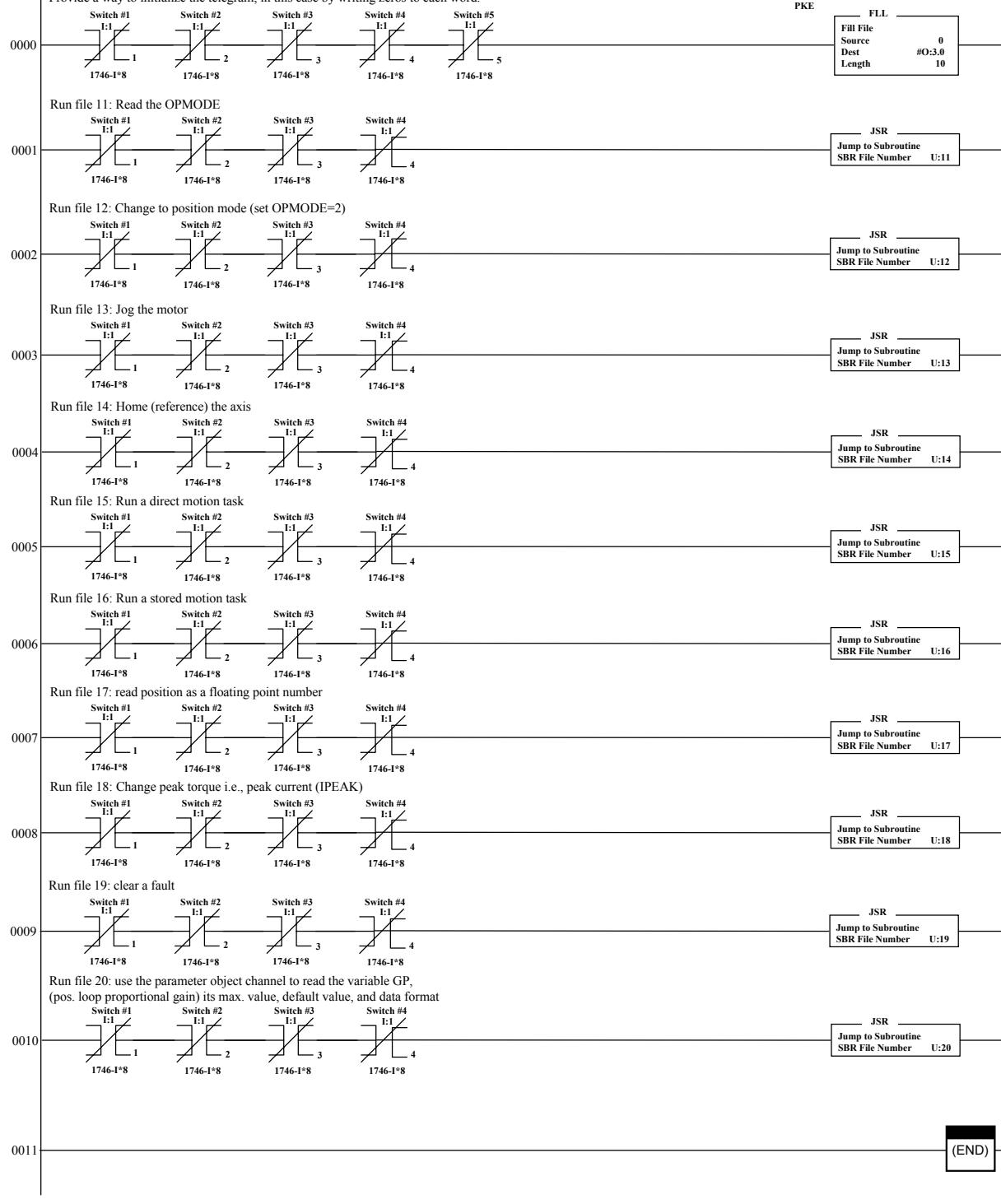
- SERVOSTAR S600 with OPT-PB Profibus option card
- PC with RSLogix 500 programming software
- Allen-Bradley SLC-500 rack and power supply with:
 - Slot 0: SLC5/03 processor
 - Slot 1: DC input module (8 inputs) wired to toggle switches
 - Slot 2: DC output module (8 outputs)
 - Slot 3: SST-PFB-SLC Profibus scanner configured as a master for a single SERVOSTAR S600 DP slave

Main Program

Profibus Application Note Demo Program

This is the Main routine which simply calls one of the 10 subroutines, based on the state of switches 1, 2, 3, and 4. Switches 5, 6, 7, 8 take on different functions in each of the subroutines.

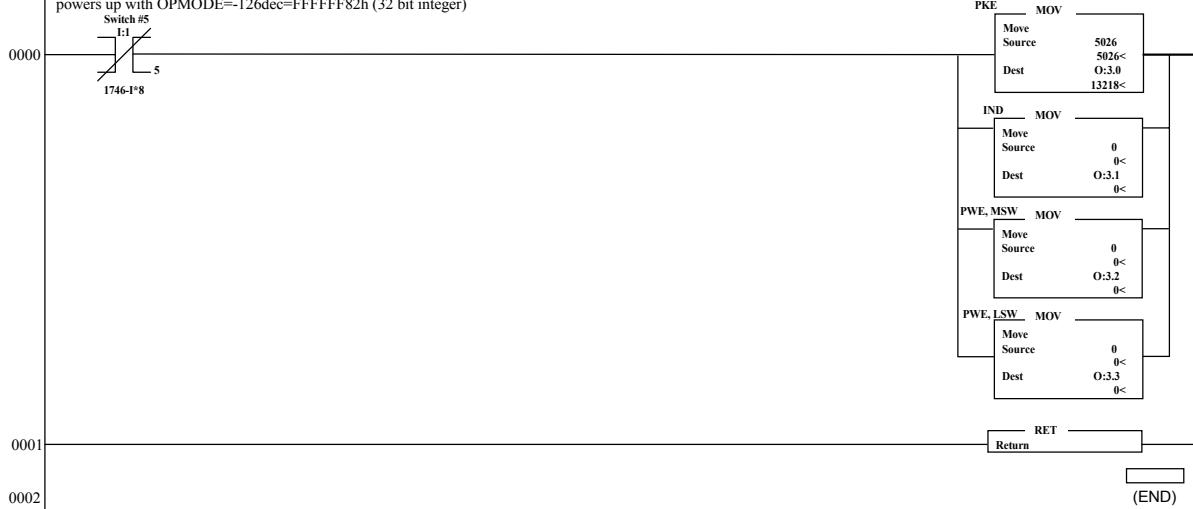
Provide a way to initialize the telegram, in this case by writing zeros to each word.



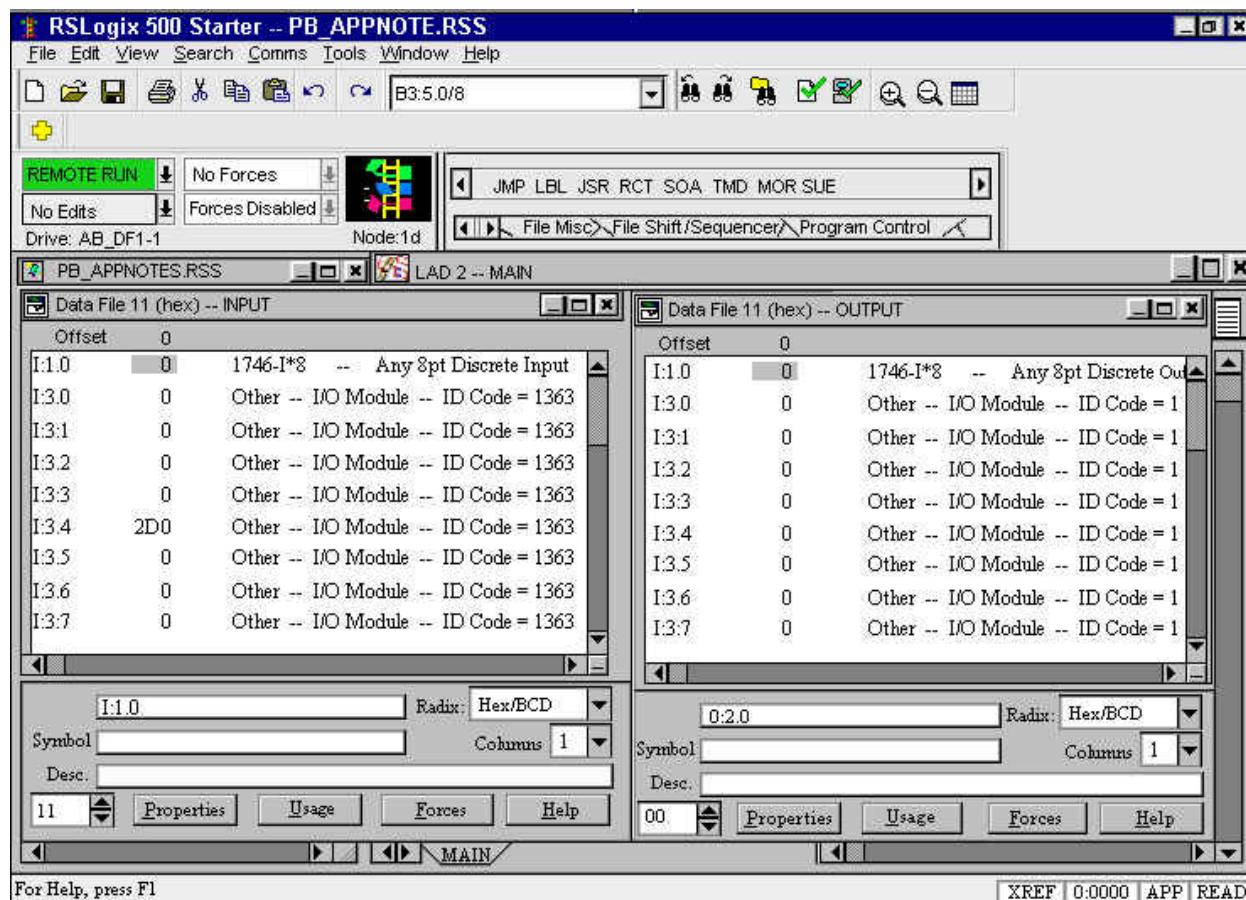
Read Profibus OPMODE

File 11: read parameter 930 - profibus OPMODE

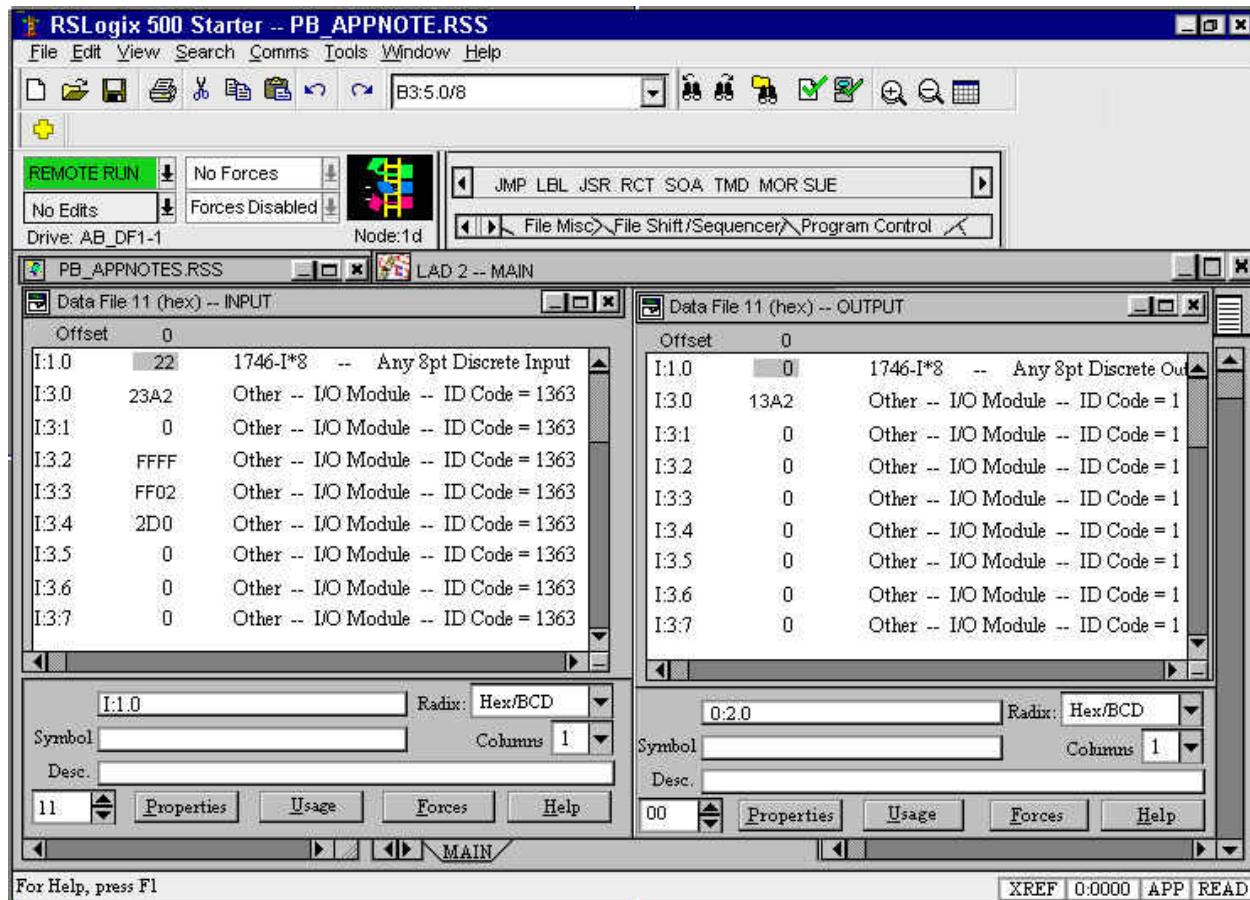
To read a PNU, supply the PNU (930 dec = 3A2 H) and the AK (1 to read a parameter). The PKE=13A2h=5026 dec. This data is written to the PKE, in this case O:3.0. The drive responds with the requested PNU, AK=2 (successful response) in the PKE and the data, so I:3.0=23A2h, and PWE MWS=FFFFh, PWE LSW=FF82h. The drive powers up with OPMODE=-126dec=FFFFFF82h (32 bit integer)



Read Profibus OPMODE Screen 1

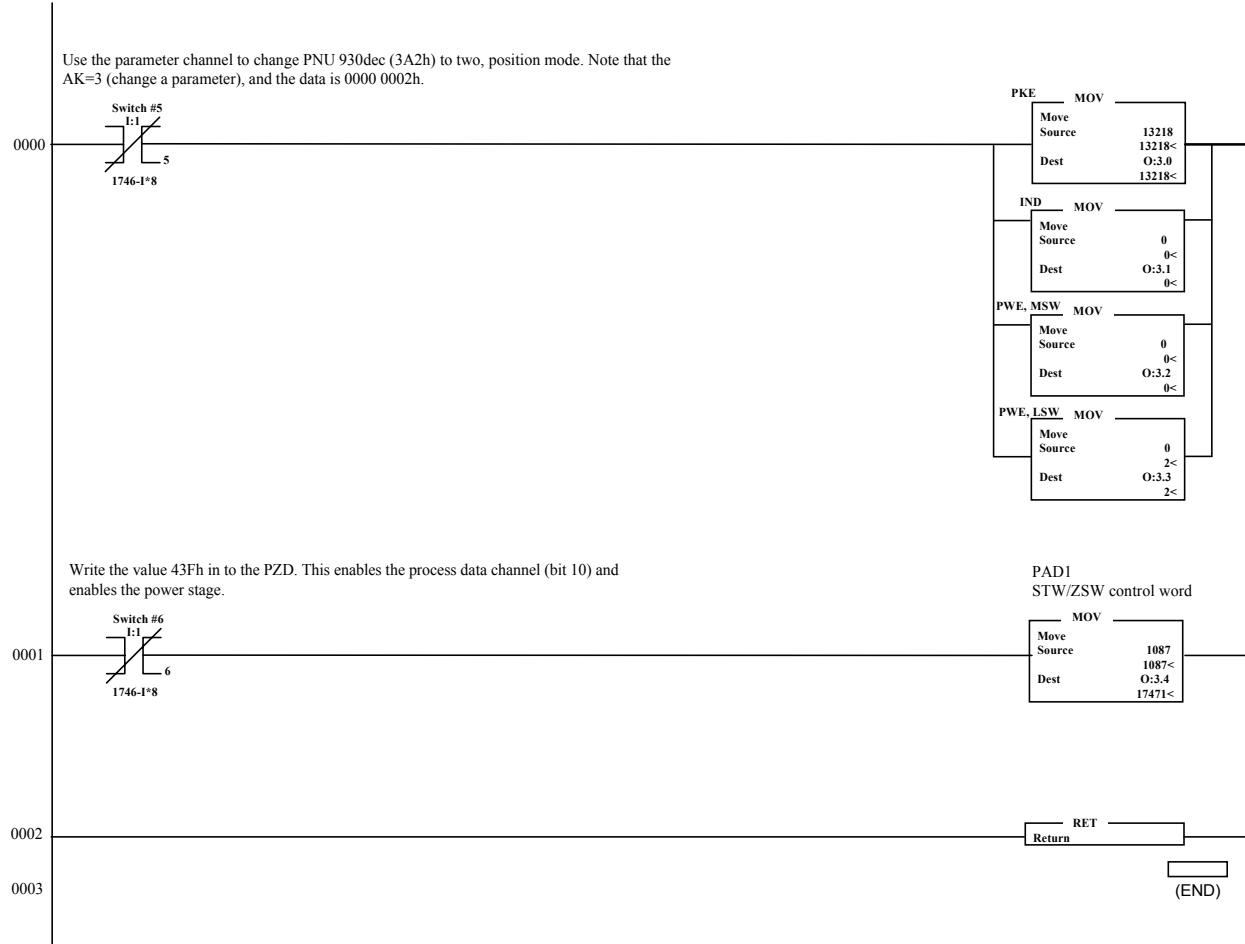


Read Profibus OPMODE Screen 2

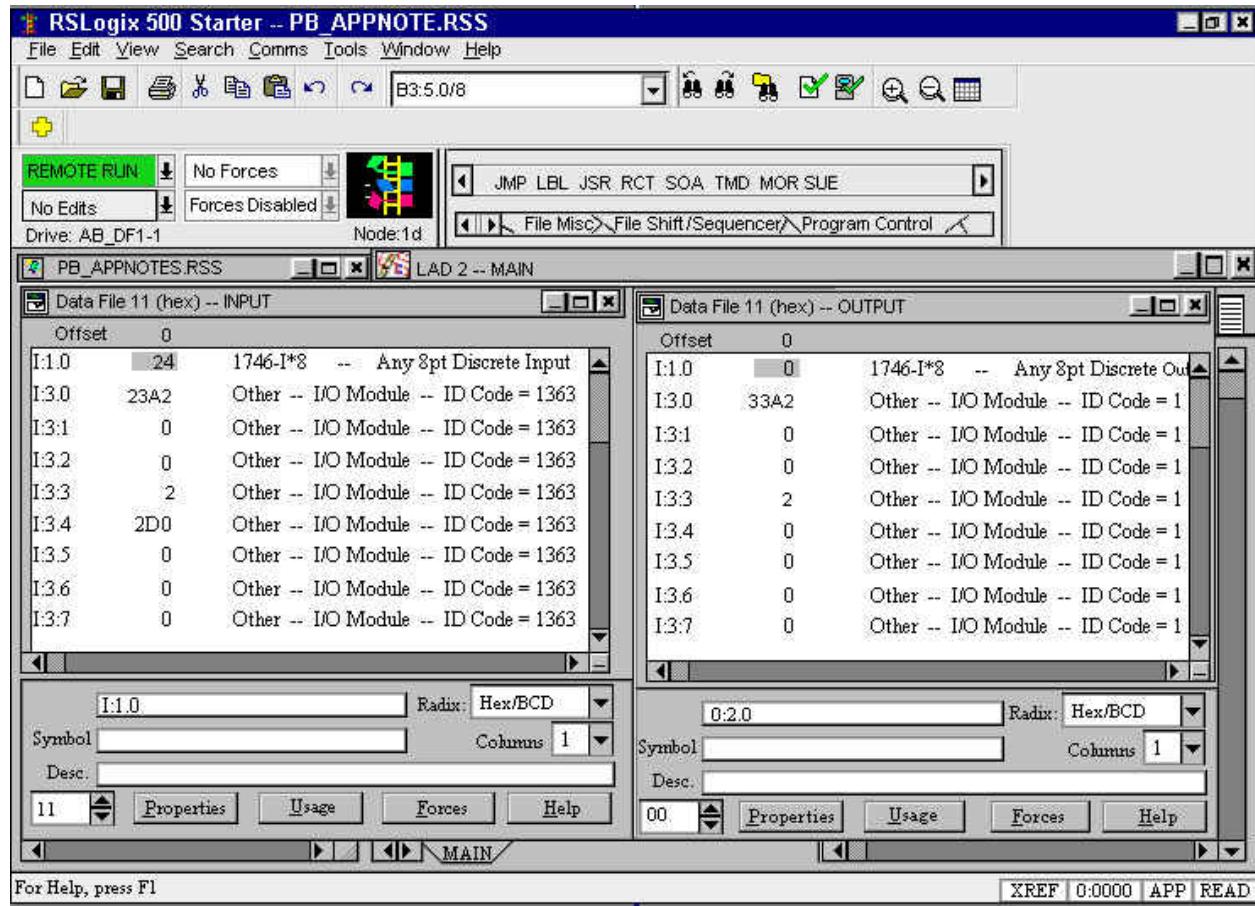


Change to Position Mode (OPMODE=2)

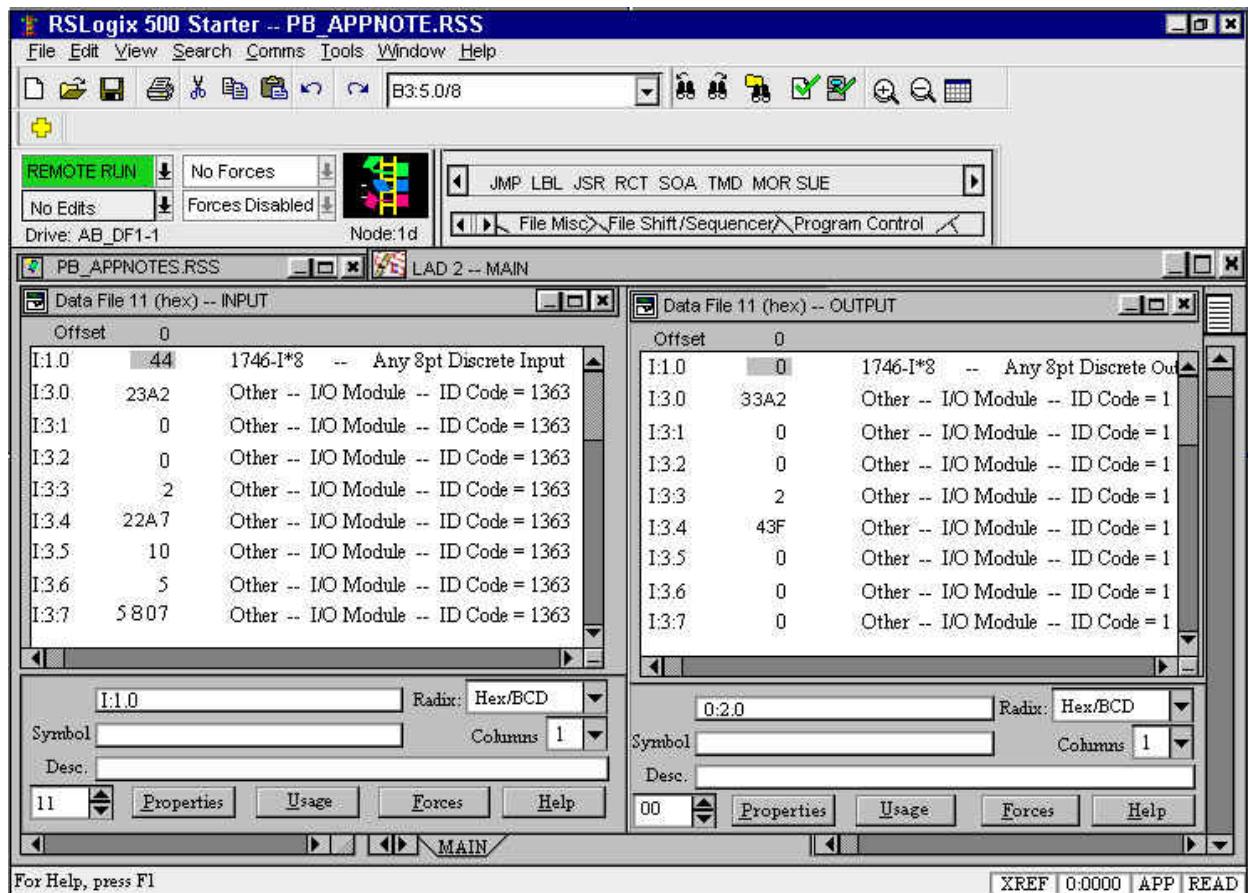
File 12: set position mode (OPMODE=2) and enable PZD



Change Position Mode Screen 1

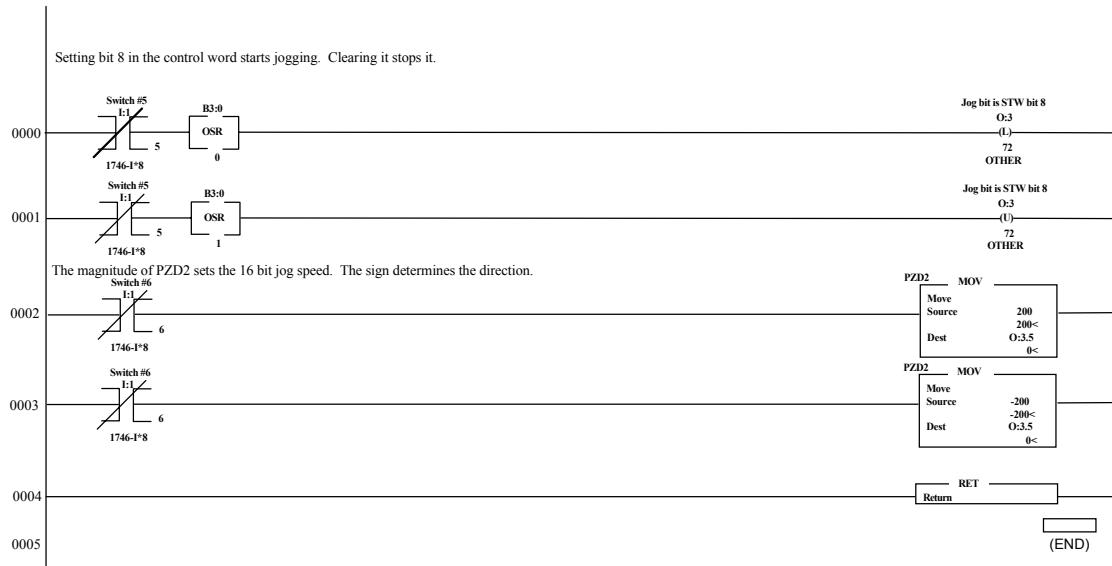


Change Position Mode Screen 2

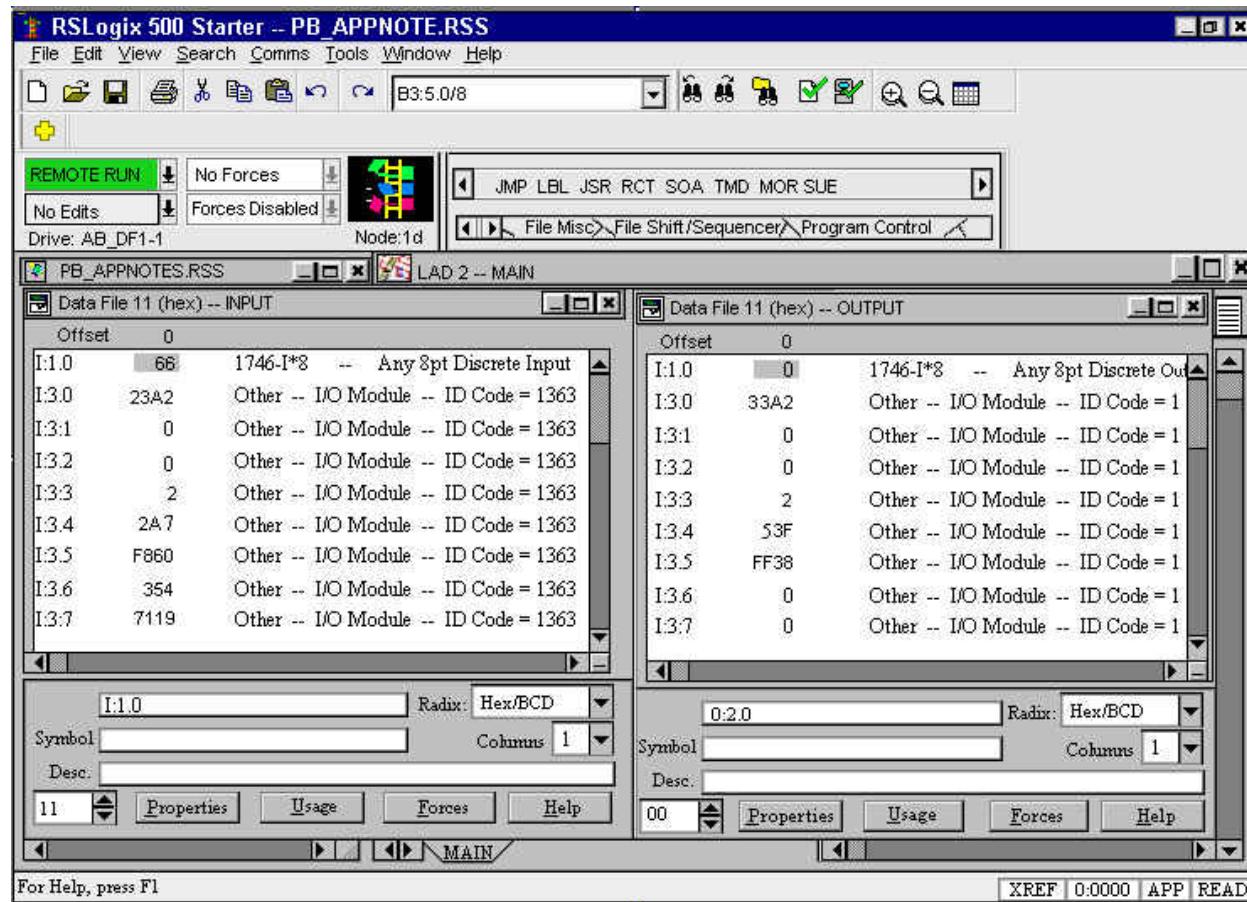


Jog the Motor

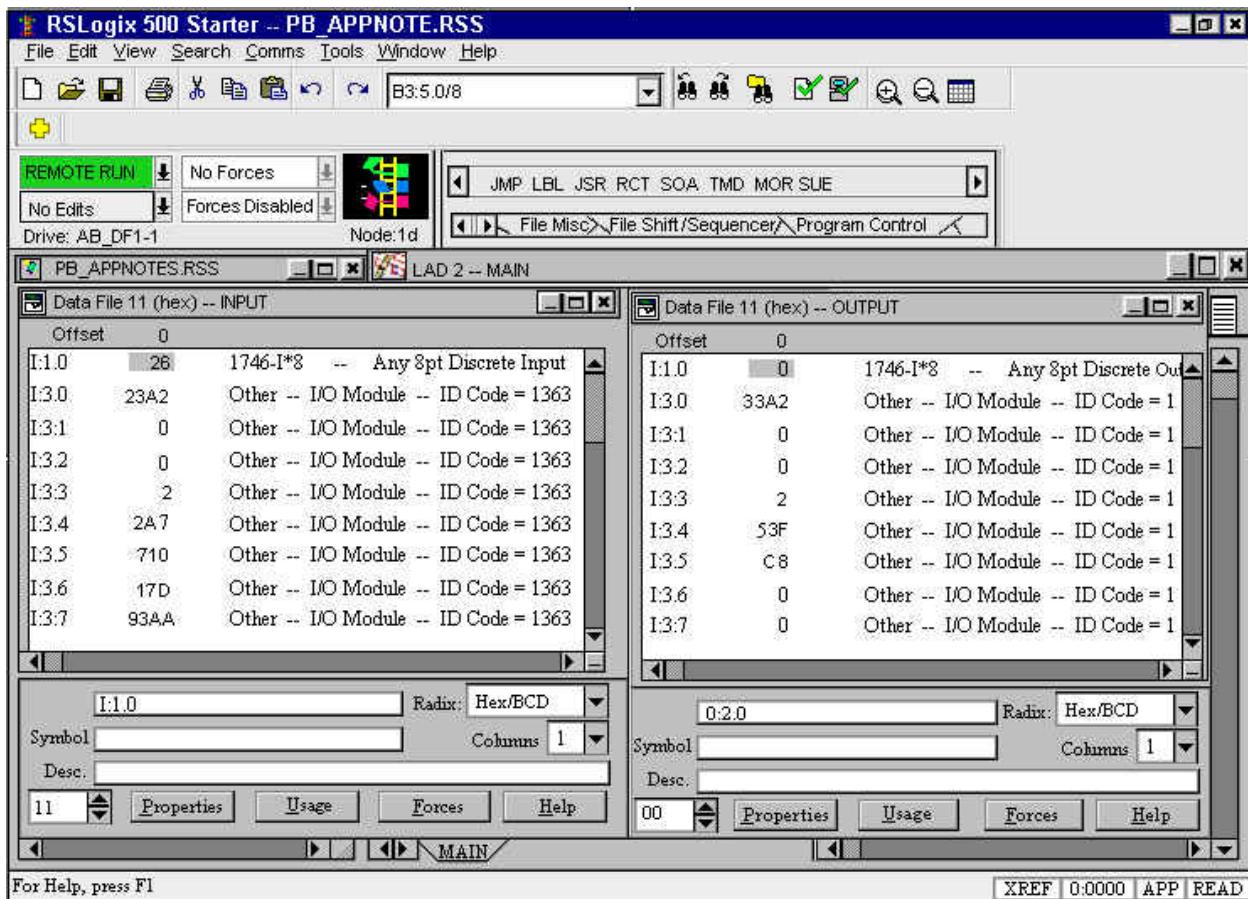
File 13: Jog the motor



Jog Motor Screen 1



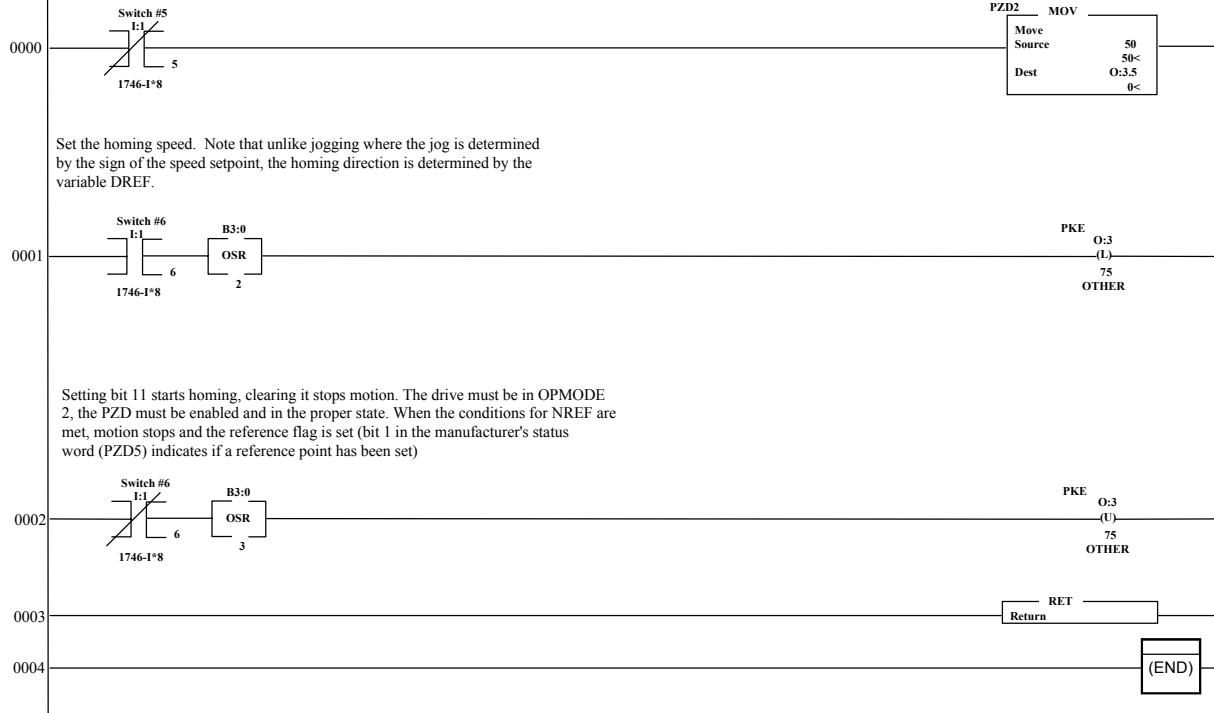
Jog Motor Screen 2



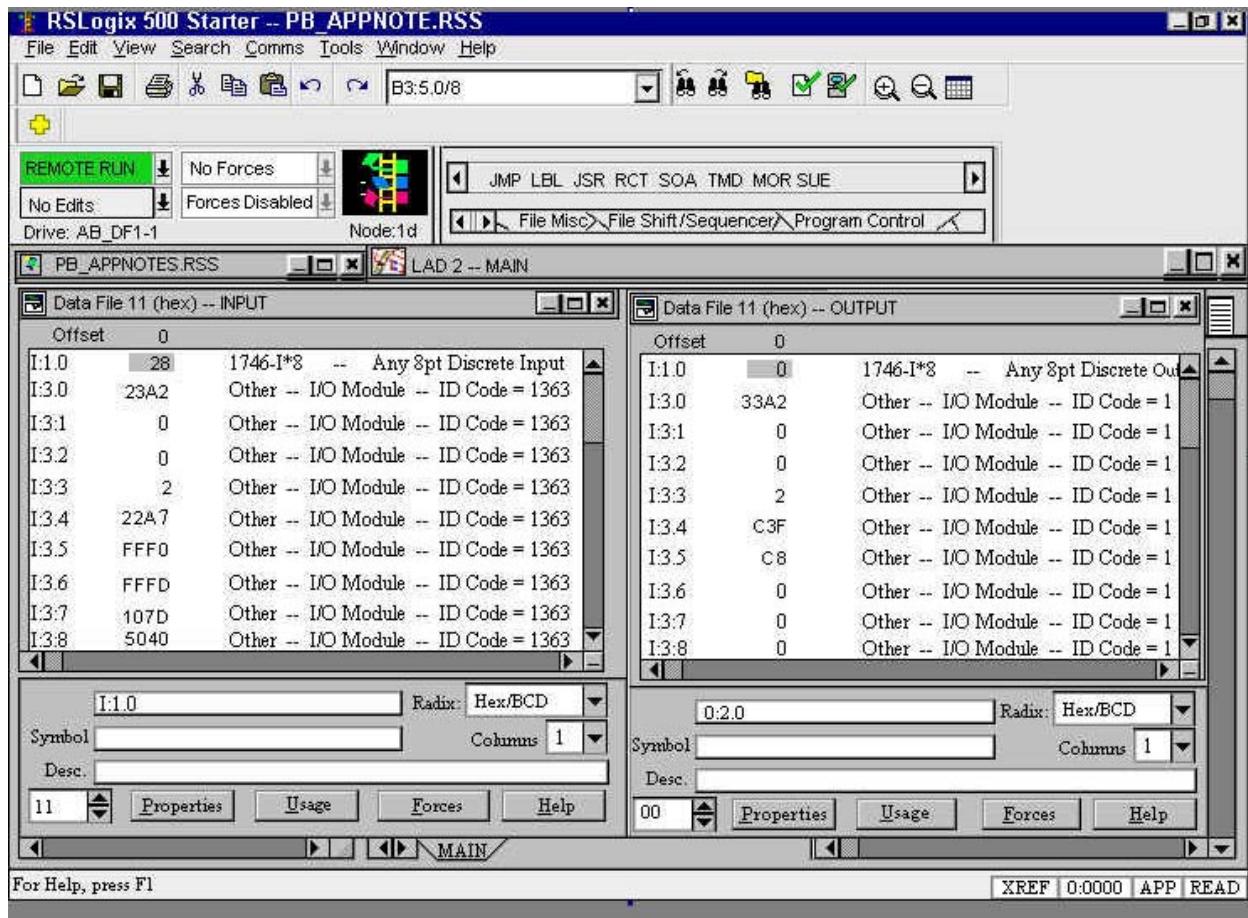
Home Axis

File 14: home the axis

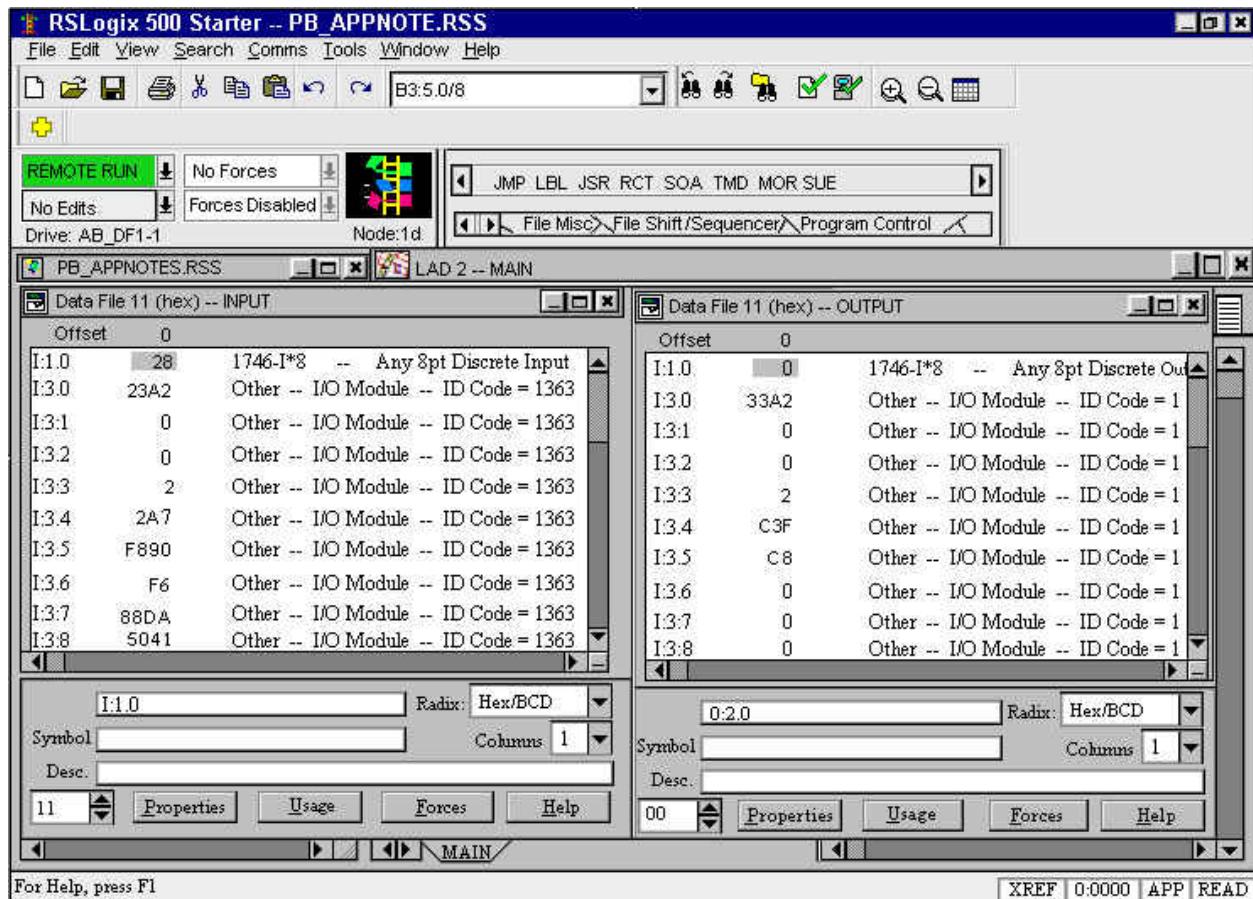
Set the homing speed. Note that unlike jogging where the jog direction is determined by the sign of the speed setpoint, the homing direction is determined by the variable, DREF.



Home Axis Screen 1

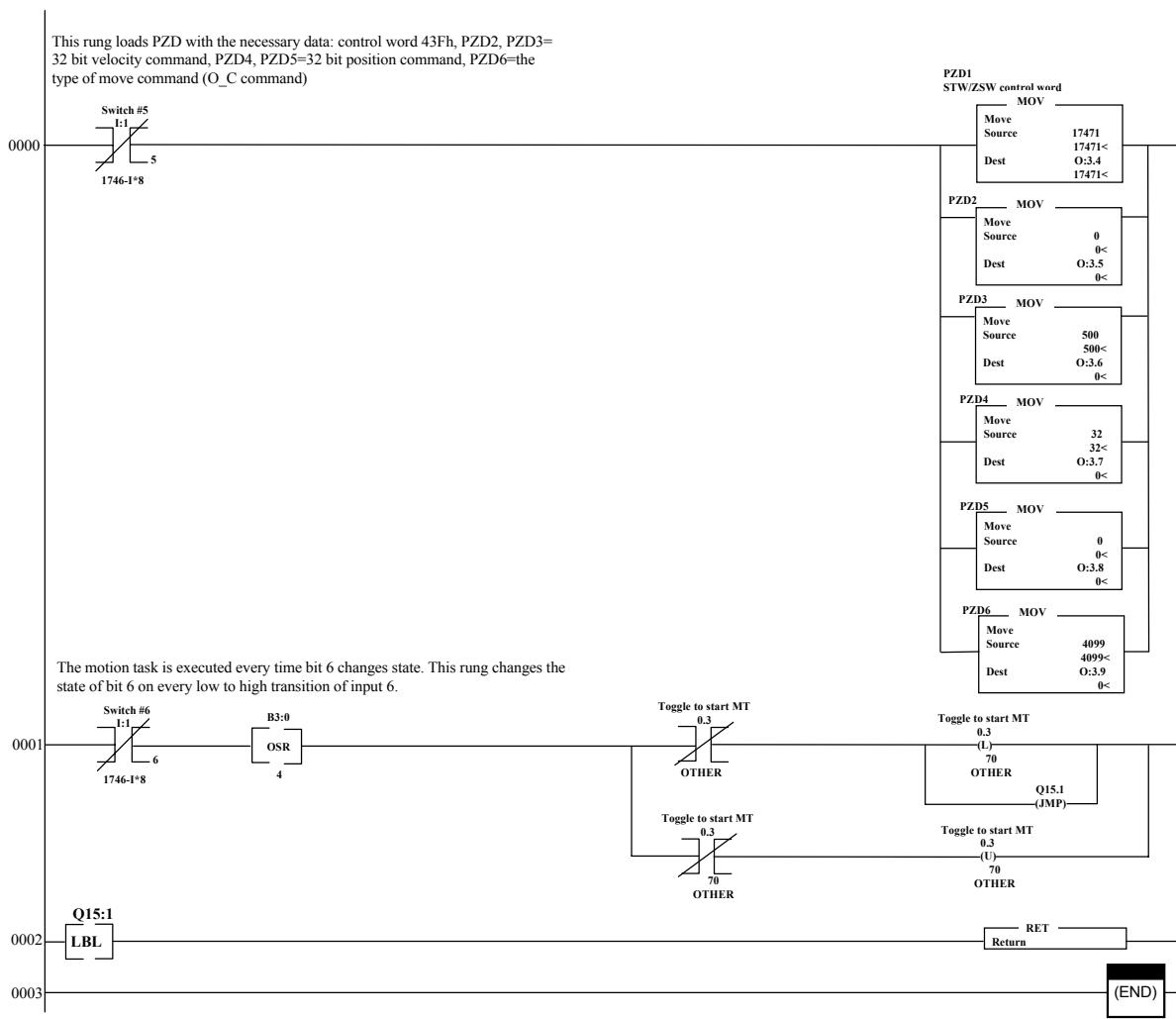


Home Axis Screen 2

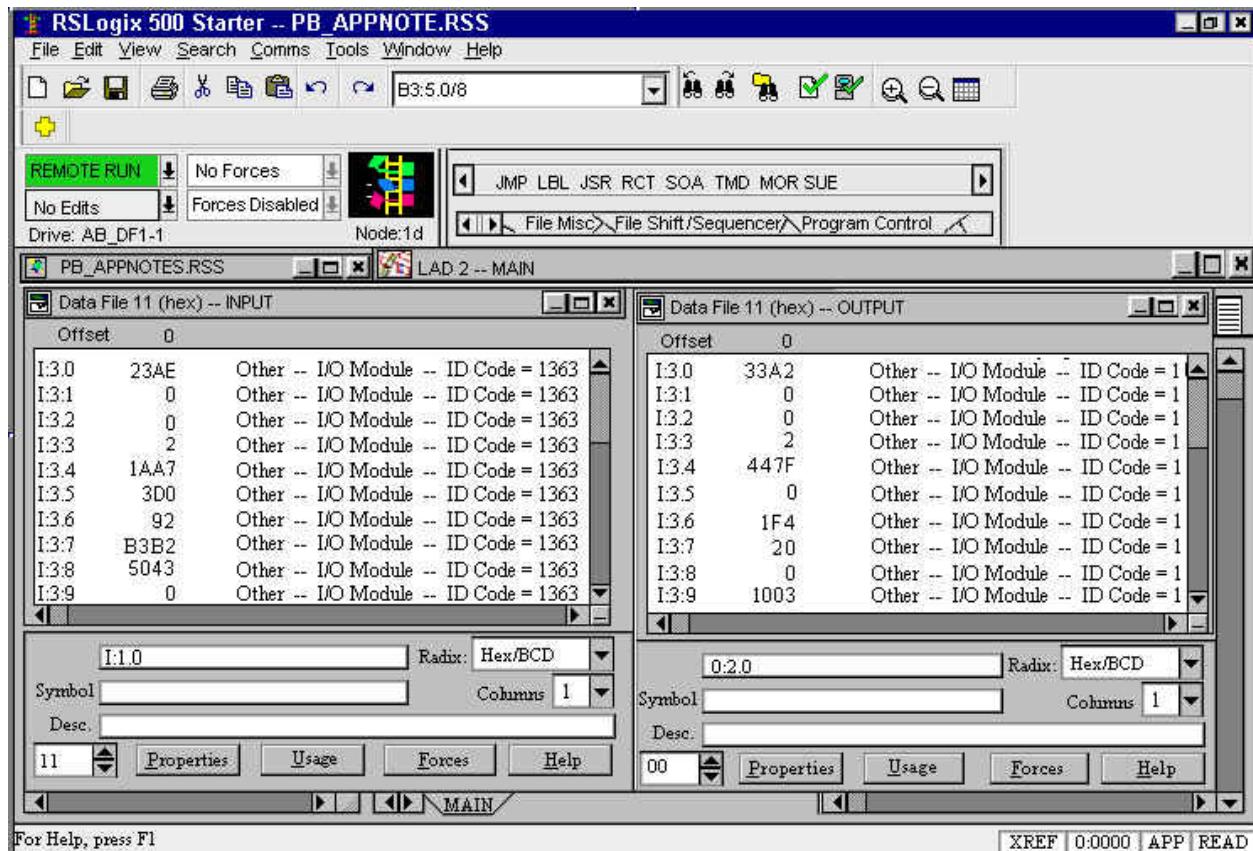


Run Direct Motion Task

File 15: run direct motion task

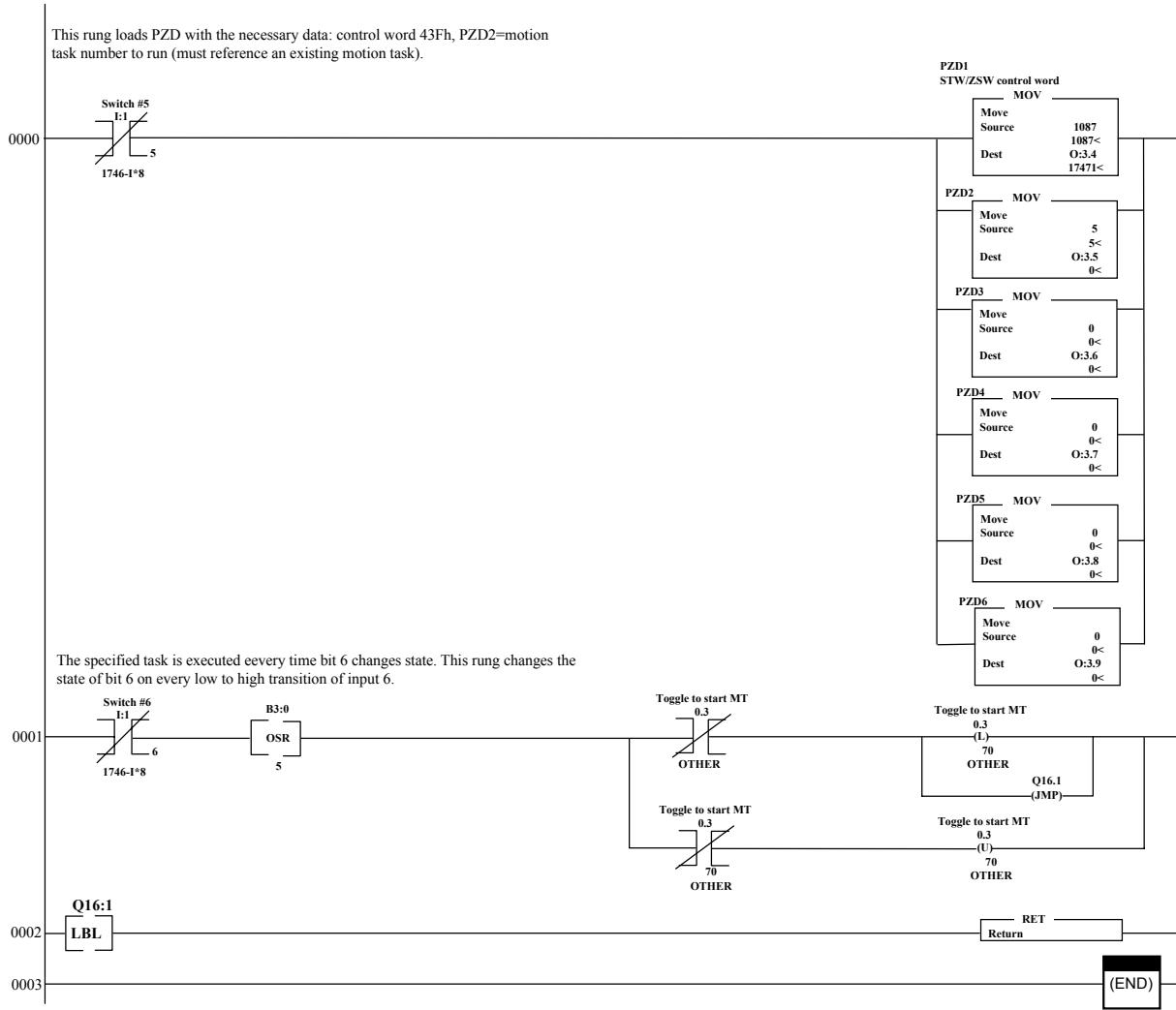


Run Direct Motion Task Screen

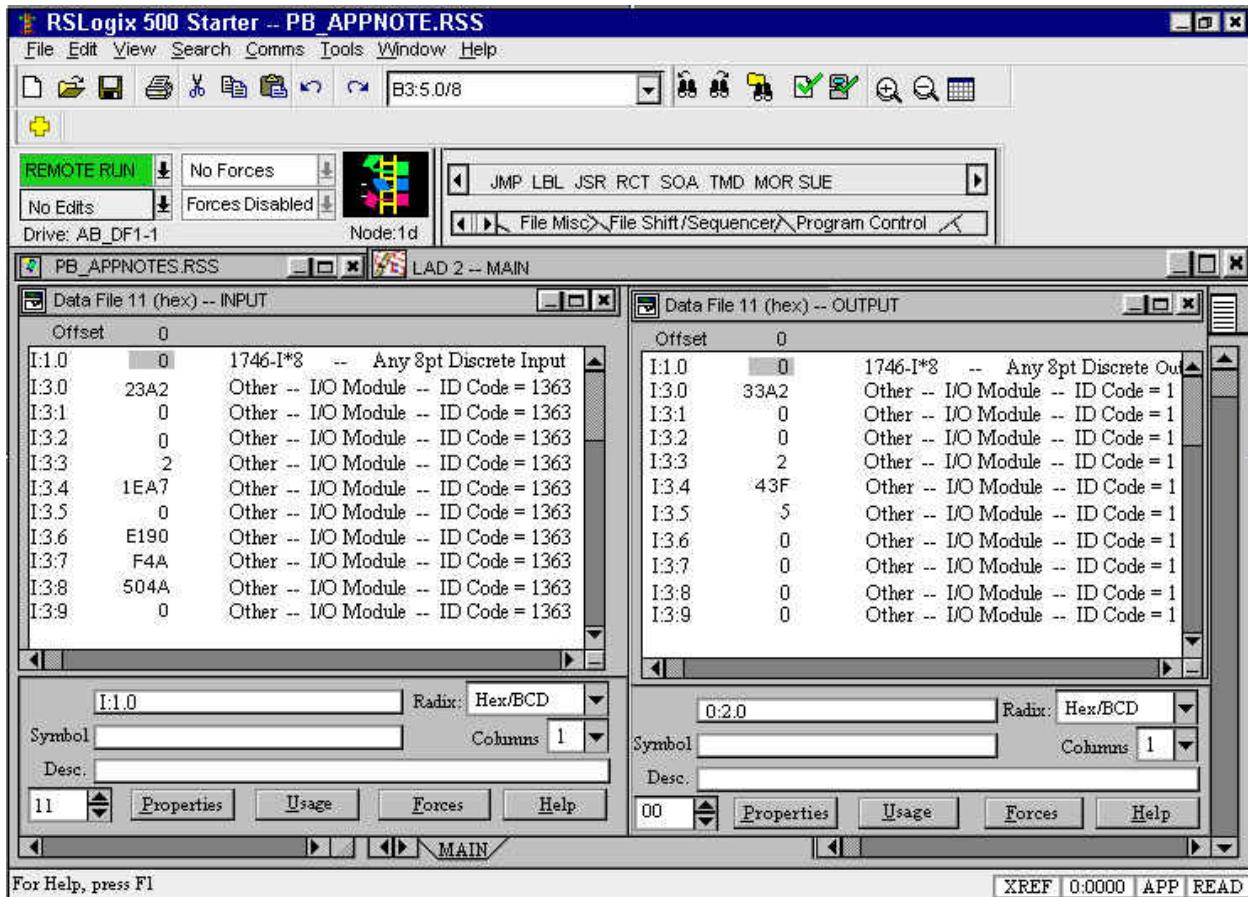


Run Stored Motion Task

File 16: run a stored motion task

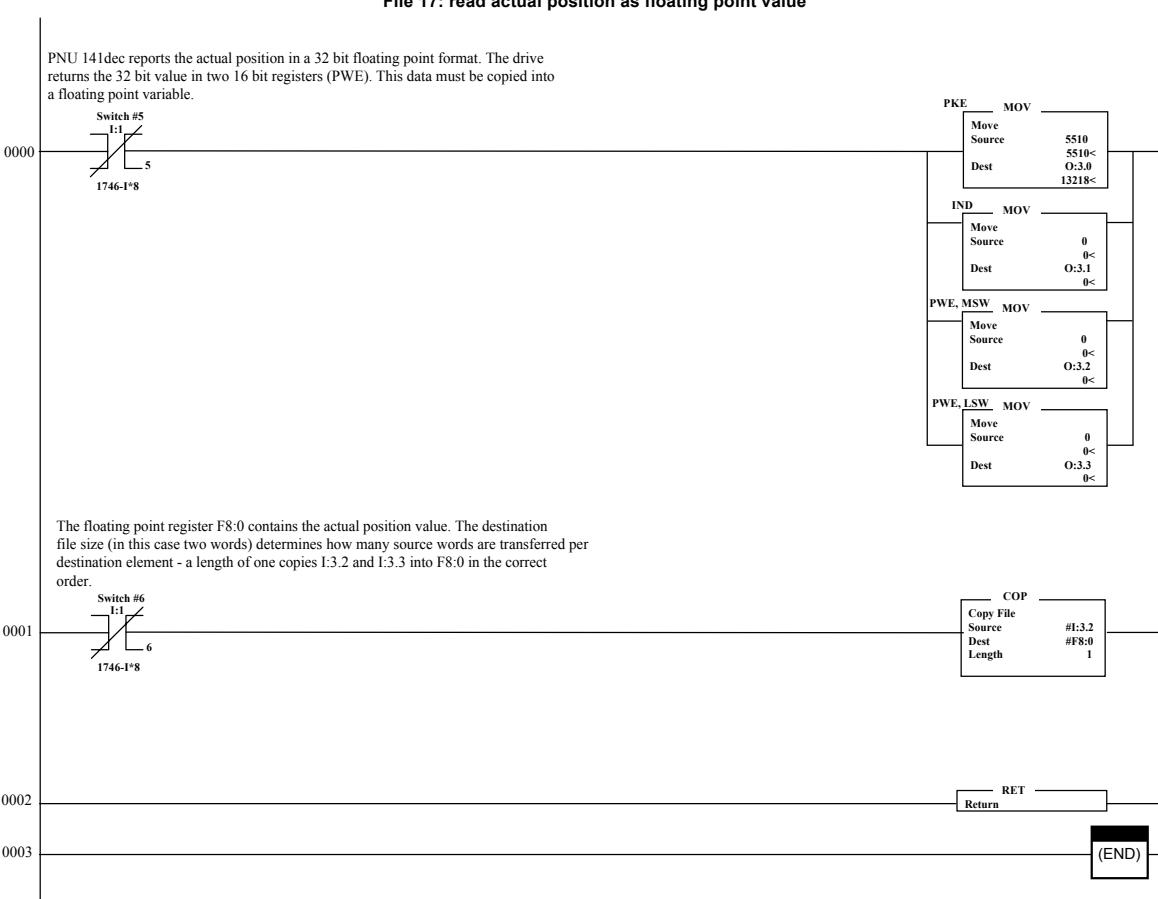


Run Stored Motion Task Screen

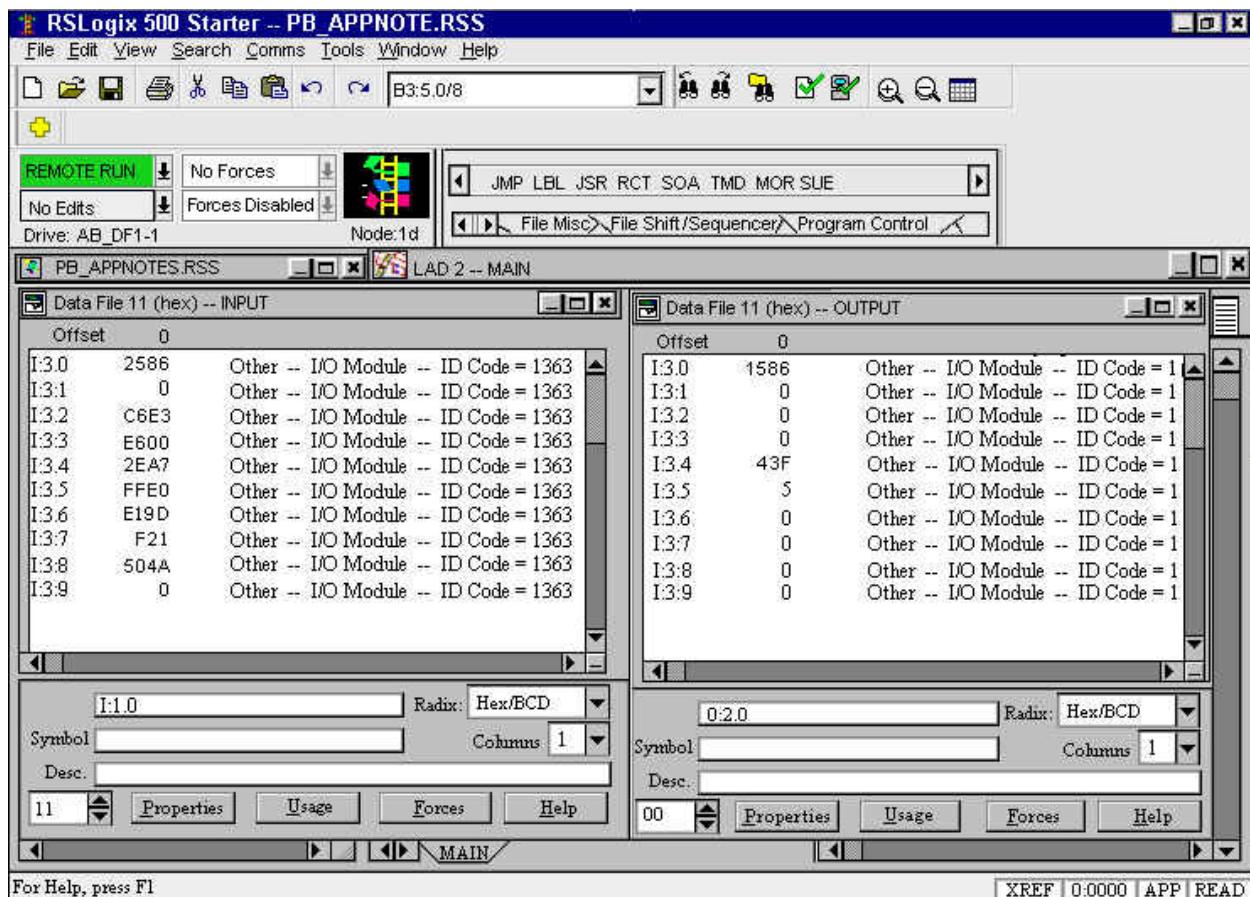


Read Position as Floating-Point Value

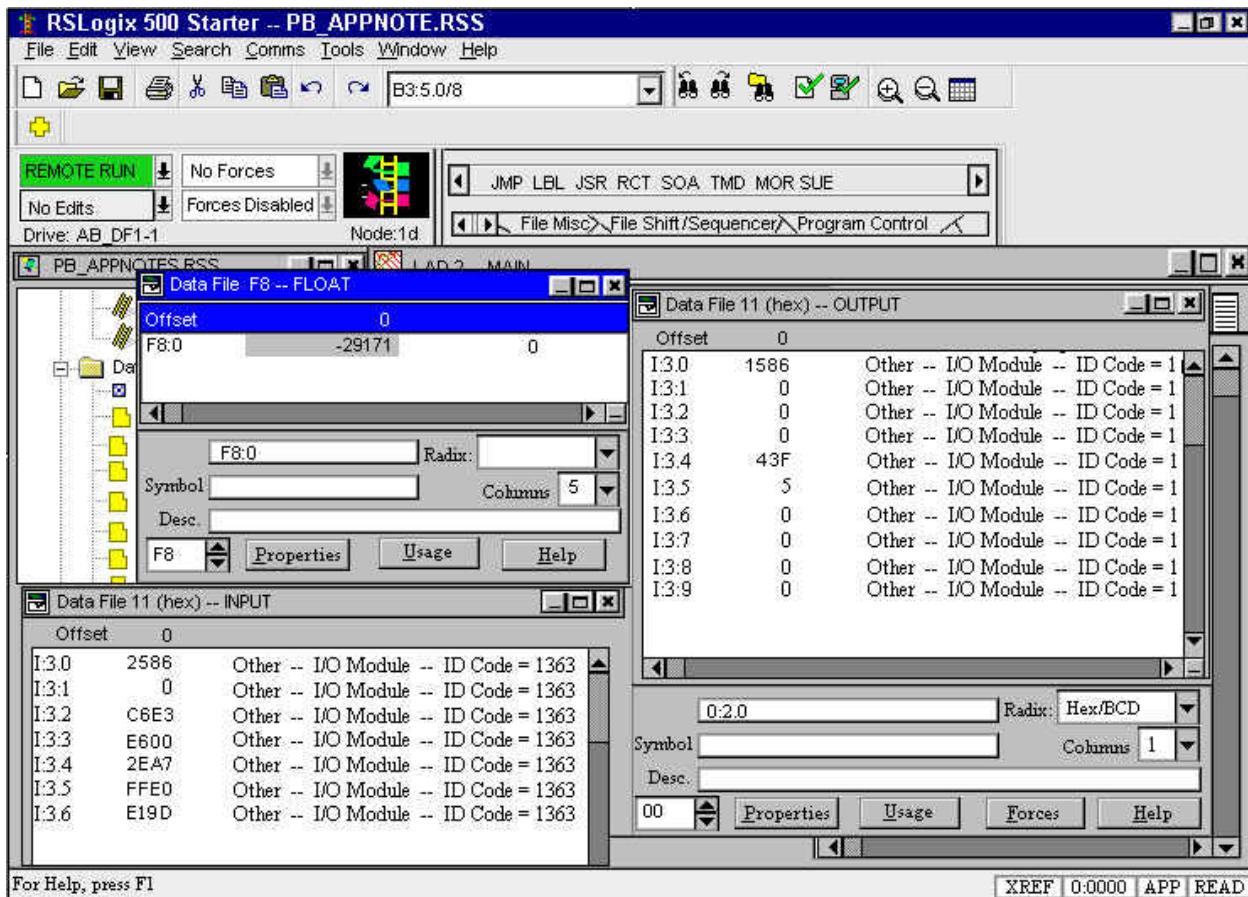
File 17: read actual position as floating point value



Read Position as Floating-Point Value Screen 1

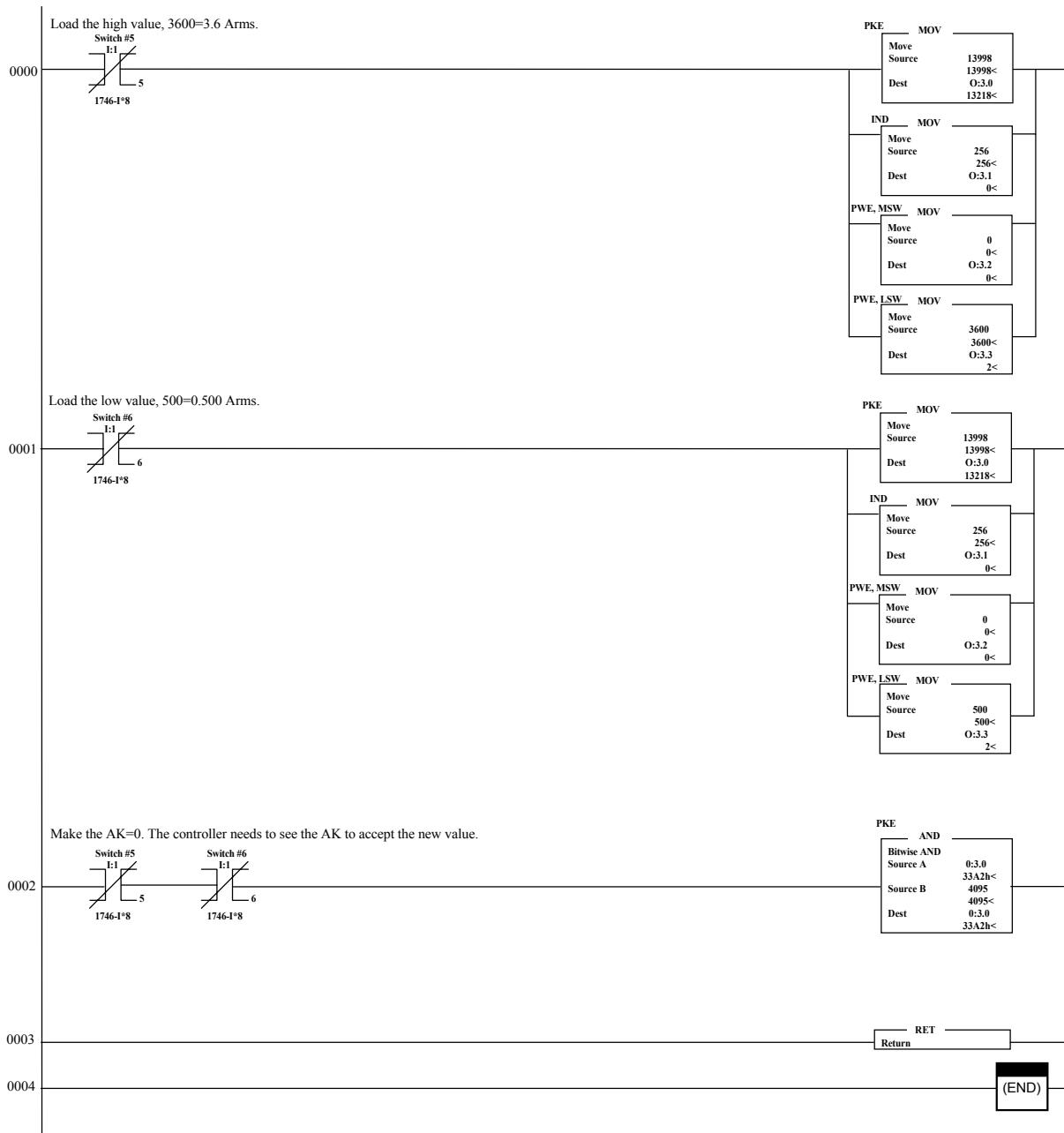


Read Position as Floating-Point Value Screen 2

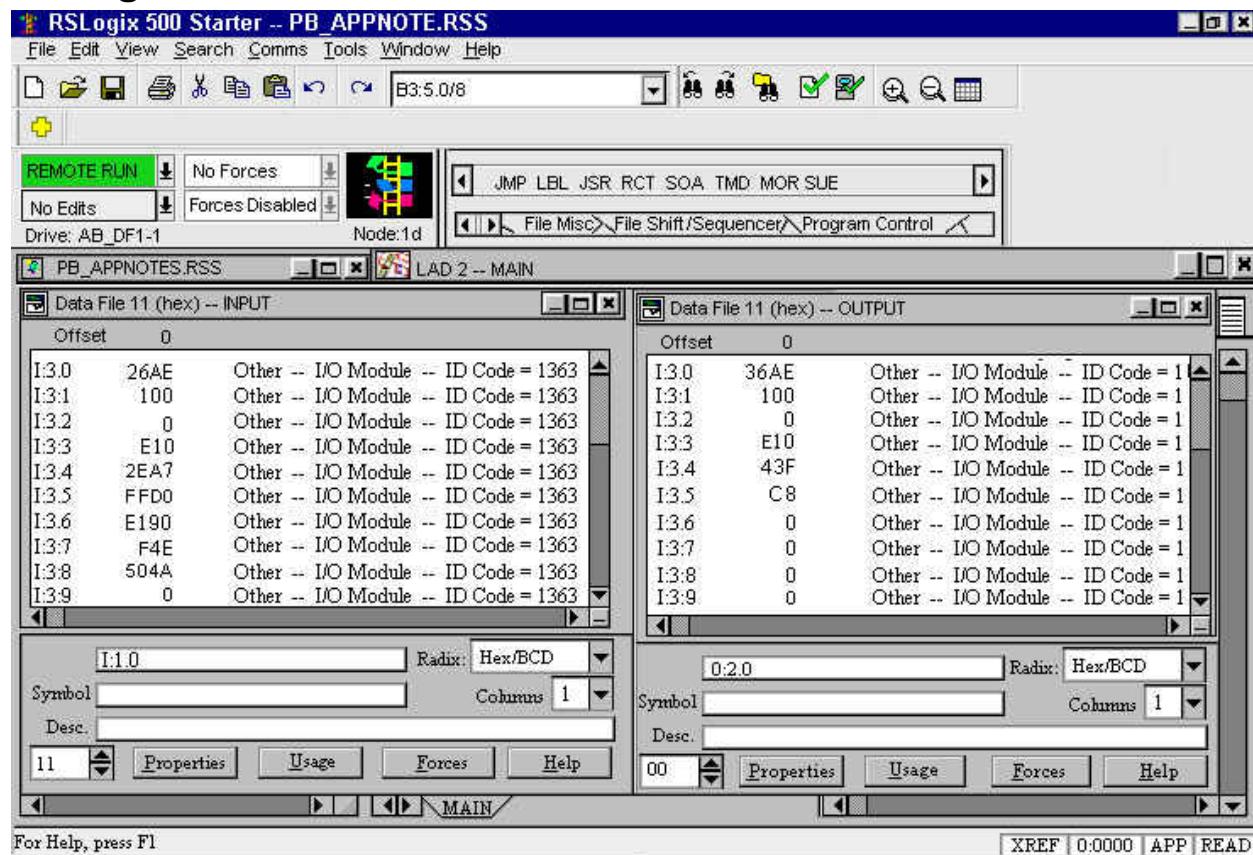


Change Index Parameter (IPEAK)

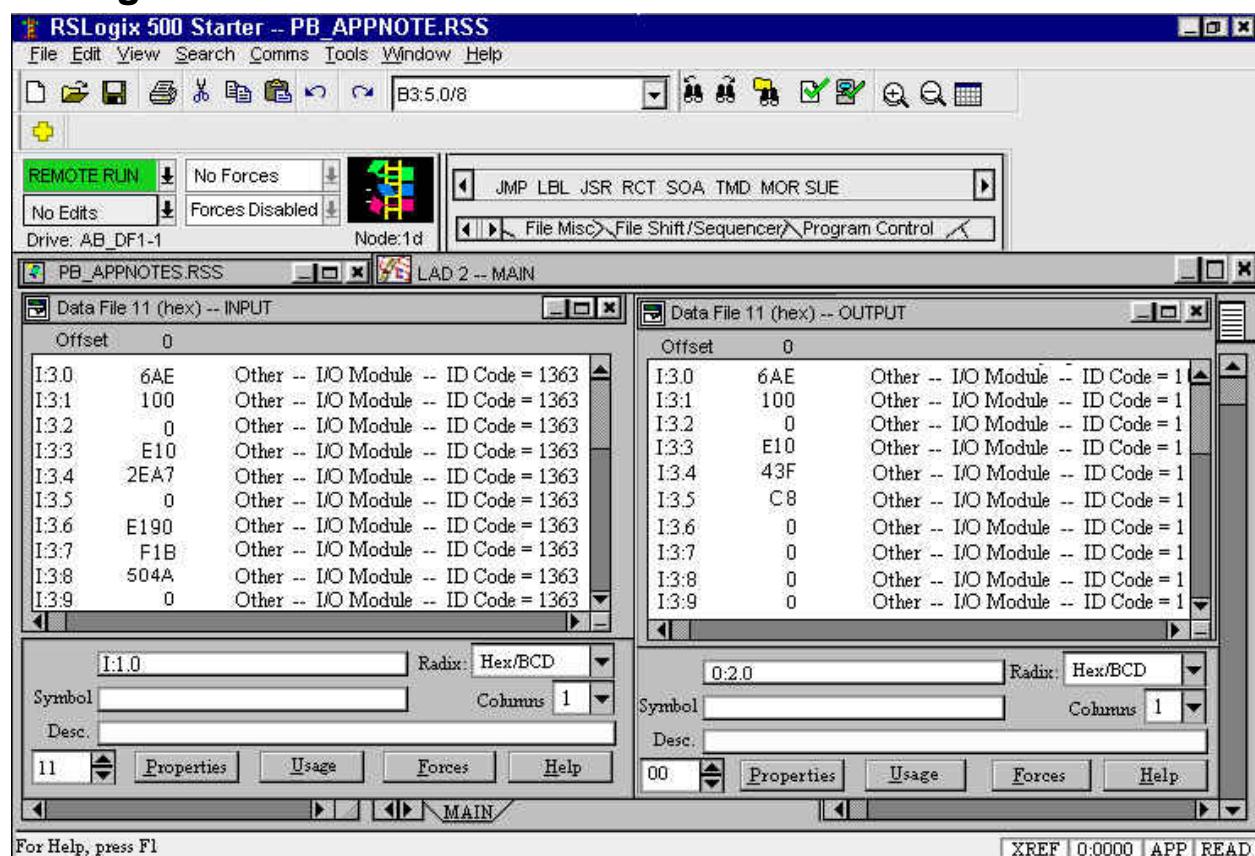
File 18: change between two values of peak current (IPEAK) peak torque



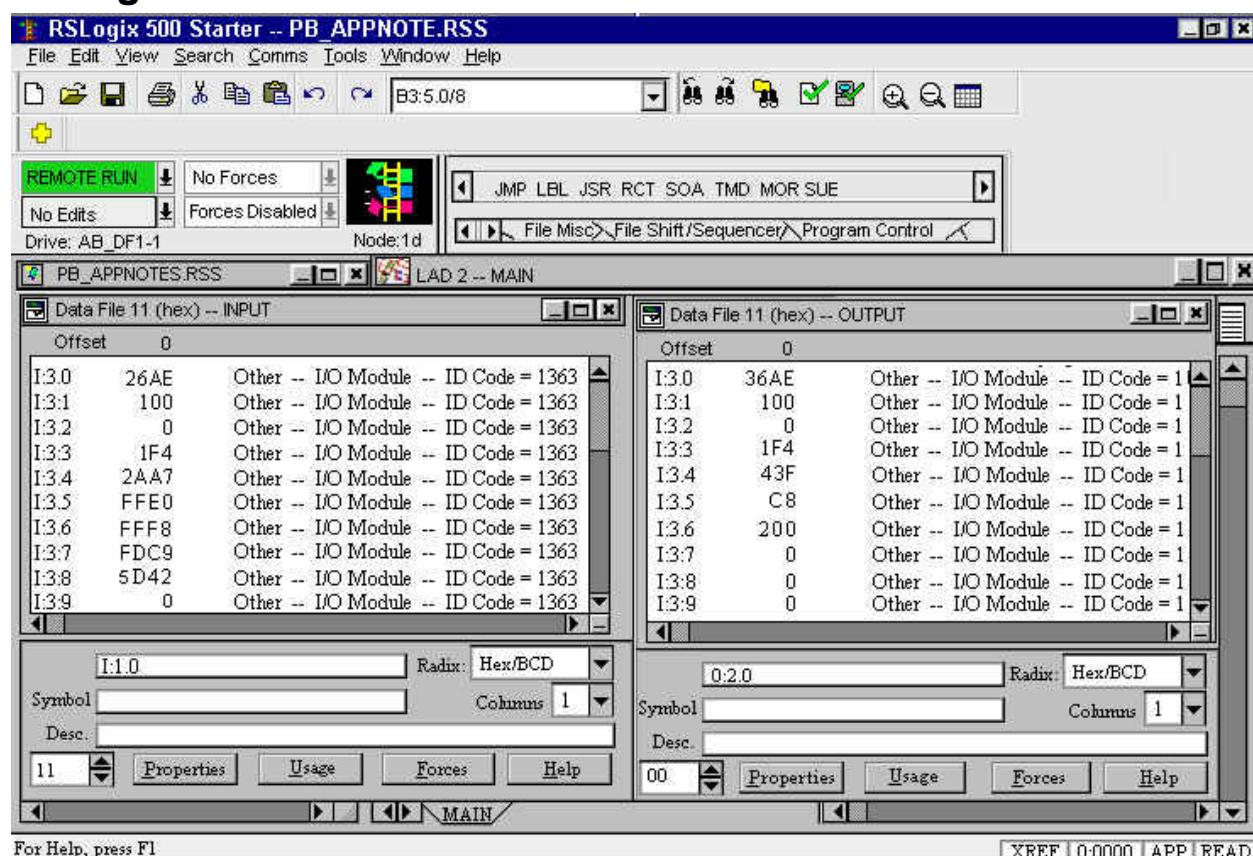
Change IPEAK Screen 1



Change IPEAK Screen 2

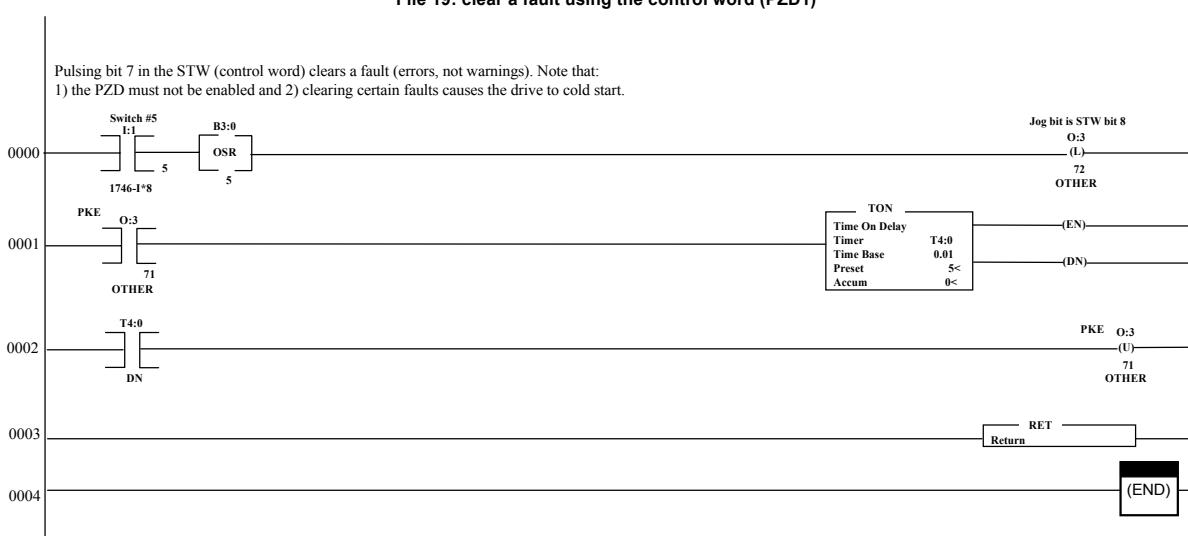


Change IPEAK Screen 3

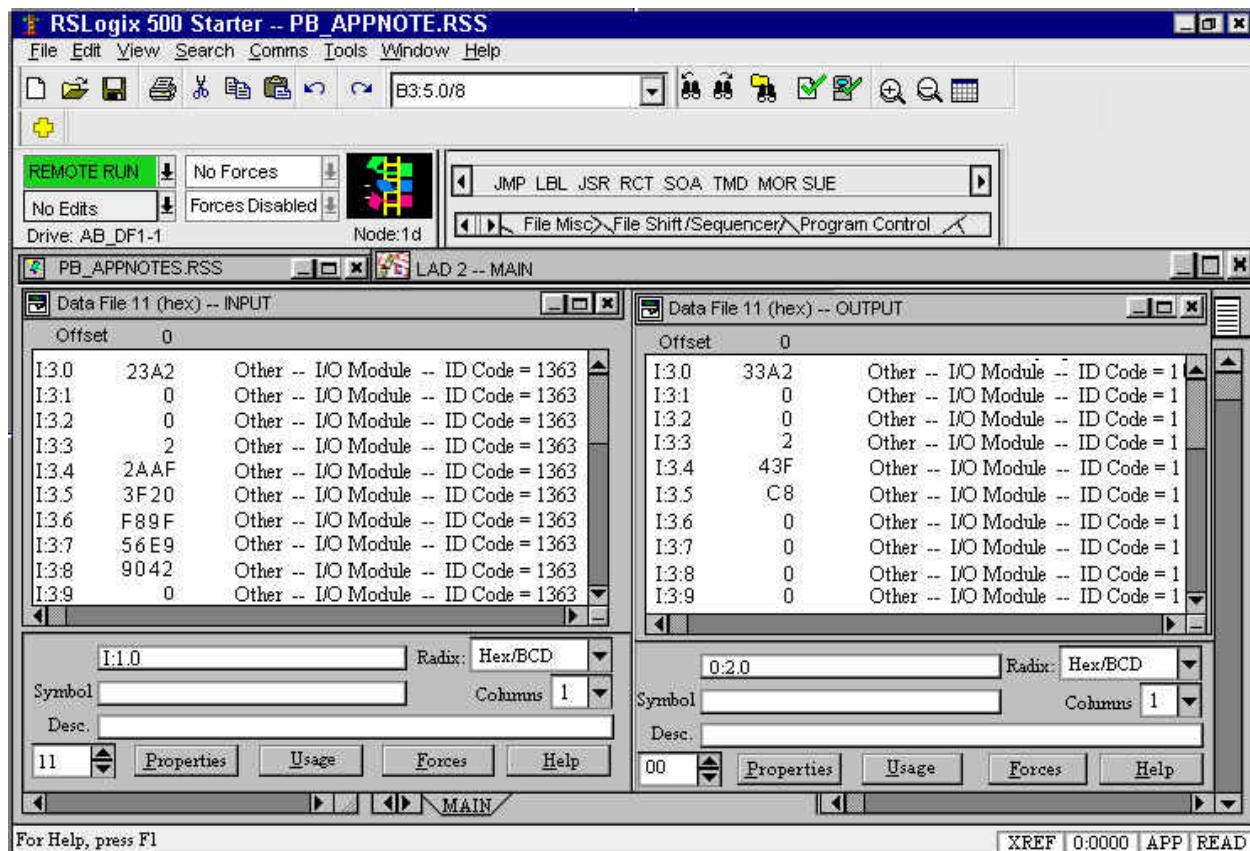


Clear a Fault

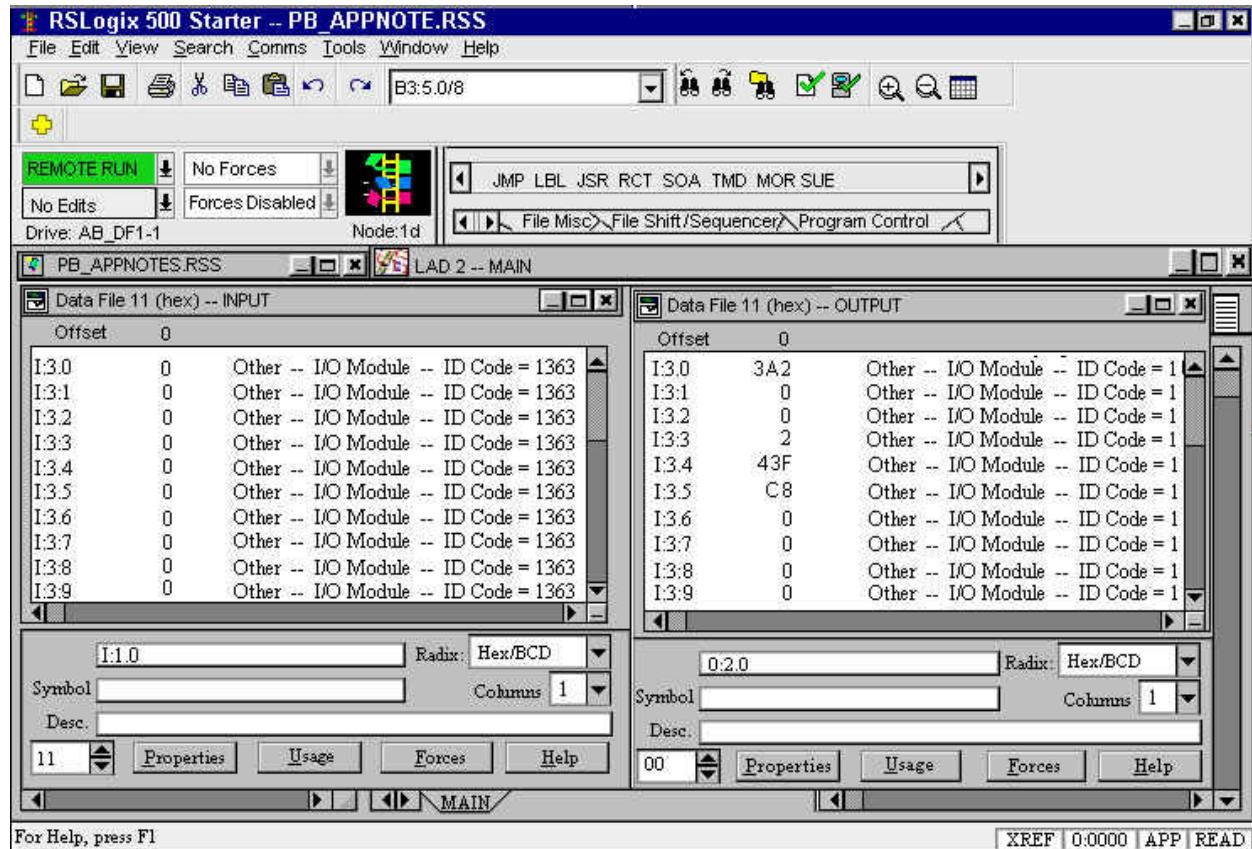
File 19: clear a fault using the control word (PZD1)



Clear a Fault Screen 1

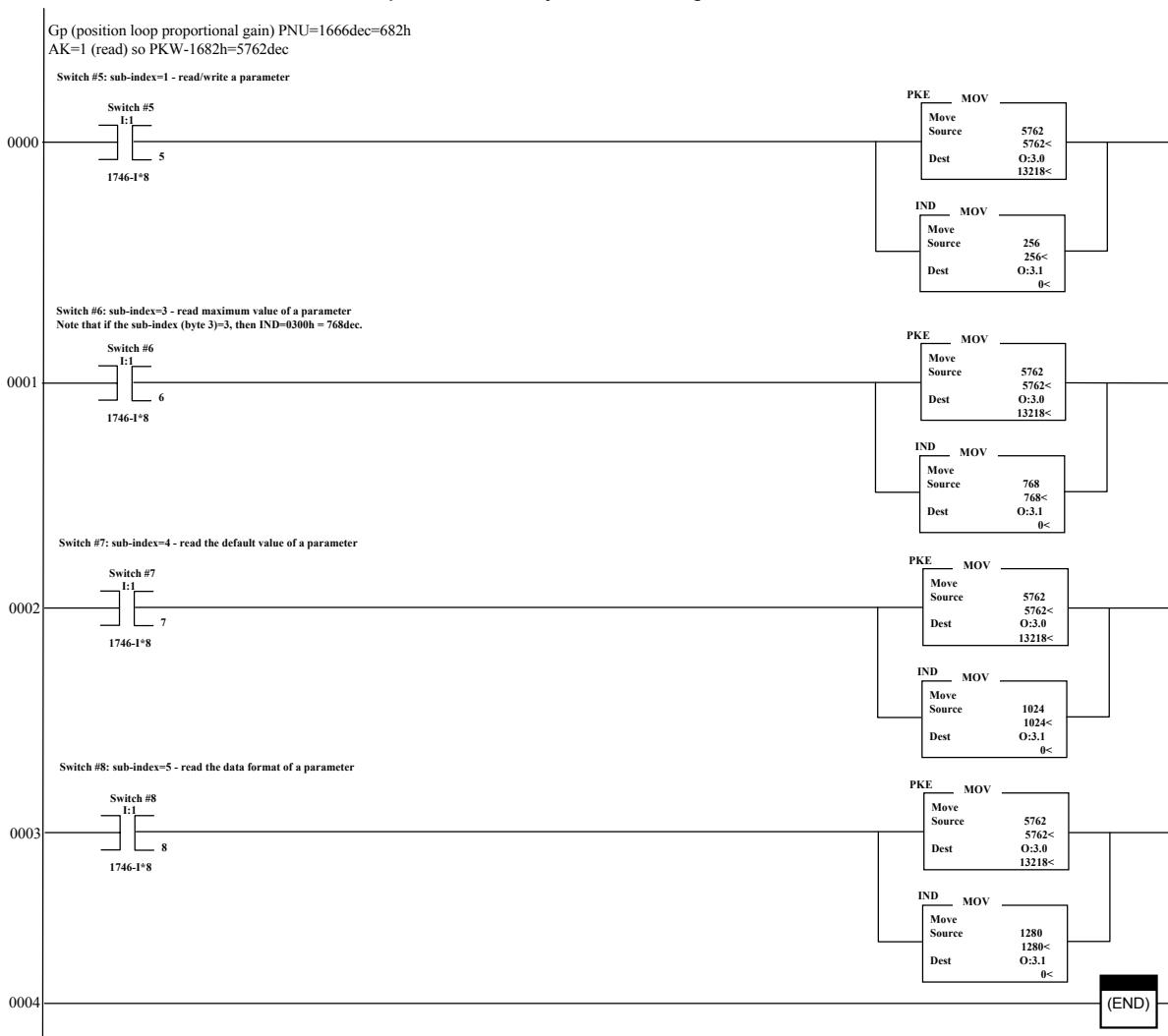


Clear a Fault Screen 2

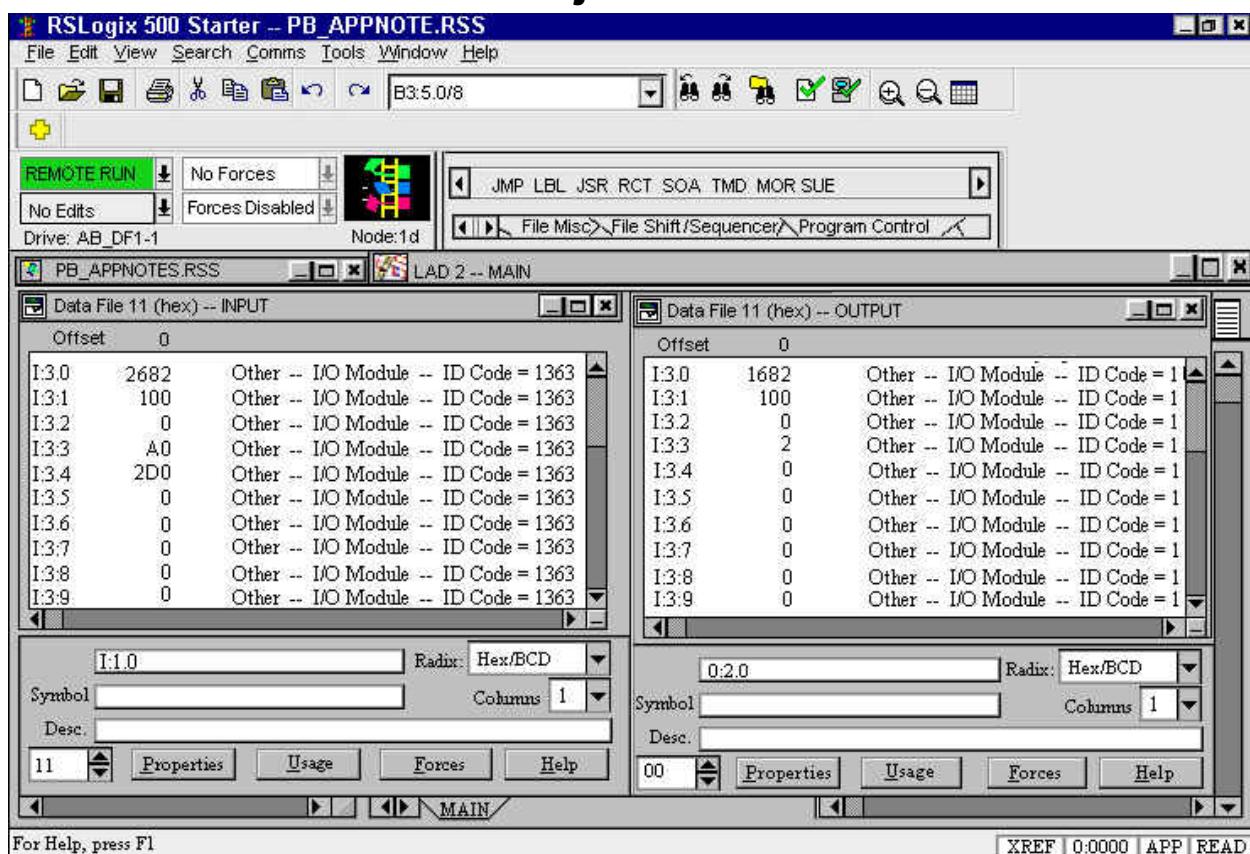


Read Data Via Parameter Object Channel

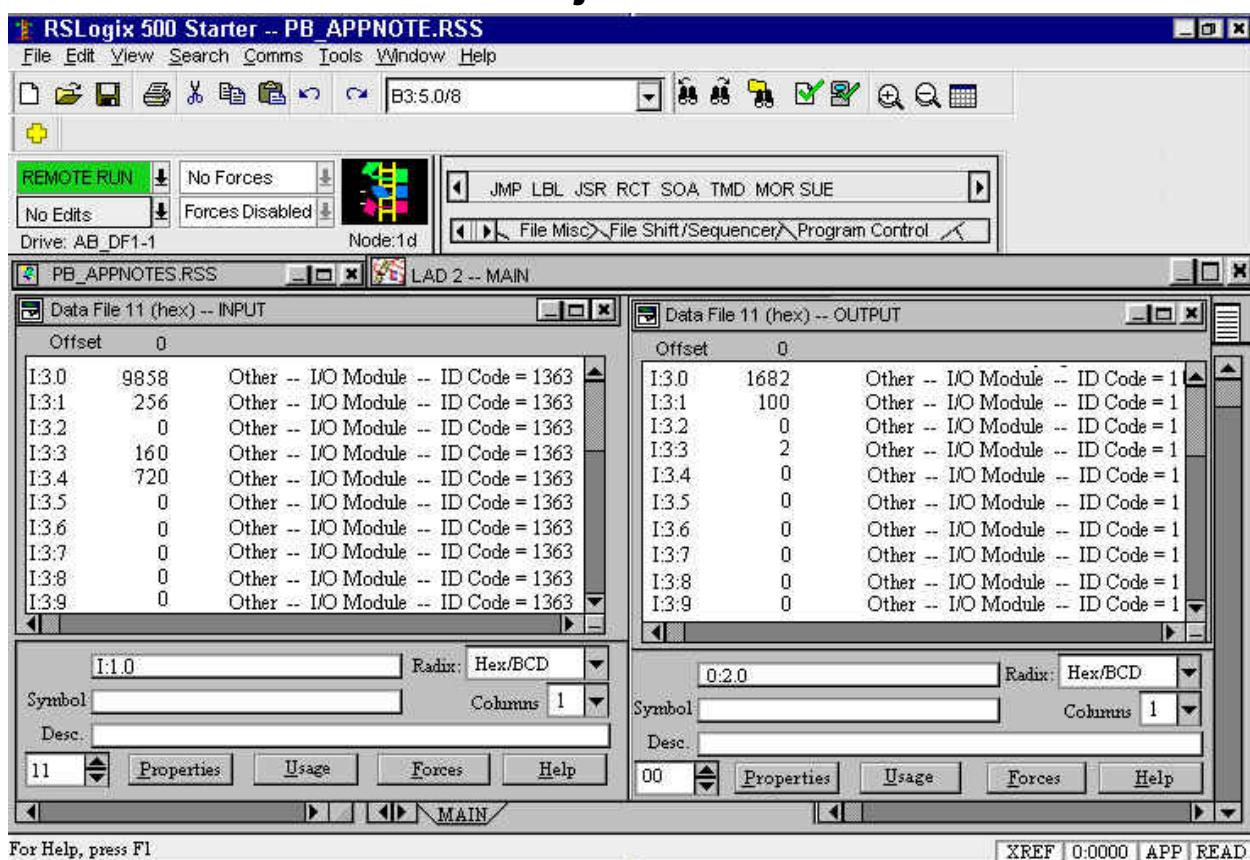
File 20: Read Gp via Parameter Object Channel Using Sub-Index



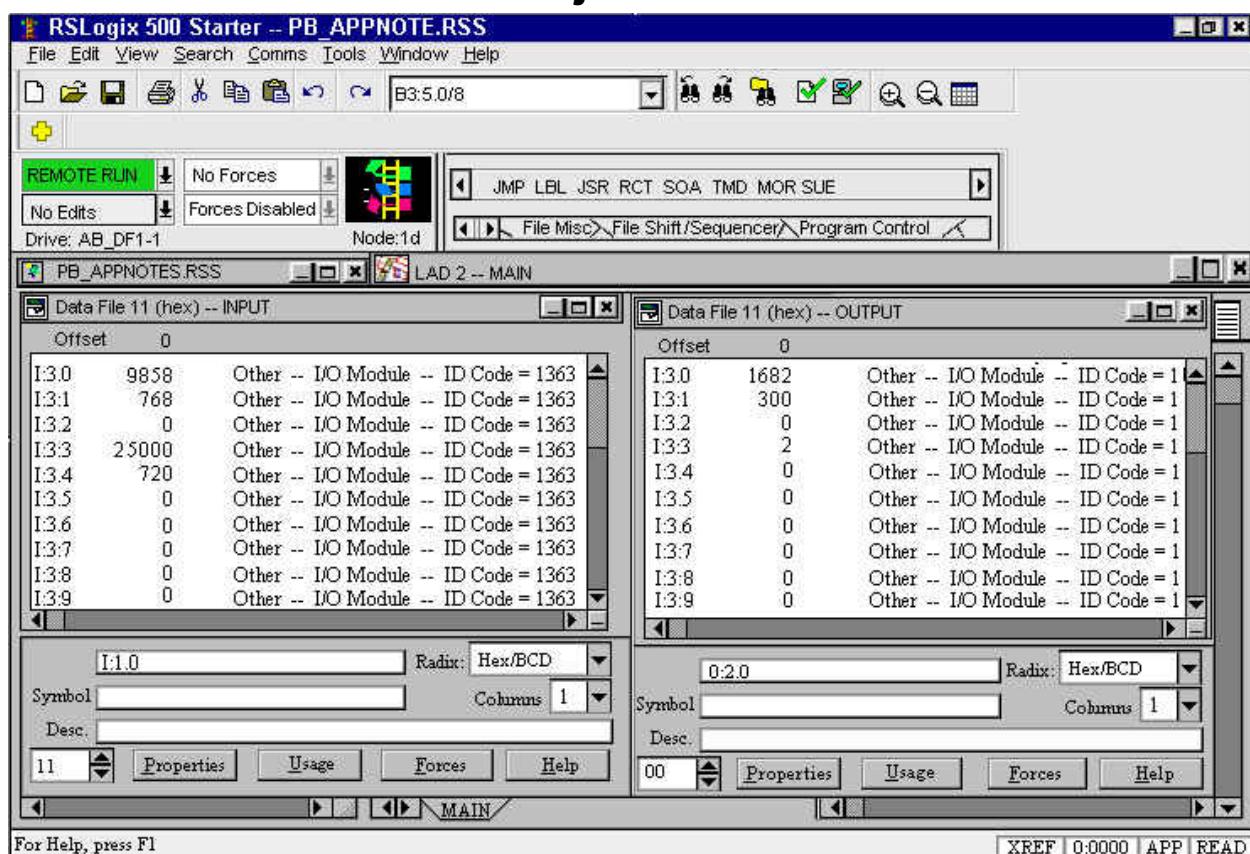
Read Data via Parameter Object Channel Screen 1



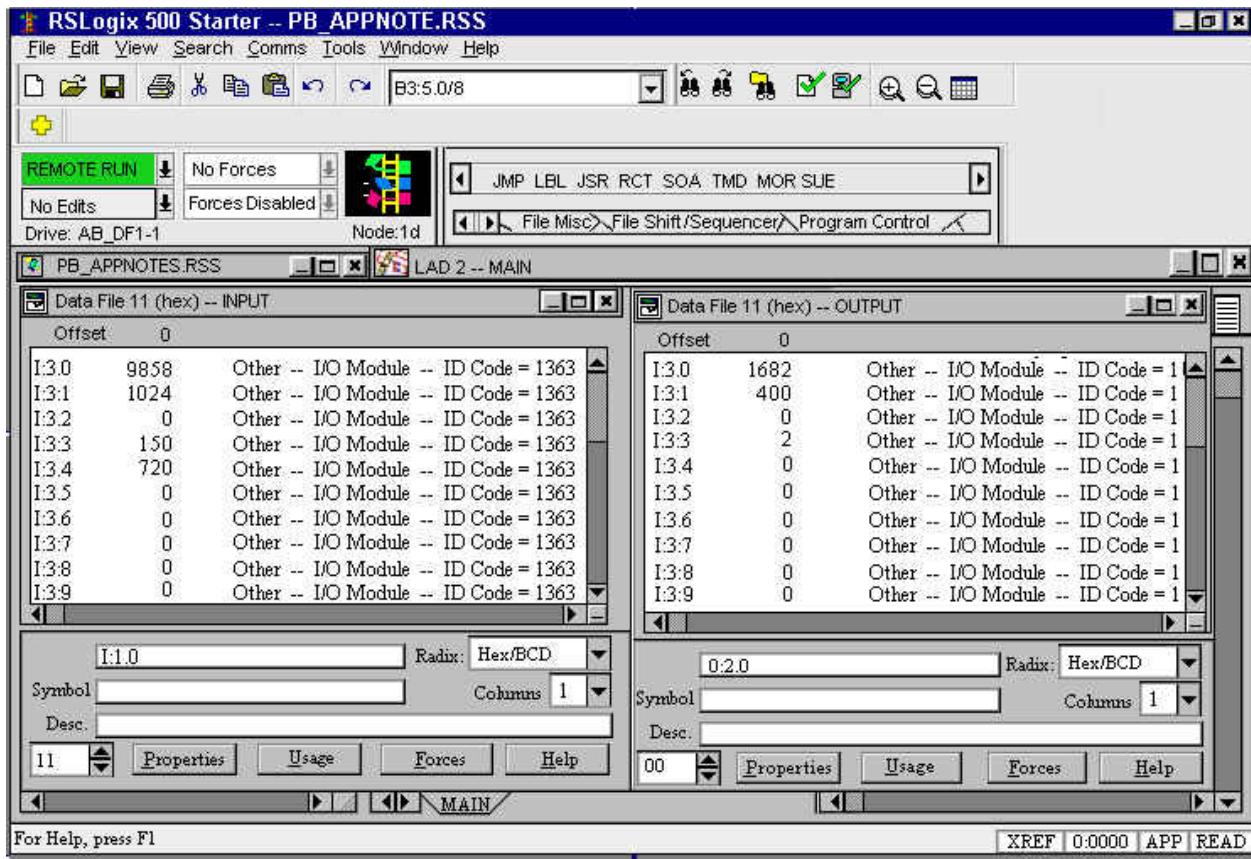
Read Data via Parameter Object Channel Screen 2



Read Data via Parameter Object Channel Screen 3



Read Data via Parameter Object Channel Screen 4



Read Data via Parameter Object Channel Screen 5

