Drive^{IT} Low Voltage AC Drives

Embedded Fieldbus (EFB) Control

Modbus®, Metasys® N2, APOGEE® FLN and BACnet® Protocols for ACH550-01/02/U1/U2 Drives

ACH550 Drive Manuals

GENERAL MANUALS

ACH550-01/UH User's Manual (0.75…90 kW) / (1…150 HP)

- Safety
- Installation
- Start-Up
- Diagnostics
- Maintenance
- Technical Data

ACH550-02/U2 User's Manual (110…355 kW) / (150…550 HP)

- Safety
- Installation
- Start-Up
- Diagnostics
- Maintenance
- Technical Data

ACH550 Technical Reference Manual

- Detailed Product Description
  - Technical product description including dimensional drawings
  - Cabinet mounting information including power losses
  - Software and control including complete parameter descriptions
  - User interfaces and control connections
  - Complete options descriptions
  - Spare parts
  - Etc.
- Practical Engineering Guides
  - PID & PFA engineering guides
  - Dimensioning and sizing guidelines
  - Diagnostics and maintenance information
  - Etc.

OPTION MANUALS

(Fieldbus Adapters, I/O Extension Modules etc., manuals delivered with optional equipment)

Relay Output Extension Module (typical title)

- Installation
- Programming
- Fault tracing
- Technical data

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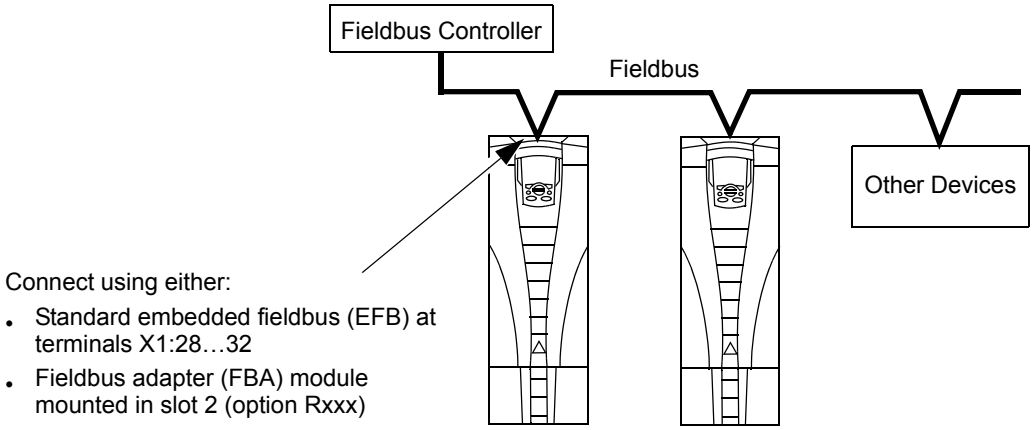
Embedded Fieldbus

Overview

The ACH550 can be set up to accept control from an external system using standard serial communication protocols. When using serial communication, the ACH550 can either:

- Receive all of its control information from the fieldbus, or
- Be controlled from some combination of fieldbus control and other available control locations, such as digital or analog inputs, and the control panel.



Two basic serial communications configurations are available:

- Embedded fieldbus (EFB) – Using the RS485 interface at terminals X1:28…32 on the control board, a control system can communicate with the drive using the Modbus® protocol. (For protocol and profile descriptions, see "Modbus Protocol Technical Data", "ABB Control Profiles Technical Data", etc. starting on page 18.):
  - Modbus®
  - Metasys® N2
  - APOGEE® FLN
  - BACnet®
- Fieldbus adapter (FBA) – See *ACH550 User's Manual*.

Control Interface

In general, the basic control interface between the fieldbus system and the drive consists of:

Protocol	Control Interface	Reference for more information
Modbus	• Output Words – Control word – Reference1 – Reference2 • Input Words – Status word – Actual value 1 – Actual value 2 – Actual value 3 – Actual value 4 – Actual value 5 – Actual value 6 – Actual value 7 – Actual value 8	The content of these words is defined by profiles. For details on the profiles used, see "ABB Control Profiles Technical Data"
N2	• Binary output objects • Analog output objects • Binary input objects • Analog input objects	"N2 Protocol Technical Data"
FLN	• Binary output points • Analog output points • Binary input points • Analog input points	"FLN Protocol Technical Data"
BACnet	• Device management • Binary output objects • Analog output objects • Binary input objects • Analog input objects	"BACnet Technical Data"

Note! The words “output” and “input” are used as seen from the fieldbus controller point of view. For example an output describes data flow from the fieldbus controller to the drive and appears as an input from the drive point of view.

Planning

Network planning should address the following questions:

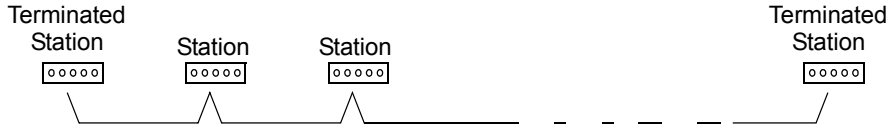
- What types and quantities of devices must be connected to the network?
- What control information must be sent down to the drives?
- What feedback information must be sent from the drives to the controlling system?

Mechanical and Electrical Installation – EFB

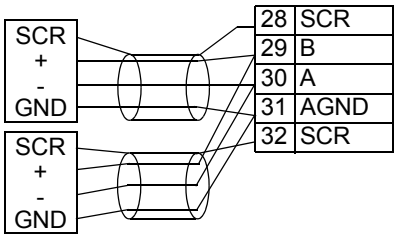
Warning! Connections should be made only while the drive is disconnected from the power source.

Drive terminals 28...32 are for RS485 communications.

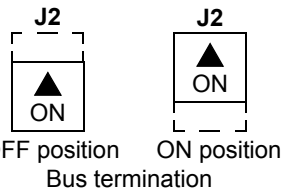
- Use Belden 9842 or equivalent. Belden 9842 is a dual twisted, shielded pair cable with a wave impedance of 120 Ω.
- Use one of these twisted shielded pairs for the RS485 link. Use this pair to connect all A (-) terminals together and all B (+) terminals together.
- Use one of the wires in the other pair for the logical ground (terminal 31), leaving one wire unused.
- Do not directly ground the RS485 network at any point. Ground all devices on the network using their corresponding earthing terminals.
- As always, the grounding wires should not form any closed loops, and all the devices should be earthed to a common ground.
- Connect the RS485 link in a daisy-chained bus, without dropout lines.
- To reduce noise on the network, terminate the RS485 network using 120 Ω resistors at both ends of the network. Use the DIP switch to connect or disconnect the termination resistors. See following diagram and table.



X1	Identification	Hardware Description
28	Screen	RS485 Multidrop application
29	B (Positive +)	
30	A (Negative -)	
31	AGND	
32	Screen	



RS485 interface



- Connect the shield at each end of the cable to a drive. On one end, connect the shield to terminal 28, and on the other end connect to terminal 32. Do not connect the incoming and outgoing cable shields to the same terminals, as that would make the shielding continuous.
- For configuration information see the following:
  - "Communication Set-up – EFB" below.
  - "Activate Drive Control Functions – EFB" on page 9.
  - The appropriate EFB protocol specific technical data. For example, "Modbus Protocol Technical Data" on page 18.

Communication Set-up – EFB

Serial Communication Selection

To activate the serial communication, set parameter 9802 COMM PROTOCOL SEL =

- 1 (STD MODBUS).
- 2 (N2)
- 3 (FLN)
- 5 (BACNET)

Note! If you cannot see the desired selection on the panel, your drive does not have that protocol software in the application memory.

Serial Communication Configuration

Setting 9802 automatically sets the appropriate default values in parameters that define the communication process. These parameters and descriptions are defined below. In particular, note that the station Id may require adjustment.

Code	Description	EFB Protocol Reference			
		Modbus	**N2**	**FLN**	**BACnet**
5301	EFB PROTOCOL ID Contains the identification and program revision of the protocol.	Do not edit. Any non-zero value entered for parameter 9802 COMM PROT SEL, sets this parameter automatically. The format is: XXYY, where xx = protocol ID, and YY = program revision.			
5302	EFB STATION ID Defines the node address of the RS485 link.	Set each drive on the network with a unique value for this parameter. When this protocol is selected, the default value for this parameter is: 1 **Note:** For a new address to take affect, the drive power must be cycled **OR** 5302 must first be set to 0 before selecting a new address. Leaving 5302 = 0 places the RS485 channel in reset, disabling communication.			Sets MS/TP MAC ID
5303	EFB BAUD RATE Defines the communication speed of the RS485 link in kbits per second (kbits/s). 1.2 kbits/s 2.4 kbits/s 4.8 kbits/s 9.6 kbits/s 19.2 kbits/s 38.4 kbits/s 57.6 kbits/s 76.8 kbits/s	When this protocol is selected, the default value for this parameter is: 9.6			When this protocol is selected, the default value for this parameter is: 9600. Do not edit.

Code	Description	EFB Protocol Reference			
		Modbus	N2	FLN	BACnet
5304	EFB PARITY Defines the data length, parity and stop bits to be used with the RS485 link communication. • The same settings must be used in all on-line stations. 0 = 8N1 – 8 data bits, No parity, one stop bit. 1 = 8N2 – 8 data bits, No parity, two stop bits. 2 = 8E1 – 8 data bits, Even parity, one stop bit. 3 = 8O1 – 8 data bits, Odd parity, one stop bit.	When this protocol is selected, the default value for this parameter is: 1	When this protocol is selected, the default value for this parameter is: 0		Sets MS/TP character format.
5305	EFB CTRL PROFILE Selects the communication profile used by the EFB protocol. 0 = ABB DRV LIM – Operation of Control/Status Words conform to ABB Drives Profile, as used in ACH400. 1 = DCU PROFILE – Operation of Control/Status Words conform to 32-bit DCU Profile. 2 = ABB DRV FULL – Operation of Control/Status Words conform to ABB Drives Profile, as used in ACH600/800.	When this protocol is selected, the default value for this parameter is: 0	N/A. When this protocol is selected, the default value for this parameter is: 0. Changing the value for this parameter has no affect on this protocol's behavior.		
5310	EFB PAR10	Not used for Comm setup.	Sets them response turnaround time in milliseconds. When this protocol is selected, the default value is:		
			3 msec.	0 msec.	5 msec.
5314	EFB PAR14		Not used.		Enables autobaud detection. 0 = DISABLE 1 = ENABLE
5315	EFB PAR15				Displays the detected baud rate when autobaud detection is used.

Note! After any changes to the communication settings, protocol must be reactivated by either cycling the drive power, or by clearing and then restoring the station Id (5302).

Activate Drive Control Functions – EFB

Controlling the Drive

Fieldbus control of various drive functions requires configuration to:

- Tell the drive to accept fieldbus control of the function.
- Define as a fieldbus input, any drive data required for control.
- Define as a fieldbus output, any control data required by the drive.

The following sections describe, at a general level, the configuration required for each control function. For the protocol-specific details, see the document supplied with the FBA module.

Start/Stop Direction Control

Using the fieldbus for start/stop/direction control of the drive requires:

- Drive parameter values set as defined below.
- Fieldbus controller supplied command(s) in the appropriate location. (The location is defined by the Protocol Reference, which is protocol dependent.)

Drive Parameter		Value	Description	Protocol Reference				
				Modbus[1]		N2	FLN	BACnet
				ABB DRV	DCU PROFILE			
1001	EXT1 COMMANDS	10 (COMM)	Start/Stop by fieldbus with Ext1 selected.	40001 bits 0…3	40031 bits 0, 1	BO1	24	BV10
1002	EXT2 COMMANDS	10 (COMM)	Start/Stop by fieldbus with Ext2 selected.	40001 bits 0…3	40031 bits 0, 1	BO1	24	BV10
1003	DIRECTION	3 (REQUEST)	Direction by fieldbus.	4002/ 4003[2]	40031 bit 3	BO2	22	BV11

1. For Modbus, the protocol reference can depend on the profile used, hence two columns in these tables. One column refers to the ABB Drives profile, selected when parameter 5305 = 0 (ABB DRV LIM) or 5305 = 2 (ABB DRV FULL). The other column refers to the DCU profile selected when parameter 5305 = 1 (DCU PROFILE). See "ABB Control Profiles Technical Data" on page 26.
2. The reference provides direction control – a negative reference provides reverse rotation.

Input Reference Select

Using the fieldbus to provide input references to the drive requires:

- Drive parameter values set as defined below.
- Fieldbus controller supplied reference word(s) in the appropriate location. (The location is defined by the Protocol Reference, which is protocol dependent.)

Drive Parameter		Value	Setting	Protocol Reference				
				Modbus		N2	FLN	BACnet
				ABB DRV	DCU PROFILE			
1102	EXT1/EXT2 SEL	8 (COMM)	Reference set selection by fieldbus.	40001 bit 11	40031 bit 5	BO5	26	BV13
1103	REF1 SEL	8 (COMM)	Input reference 1 by fieldbus.	40002		AO1	60	AV16
1106	REF2 SEL	8 (COMM)	Input reference 2 by fieldbus.	40003		AO2	61	AV17

Reference Scaling

Where required, REFERENCES can be scaled. See the following, as appropriate:

- Modbus Register "40002" in the "Modbus Protocol Technical Data" section.
- "Reference Scaling" in the "ABB Control Profiles Technical Data" section.
- "N2 Analog Output Objects" in the "N2 Protocol Technical Data" section.
- The slope of points 60 and 61 in the "FLN Protocol Technical Data" section.

Miscellaneous Drive Control

Using the fieldbus for miscellaneous drive control requires:

- Drive parameter values set as defined below.
- Fieldbus controller supplied reference word(s) in the appropriate location. (The location is defined by the Protocol Reference, which is protocol dependent.)

Drive Parameter		Value	Setting	Protocol Reference				
				Modbus		N2	FLN	BACnet
				ABB DRV	DCU PROFILE			
1601	RUN ENABLE	7 (COMM)	Run enable by fieldbus.	40001 bit 3	40031 bit 6 (inverted)	BO4	35	BV12
1604	FAULT RESET SEL	8 (COMM)	Fault reset by fieldbus.	40001 bit 7	40031 bit 4	BO6	94	BV14
1606	LOCAL LOCK	8 (COMM)	Source for local lock selection is the fieldbus.	Does not apply	40031 bit 14			
1607	PARAM SAVE	1 (SAVE)	Saves altered parameters to memory (then value returns to 0).	41607	40032 bit 2	BO18	N/A[1]	
1608	START ENABLE 1	7 (COMM)	Source for start enable 1 is the fieldbus Command word.	Does not apply.	40032 bit 2			BV20
1609	START ENABLE 2	7 (COMM)	Source for start enable 2 is the fieldbus Command word.		40032 bit 3			BV21
2013	MIN TORQUE SEL	7 (COMM)	Source for minimum torque selection is the fieldbus.		40031 bit 15			
2014	MAX TORQUE SEL	7 (COMM)	Source for maximum torque selection is the fieldbus.					
2201	ACC/DEC 1/2 SEL	7 (COMM)	Source for ramp pair selection is the fieldbus.		40031 bit 10			

1. Use Memorize Point command.

Relay Output Control

Using the fieldbus for relay output control requires:

- Drive parameter values set as defined below.
- Fieldbus controller supplied reference word(s) in the appropriate location. (The location is defined by the Protocol Reference, which is protocol dependent.)

Drive Parameter		Value	Setting	Protocol Reference				
				Modbus		N2	FLN	BACnet
				ABB DRV	DCU PROFILE			
1401	RELAY OUTPUT 1	35 (COMM)	Relay Output 1 controlled by fieldbus.	40134 bit 0 or 00033		BO7	40	BO0
1402	RELAY OUTPUT 2	35 (COMM)	Relay Output 2 controlled by fieldbus.	40134 bit 1 or 00034		BO8	41	BO1
1403	RELAY OUTPUT 3	35 (COMM)	Relay Output 3 controlled by fieldbus.	40134 bit 2 or 00035		BO9	42	BO2
1410[1]	RELAY OUTPUT 4	35 (COMM)	Relay Output 4 controlled by fieldbus.	40134 bit 3 or 00036		BO10	43	BO3
1411[1]	RELAY OUTPUT 5	35 (COMM)	Relay Output 5 controlled by fieldbus.	40134 bit 4 or 00037		BO11	44	BO4
1412[1]	RELAY OUTPUT 6	35 (COMM)	Relay Output 6 controlled by fieldbus.	40134 bit 5 or 00038		BO12	45	BO5

1. More than 3 relays requires the addition of a relay extension module.

For example: To control relays 1 and 2 using serial communication:
Set parameters 1401 RELAY OUTPUT 1 and 1402 RELAY OUTPUT 1 = 35 (COMM).

Then, for example using N2:

- To turn Relay 1 On: Force object B07 to On.
- To turn Relay 2 On: Force object B08 to On.
- To turn both Relay 1 and 2 On: Force objects B07 and B08 On.

Note! Relay status feedback occurs without configuration as defined below.

Drive Parameter		Value	Setting	Protocol Reference				
				Modbus		N2	FLN	BACnet
				ABB DRV	DCU PROFILE			
0122	RO 1-3 STATUS	Relay 1…3 status.	40122	0122		BI4… BI6	76… 78	BI0… BI2
0123	RO 4-6 STATUS	Relay 4…6 status.	40123	0123		BI7… BI9	79… 81	BI3… BI5

Analog Output Control

Using the fieldbus for analog output control requires:

- Drive parameter values set as defined below.
- Fieldbus controller supplied reference word(s) in the appropriate location. (The location is defined by the Protocol Reference, which is protocol dependent.)

Drive Parameter		Value	Setting	Protocol Reference				
				Modbus		N2	FLN	BACnet
				ABB DRV	DCU PROFILE			
1501	AO1 CONTENT SEL	135 (COMM VALUE 1)	Analog Output 1 controlled by writing to parameter 0135.	–		–	–	–
0135	COMM VALUE 1	–		40135		AO14	46	AO0
1507	AO2 CONTENT SEL	136 (COMM VALUE 2)	Analog Output 2 controlled by writing to parameter 0136.	–		–	–	–
0136	COMM VALUE 2	–		40136		AO15	47	AO1

PID Control Setpoint Source

Use the following settings to select the fieldbus as the setpoint source for PID loops:

Drive Parameter		Value	Setting	Protocol Reference				
				Modbus		N2	FLN	BACnet
				ABB DRV	DCU PROFILE			
4010	SET POINT SEL (Set 1)	8 (COMM VALUE 1) 9 (COMM + AI1) 10 (COMM*AI1)	Setpoint is either: • Input Reference 2 (+/-/* AI1). Control requires parameter 1106 value = comm. • Process PID setpoint. Control requires parameter 1106 value = pid1 out and parameter 4010 value = comm.	40003		AO2	61	AV17
4110	SET POINT SEL (Set 2)							
4210	SET POINT SEL (Ext/ Trim)							

Communication Fault

When using fieldbus control, specify the drive's action if serial communication is lost.

Drive Parameter		Value	Description
3018	COMM FAULT FUNC	0 (NOT SEL) 1 (FAULT) 2 (CONST SP7) 3 (LAST SPEED)	Set for appropriate drive response.
3019	COMM FAULT TIME	Set time delay before acting on a communication loss.	

Feedback from the Drive – EFB

Pre-defined Feedback

Inputs to the controller (drive outputs) have pre-defined meanings established by the protocol. This feedback does not require drive configuration. The following table lists a sample of feedback data. For a complete listing, see input word/point/object listings in the technical data for the appropriate protocol starting on page 18.

Drive Parameter		Protocol Reference			
		Modbus	N2	FLN	BACnet
0102	SPEED	40102	AI3	5	AV0
0103	FREQ OUTPUT	40103	AI1	2	AV1
0104	CURRENT	40104	AI4	6	AV4
0105	TORQUE	40105	AI5	7	AV5
0106	POWER	40106	AI6	8	AV6
0107	DC BUS VOLT	40107	AI11	13	AV2
0109	OUTPUT VOLTAGE	40109	AI12	14	AV3
0115	KWH COUNTER	40115	AI8	10	AV8
0118	DI1-3 STATUS – bit 1 (DI3)	40118	BI12	72	BI6, BI7, BI8
0122	RO1-3 STATUS	40122	BI4, BI5, BI6	76, 77, 78	BI0, BI1, BI2
0301	FB STATUS WORD – bit 0 (STOP)	40301 bit 0	BI1	23	BV0
0301	FB STATUS WORD – bit 2 (REV)	40301 bit 2	BI2	21	BV1

Note! With Modbus, any parameter can be accessed using the format: 4 followed by the parameter number.

Mailbox Read/Write

The ACH550 provides a “Mailbox” function to access parameters that have not been pre-defined by the protocol. Using mailbox, any drive parameter can be identified and read. Mailbox can also be used to adjust parameter settings by writing a value to any parameter identified. The following table describes the use of this function.

Name	Description	Protocol Reference			
		Modbus[1]	N2	FLN	BACnet
Mailbox Parameter	Enter the number of the drive parameter to access.	Does not apply.	AO19	95	AV25
Mailbox Data	Contains the parameter value after a read, or enter the desired parameter value for a write.		AO20	96	AV26
Mailbox Read	A binary value triggers a read – the value of the “Mailbox Parameter” appears in “Mailbox data”.		BO19	97	BV15
Mailbox Write	A binary value triggers a write – the drive value for the “Mailbox Parameter” changes to the value in “Mailbox data”.		BO20	98	BV16

1. As noted above, Modbus provides direct access to all parameters using the format: 4 followed by the parameter number.

Actual Value Scaling

The scaling of actual values can be protocol dependent. In general, for Actual Values, scale the feedback integer using the parameter's resolution. (See "Parameter Descriptions" section in *ACH550 User's Manual* for parameter resolutions.) For example:

Feedback Integer	Parameter Resolution	(Feedback Integer) * (Parameter Resolution) = Scaled Value
1	0.1 mA	1 * 0.1 mA = 0.1 mA
10	0.1%	10 * 0.1% = 1%

Where parameters are in percent, the "Parameter Descriptions" section specifies what parameter corresponds to 100%. In such cases, to convert from percent to engineering units, multiply by the value of the parameter that defines 100% and divide by 100%. For example:

Feedback Integer	Parameter Resolution	Value of the Parameter that defines 100%	(Feedback Integer) * (Parameter Resolution) * (Value of 100% Ref.) / 100% = Scaled Value
10	0.1%	1500 rpm[1]	10 * 0.1% * 1500 RPM / 100% = 15 rpm
100	0.1%	500 Hz[2]	100 * 0.1% * 500 Hz / 100% = 50 Hz

1. Assuming, for the sake of this example, that the Actual Value uses parameter 9908 MOT NOM SPEED as the 100% reference, and that 9908 = 1500 rpm.
2. Assuming, for the sake of this example, that the Actual Value uses parameter 9907 MOT NOM FREQ as the 100% reference, and that 9907 = 500 Hz.

Although Actual Value scaling could differ from the above for the N2 and FLN protocols, it currently does not. To confirm, see the following sections, as appropriate:

- "N2 Analog Input Objects" in the "N2 Protocol Technical Data" section.
- "Scaling Drive Feedback Values" in the "FLN Protocol Technical Data" section.

Scaling does not apply for the BACnet protocol.

Diagnostics – EFB

Fault Queue for Drive Diagnostics

For general ACH550 diagnostics information, see "Diagnostics" section in *ACH550 User's Manual*. The three most recent ACH550 faults are reported to the fieldbus as defined below.

Drive Parameter		Protocol Reference			
		Modbus	**N2**	**FLN**	**BACnet[1]**
0401	Last Fault	40401	17	90	AV18
0412	Previous Fault 1	40402	18	91	AV19
0413	Previous Fault 2	40403	19	92	AV20

Serial Communication Diagnostics

Network problems can be caused by multiple sources. Some of these sources are:

- Loose connections
- Incorrect wiring (including swapped wires)
- Bad grounding
- Duplicate station numbers
- Incorrect setup of drives or other devices on the network

The major diagnostic features for fault tracing on an EFB network include Group 53 EFB Protocol parameters 5306…5309. The "Parameter Descriptions" section in *ACH550 User's Manual* describes these parameters in detail.

Diagnostic Situations

The sub-sections below describe various diagnostic situations – the problem symptoms and corrective actions.

Normal Operation

During normal network operation, 5306…5309 parameter values act as follows at each drive:

- 5306 EFB OK MESSAGES advances (advances for each message properly received and addressed to this drive).
- 5307 EFB CRC ERRORS does not advance at all (advances when an invalid message CRC is received).
- 5308 EFB UART ERRORS does not advance at all (advances when character format errors are detected, such as parity or framing errors).
- 5309 EFB status value varies depending on network traffic.

Loss of Communication

The ACH550 behavior, if communication is lost, was configured in "Communication Fault". The parameters are 3018 COMM FAULT FUNC and 3019 COMM FAULT TIME.

The "Parameter Descriptions" section in *ACH550 User's Manual* describes these parameters in detail.

No Master Station on Line

If no master station is on line: Neither the EFB OK MESSAGES nor the errors (5307 EFB CRC ERRORS and 5308 EFB UART ERRORS) increase on any of the stations.

To correct:

- Check that a network master is connected and properly programmed on the network.
- Verify that the cable is connected, and is not cut or short circuited.

Duplicate Stations

If two or more stations have duplicate numbers:

- Two or more drives cannot be addressed.
- Every time there is a read or write to one particular station, the value for 5307 EFB CRC ERRORS or 5308 EFB UART ERRORS advances.

To correct: Check all station numbers and edit conflicting values.

Swapped Wires

If the communication wires are swapped (terminal A on one drive is connected to terminal B on another):

- The value of 5306 EFB OK MESSAGES does not advance.
- The values of 5307 EFB CRC ERRORS and 5308 EFB UART ERRORS are advancing.

To correct: Check that the RS-485 lines are not swapped.

Fault 28 – Serial 1 Err

If the drive's control panel shows fault code 28 "SERIAL 1 ERR", check for either of the following:

- The master system is down. To correct, resolve problem with master system.
- The communication connection is bad. To correct, check communication connection at the drive.
- The time-out selection for the drive is too short for the given installation. The master is not polling the drive within the specified time-out delay. To correct, increase the time set by parameter 3019 COMM FAULT TIME.

Faults 31…33 – EFB1…EFB3

The three EFB fault codes listed for the drive in "Diagnostics" section of *ACH550 User's Manual* (fault codes 31…33) are not used.

Intermittent Off-line Occurrences

The problems described above are the most common problems encountered with ACH550 serial communication. Intermittent problems might also be caused by:

- Marginally loose connections,
- Wear on wires caused by equipment vibrations,

- Insufficient grounding and shielding on both the devices and on the communication cables.

Modbus Protocol Technical Data

Overview

The Modbus® protocol was introduced by Modicon, Inc. for use in control environments featuring Modicon programmable controllers. Due to its ease of use and implementation, this common PLC language was quickly adopted as a de-facto standard for integration of a wide variety of master controllers and slave devices.

Modbus is a serial, asynchronous protocol. Transactions are half-duplex, featuring a single Master controlling one or more Slaves. While RS232 can be used for point-to-point communication between a single Master and a single Slave, a more common implementation features a multi-drop RS485 network with a single Master controlling multiple Slaves. The ACH550 features RS485 for its Modbus physical interface.

RTU

The Modbus specification defines two distinct transmission modes: ASCII and RTU. The ACH550 supports RTU only.

Feature Summary

The following Modbus function codes are supported by the ACH550.

Function	Code (Hex)	Description
Read Coil Status	0x01	Read discrete output status. For the ACH550, the individual bits of the control word are mapped to Coils 1…16. Relay outputs are mapped sequentially beginning with Coil 33 (e.g. RO1=Coil 33).
Read Discrete Input Status	0x02	Read discrete inputs status. For the ACH550, the individual bits of the status word are mapped to Inputs 1…16 or 1…32, depending on the active profile. Terminal inputs are mapped sequentially beginning with Input 33 (e.g. DI1=Input 33).
Read Multiple Holding Registers	0x03	Read multiple holding registers. For the ACH550, the entire parameter set is mapped as holding registers, as well as command, status and reference values.
Read Multiple Input Registers	0x04	Read multiple input registers. For the ACH550, the 2 analog input channels are mapped as input registers 1 & 2.
Force Single Coil	0x05	Write a single discrete output. For the ACH550, the individual bits of the control word are mapped to Coils 1…16. Relay outputs are mapped sequentially beginning with Coil 33 (e.g. RO1=Coil 33).
Write Single Holding Register	0x06	Write single holding register. For the ACH550, the entire parameter set is mapped as holding registers, as well as command, status and reference values.
Diagnostics	0x08	Perform Modbus diagnostics. Subcodes for Query (0x00), Restart (0x01) & Listen Only (0x04) are supported.
Force Multiple Coils	0x0F	Write multiple discrete outputs. For the ACH550, the individual bits of the control word are mapped to Coils 1…16. Relay outputs are mapped sequentially beginning with Coil 33 (e.g. RO1=Coil 33).
Write Multiple Holding Registers	0x10	Write multiple holding registers. For the ACH550, the entire parameter set is mapped as holding registers, as well as command, status and reference values.

Function	Code (Hex)	Description
Read/Write Multiple Holding Registers	0x17	This function combines functions 0x03 and 0x10 into a single command.

Mapping Summary

The following table summarizes the mapping between the ACH550 (parameters and I/0) and Modbus reference space. For details, see "Modbus Addressing" below.

ACH550	Modbus Reference	Supported Function Codes
• Control Bits • Relay Outputs	Coils(0xxxx)	• 01 – Read Coil Status • 05 – Force Single Coil • 15 – Force Multiple Coils
• Status Bits • Discrete Inputs	Discrete Inputs(1xxxx)	• 02 – Read Input Status
• Analog Inputs	Input Registers(3xxxxx)	• 04 – Read Input Registers
• Parameters • Control/Status Words • References	Holding Registers(4xxxx)	• 03 – Read 4X Registers • 06 – Preset Single 4X Register • 16 – Preset Multiple 4X Registers • 23 – Read/Write 4X Registers

Communication Profiles

When communicating by Modbus, the ACH550 supports multiple profiles for control and status information. Parameter 5305 (EFB CTRL PROFILE) selects the profile used.

- ABB DRV LIM – The primary (and default) profile is the ABB DRV LIM profile, which standardizes the control interface with ACH400 drives. This profile is based on the PROFIBUS interface, and is discussed in detail in the following sections.
- DCU PROFILE – Another profile is called the DCU PROFILE profile. It extends the control and status interface to 32 bits, and is the internal interface between the main drive application and the embedded fieldbus environment.
- ABB DRV FULL – This profile standardizes the control interface with ACH600 and ACS800 drives. This profile is also based on the PROFIBUS interface, and supports two control word bits not supported by the ABB DRV LIM profile.

Modbus Addressing

With Modbus, each function code implies access to a specific Modbus reference set. Thus, the leading digit is not included in the address field of a Modbus message.

Note: The ACH550 supports the zero-based addressing of the Modbus specification. Holding register 40002 is addressed as 0001 in a Modbus message. Similarly, coil 33 is addressed as 0032 in a Modbus message.

Refer again to the "Mapping Summary" above. The following sections describe, in detail, the mapping to each Modbus reference set.

0xxxx Mapping – Modbus Coils. The drive maps the following information to the 0xxxx Modbus set called Modbus Coils:

- Bit-wise map of the CONTROL WORD (selected using parameter 5305 EFB CTRL PROFILE). The first 32 coils are reserved for this purpose.
- Relay output states, numbered sequentially beginning with coil 00033.

The following table summarizes the 0xxxx reference set:

Modbus Ref.	**Internal Location (All Profiles)**	ABB DRV LIM **(5305 = 0)**	DCU PROFILE **(5305 = 1)**	ABB DRV FULL **(5305 = 2)**
00001	CONTROL WORD – Bit 0	OFF1*	STOP	OFF1*
00002	CONTROL WORD – Bit 1	OFF2*	START	OFF2*
00003	CONTROL WORD – Bit 2	OFF3*	REVERSE	OFF3*
00004	CONTROL WORD – Bit 3	START	LOCAL	START
00005	CONTROL WORD – Bit 4	N/A	RESET	RAMP_OUT_ZERO*
00006	CONTROL WORD – Bit 5	RAMP_HOLD*	EXT2	RAMP_HOLD*
00007	CONTROL WORD – Bit 6	RAMP_IN_ZERO*	RUN_DISABLE	RAMP_IN_ZERO*
00008	CONTROL WORD – Bit 7	RESET	STPMODE_R	RESET
00009	CONTROL WORD – Bit 8	N/A	STPMODE_EM	N/A
00010	CONTROL WORD – Bit 9	N/A	STPMODE_C	N/A
00011	CONTROL WORD – Bit 10	N/A	RAMP_2	REMOTE_CMD*
00012	CONTROL WORD – Bit 11	EXT2	RAMP_OUT_0	EXT2
00013	CONTROL WORD – Bit 12	N/A	RAMP_HOLD	N/A
00014	CONTROL WORD – Bit 13	N/A	RAMP_IN_0	N/A
00015	CONTROL WORD – Bit 14	N/A	REQ_LOCALLOCK	N/A
00016	CONTROL WORD – Bit 15	N/A	TORQLIM2	N/A
00017	CONTROL WORD – Bit 16	Does not apply	FBLOCAL_CTL	Does not apply
00018	CONTROL WORD – Bit 17		FBLOCAL_REF	
00019	CONTROL WORD – Bit 18		START_DISABLE1	
00020	CONTROL WORD – Bit 19		START_DISABLE2	
00021… **0**0032	Reserved	Reserved	Reserved	Reserved
00033	RELAY OUTPUT 1	Relay Output 1	Relay Output 1	Relay Output 1
00034	RELAY OUTPUT 2	Relay Output 2	Relay Output 2	Relay Output 2
00035	RELAY OUTPUT 3	Relay Output 3	Relay Output 3	Relay Output 3
00036	RELAY OUTPUT 4	Relay Output 4	Relay Output 4	Relay Output 4
00037	RELAY OUTPUT 5	Relay Output 5	Relay Output 5	Relay Output 5
00038	RELAY OUTPUT 6	Relay Output 6	Relay Output 6	Relay Output 6

* = Active low

For the 0xxxx registers:

- Status is always readable.
- Forcing is allowed by user configuration of the drive for fieldbus control.
- Additional relay outputs are added sequentially.

The ACH550 supports the following Modbus function codes for coils:

Function Code	Description
01	Read coil status
05	Force single coil
15 (0x0F Hex)	Force multiple coils

1xxxx Mapping – Modbus Discrete Inputs. The drive maps the following information to the 1xxxx Modbus set called Modbus Discrete Inputs:

- Bit-wise map of the STATUS WORD (selected using parameter 5305 EFB CTRL PROFILE). The first 32 inputs are reserved for this purpose.
- Discrete hardware inputs, numbered sequentially beginning with input 33.

The following table summarizes the 1xxxx reference set:

Modbus Ref.	Internal Location (All Profiles)	ABB DRV (5305 = 0 or 2)	DCU PROFILE (5305 = 1)
10001	STATUS WORD – Bit 0	RDY_ON	READY
10002	STATUS WORD – Bit 1	RDY_RUN	ENABLED
10003	STATUS WORD – Bit 2	RDY_REF	STARTED
10004	STATUS WORD – Bit 3	TRIPPED	RUNNING
10005	STATUS WORD – Bit 4	OFF_2_STA*	ZERO_SPEED
10006	STATUS WORD – Bit 5	OFF_3_STA*	ACCELERATE
10007	STATUS WORD – Bit 6	SWC_ON_INHIB	DECELERATE
10008	STATUS WORD – Bit 7	ALARM	AT_SETPOINT
10009	STATUS WORD – Bit 8	AT_SETPOINT	LIMIT
10010	STATUS WORD – Bit 9	REMOTE	SUPERVISION
10011	STATUS WORD – Bit 10	ABOVE_LIMIT	REV_REF
10012	STATUS WORD – Bit 11	EXT2	REV_ACT
10013	STATUS WORD – Bit 12	RUN_ENABLE	PANEL_LOCAL
10014	STATUS WORD – Bit 13	N/A	FIELDBUS_LOCAL
10015	STATUS WORD – Bit 14	N/A	EXT2_ACT
10016	STATUS WORD – Bit 15	N/A	FAULT
10017	STATUS WORD – Bit 16	Reserved	ALARM
10018	STATUS WORD – Bit 17	Reserved	REQ_MAINT
10019	STATUS WORD – Bit 18	Reserved	DIRLOCK
10020	STATUS WORD – Bit 19	Reserved	LOCALLOCK
10021	STATUS WORD – Bit 20	Reserved	CTL_MODE
10022	STATUS WORD – Bit 21	Reserved	Reserved
10023	STATUS WORD – Bit 22	Reserved	Reserved
10024	STATUS WORD – Bit 23	Reserved	Reserved
10025	STATUS WORD – Bit 24	Reserved	Reserved
10026	STATUS WORD – Bit 25	Reserved	Reserved
10027	STATUS WORD – Bit 26	Reserved	REQ_CTL

Modbus Ref.	Internal Location (All Profiles)	ABB DRV (5305 = 0 or 2)	DCU PROFILE (5305 = 1)
10028	STATUS WORD – Bit 27	Reserved	REQ_REF1
10029	STATUS WORD – Bit 28	Reserved	REQ_REF2
10030	STATUS WORD – Bit 29	Reserved	REQ_REF2EXT
10031	STATUS WORD – Bit 30	Reserved	ACK_STARTINH
10032	STATUS WORD – Bit 31	Reserved	ACK_OFF_ILCK
10033	DI1	DI1	DI1
10034	DI2	DI2	DI2
10035	DI3	DI3	DI3
10036	DI4	DI4	DI4
10037	DI5	DI5	DI5
10038	DI6	DI6	DI6

* = Active low

For the 1xxxx registers:

- Additional discrete inputs are added sequentially.

The ACH550 supports the following Modbus function codes for discrete inputs:

Function Code	Description
02	Read input status

3xxxx Mapping – Modbus Inputs. The drive maps the following information to the 3xxxx Modbus addresses called Modbus input registers:

- Any user defined analog inputs.

The following table summarizes the input registers:

Modbus Reference	Internal Location (All Profiles)	Remarks
30001	AI1	This register shall report the level of Analog Input 1 (0…100%).
30002	AI2	This register shall report the level of Analog Input 2 (0…100%).

The ACH550 supports the following Modbus function codes for 3xxxx registers:

Function Code	Description
04	Read 3xxxx input status

4xxxx Register Mapping. The drive maps its parameters and other data to the 4xxxx holding registers as follows:

- 40001…40099 map to drive control and actual values. These registers are described in the table below.
- 40101…49999 map to drive parameters 0101…9999. Register addresses that do not correspond to drive parameters are invalid. If there is an attempt to read or write outside the parameter addresses, the Modbus interface returns an exception code to the controller.

The following table summarizes the 4xxxx drive control registers 40001…40099 (for 4xxxx registers above 40099, see the drive parameter list, e.g. 40102 is parameter 0102):

Modbus Register		Access	Remarks
40001	CONTROL WORD	R/W	Maps directly to the profile'S CONTROL WORD. Supported only if 5305 = 0 or 2 (ABB Drives profile). Parameter 5319 holds a copy in hex format.
40002	Reference 1	R/W	Range = 0…+20000 (scaled to 0…1105 REF1 MAX), or -20000…0 (scaled to 1105 REF1 MAX…0).
40003	Reference 2	R/W	Range = 0…+10000 (scaled to 0…1108 REF2 MAX), or -10000…0 (scaled to 1108 REF2 MAX…0).
40004	STATUS WORD	R	Maps directly to the profile'S STATUS WORD. Supported only if 5305 = 0 or 2 (ABB Drives profile). Parameter 5320 holds a copy in hex format.
40005	Actual 1 (select using 5310)	R	By default, stores a copy of 0103 OUTPUT FREQ. Use parameter 5310 to select a different actual value for this register.
40006	Actual 2 (select using 5311)	R	By default, stores a copy of 0104 CURRENT. Use parameter 5311 to select a different actual value for this register.
40007	Actual 3 (select using 5312)	R	By default, stores nothing. Use parameter 5312 to select an actual value for this register.
40008	Actual 4 (select by 5313)	R	By default, stores nothing. Use parameter 5313 to select an actual value for this register.
40009	Actual 5 (select using 5314)	R	By default, stores nothing. Use parameter 5314 to select an actual value for this register.
40010	Actual 6 (select using 5315)	R	By default, stores nothing. Use parameter 5315 to select an actual value for this register.
40011	Actual 7 (select using 5316)	R	By default, stores nothing. Use parameter 5316 to select an actual value for this register.
40012	Actual 8 (select using 5317)	R	By default, stores nothing. Use parameter 5317 to select an actual value for this register.
40031	ACH550 CONTROL WORD LSW	R/W	Maps directly to the Least Significant Word of the DCU profile's CONTROL WORD. Supported only if 5305 = 1. See parameter 0301.
40032	ACH550 CONTROL WORD MSW	R	Maps directly to the Most Significant Word of the DCU profile's CONTROL WORD. Supported only if 5305 = 1. See parameter 0302.
40033	ACH550 STATUS WORD LSW	R	Maps directly to the Least Significant Word of the DCU profile's CONTROL WORD. Supported only if 5305 = 1. See parameter 0303.
40034	ACH550 STATUS WORD MSW	R	Maps directly to the Most Significant Word of the DCU profile's CONTROL WORD. Supported only if 5305 = 1. See parameter 0304.

For the Modbus protocol, drive parameters in group 53 report the parameter mapping to 4xxxx Registers.

Code	Description
5310	EFB PAR 10 Specifies the parameter mapped to Modbus register 40005.
5311	EFB PAR 11 Specifies the parameter mapped to Modbus register 40006.
5312	EFB PAR 12 Specifies the parameter mapped to Modbus register 40007.
5313	EFB PAR 13 Specifies the parameter mapped to Modbus register 40008.
5314	EFB PAR 14 Specifies the parameter mapped to Modbus register 40009.
5315	EFB PAR 15 Specifies the parameter mapped to Modbus register 40010.
5316	EFB PAR 16 Specifies the parameter mapped to Modbus register 40011.
5317	EFB PAR 17 Specifies the parameter mapped to Modbus register 40012.
5318	Reserved.
5319	EFB PAR 19 Holds a copy (in hex) of the CONTROL WORD, Modbus register 40001.
5320	EFB PAR 20 Holds a copy (in hex) of the STATUS WORD, Modbus register 40004.

Except where restricted by the drive, all parameters are available for both reading and writing. The parameter writes are verified for the correct value, and for a valid register addresses.

Note! Parameter writes through standard Modbus are always volatile i.e. modified values are not automatically stored to permanent memory. Use parameter 1607 PARAM. SAVE to save all altered values.

The ACH550 supports the following Modbus function codes for 4xxxx registers:

Function Code	Description
03	Read holding 4xxxx registers
06	Preset single 4xxxx register
16 (0x10 Hex)	Preset multiple 4xxxx registers
23 (0x17 Hex)	Read/write 4xxxx registers

Actual Values

The contents of the register addresses 40005…40012 are ACTUAL VALUES and are:

- Specified using parameters 5310…5317.
- Read-only values containing information on the operation of the drive.
- 16-bit words containing a sign bit and a 15-bit integer.
- When negative values, written as the two's complement of the corresponding positive value.
- Scaled as described earlier in "Actual Value Scaling".

Exception Codes

Exception codes are serial communication responses from the drive. The ACH550 supports the standard Modbus exception codes defined below.

Exception Code	Name	Meaning
01	ILLEGAL FUNCTION	Unsupported Command
02	ILLEGAL DATA ADDRESS	The data address received in the query is not allowable. It is not a defined parameter/group.
03	ILLEGAL DATA VALUE	A value contained in the query data field is not an allowable value for the ACH550, because it is one of the following: • Outside min. or max. limits. • Parameter is read-only. • Message is too long. • Parameter write not allowed when start is active. • Parameter write not allowed when factory macro is selected.

ABB Control Profiles Technical Data

Overview

ABB Drives Profile

The ABB Drives profile provides a standard profile that can be used on multiple protocols, including Modbus and the protocols available on the FBA module. Two implementations of the ABB Drives profile are available:

- ABB DRV FULL – This implementation standardizes the control interface with ACS600 and ACS800 drives.
- ABB DRV LIM – This implementation standardizes the control interface with ACS400 drives. This implementation does not support two control word bits supported by ABB DRV FULL.

Except as noted, the following “ABB Drives Profile” descriptions apply to both implementations.

DCU Profile

The DCU profile extends the control and status interface to 32 bits, and is the internal interface between the main drive application and the embedded fieldbus environment.

Control Word

The CONTROL WORD is the principal means for controlling the drive from a fieldbus system. The fieldbus master station sends the CONTROL WORD to the drive. The drive switches between states according to the bit-coded instructions in the CONTROL WORD. Using the CONTROL WORD (ABB Drives profile version) requires that:

- The drive is in remote (REM) control.
- The serial communication channel is defined as the source for controlling commands (set using parameters 1001 EXT1 COMMANDS, 1002 EXT2 COMMANDS and 1102 EXT1/EXT2 SEL).
- The serial communication channel used is configured to use an ABB control profile. For example, to use the control profile ABB DRV FULL, requires both parameter 9802 COMM PROT SEL = 1 (STD MODBUS), and parameter 5305 EFB CTRL PROFILE = 2 (ABB DRV FULL).

ABB Drives Profile

The following table and the state diagram later in this sub-section describe the CONTROL WORD content for the ABB Drives Profile.

ABB Drives Profile (EFB) CONTROL WORD				
Bit	**Name**	**Value**	**Commanded State**	**Comments**
0	OFF1 CONTROL	1	READY TO OPERATE	Enter READY TO OPERATE
		0	EMERGENCY OFF	Drive ramps to stop according to currently active deceleration ramp (2203 or 2205) Normal command sequence: • Enter OFF1 ACTIVE • Proceed to READY TO SWITCH ON, unless other interlocks (OFF2, OFF3) are active.
1	OFF2 CONTROL	1	OPERATING	Continue operation (OFF2 inactive)
		0	EMERGENCY OFF	Drive coasts to stop. Normal command sequence: • Enter OFF2 ACTIVE • Proceed to SWITCHON INHIBITED
2	OFF3 CONTROL	1	OPERATING	Continue operation (OFF3 inactive)
		0	EMERGENCY STOP	Drive stops within in time specified by parameter 2208. Normal command sequence: • Enter OFF3 ACTIVE • Proceed to SWITCH ON INHIBITED **WARNING! Be sure motor and driven equipment can be stopped using this mode.**
3	INHIBIT OPERATION	1	OPERATION ENABLED	Enter OPERATION ENABLED (Note the Run enable signal must be active. See 1601. If 1601 is set to COMM, this bit also actives the Run Enable signal.)
		0	OPERATION INHIBITED	Inhibit operation. Enter OPERATION INHIBITED
4	Unused (**ABB DRV LIM**)			
	RAMP_OUT_ ZERO (**ABB DRV FULL**)	1	NORMAL OPERATION	Enter RAMP FUNCTION GENERATOR: ACCELERATION ENABLED
		0	RFG OUT ZERO	Force ramp function generator output to Zero. Drive ramps to stop (current and DC voltage limits in force).
5	RAMP_HOLD	1	RFG OUT ENABLED	Enable ramp function. Enter RAMP FUNCTION GENERATOR: ACCELERATOR ENABLED
		0	RFG OUT HOLD	Halt ramping (Ramp Function Generator output held)
6	RAMP_IN_ ZERO	1	RFG INPUT ENABLED	Normal operation. Enter OPERATING
		0	RFG INPUT ZERO	Force Ramp Function Generator input to zero.

ABB Drives Profile (EFB) CONTROL WORD				
Bit	**Name**	**Value**	**Commanded State**	**Comments**
7	RESET	0=>1	RESET	Fault reset if an active fault exists (Enter SWITCH-ON INHIBITED). Effective if 1604 = COMM.
		0	OPERATING	Continue normal operation
8…9	Unused			
10	Unused (**ABB DRV LIM**)			
	REMOTE_CMD (**ABB DRV FULL**)	1		Fieldbus control enabled.
		0		• CW ≠ 0 or Ref ≠ 0: Retain last CW and Ref. • CW = 0 and Ref = 0: Fieldbus control enabled. • Ref and deceleration/acceleration ramp are locked.
11	EXT CTRL LOC	1	EXT2 SELECT	Select external control location 2 (EXT2). Effective if 1102 = COMM.
		0	EXT1 SELECT	Select external control location 1 (EXT1). Effective if 1102 = COMM.
12…15	Unused			

DCU Profile

The following tables describe the CONTROL WORD content for the DCU profile.

DCU Profile CONTROL WORD (See Parameter 0301)				
Bit	**Name**	**Value**	**Command/Req.**	**Comments**
0	STOP	1	Stop	Stops according to either the stop mode parameter or the stop mode requests (bits 7 and 8). Simultaneous STOP and START commands result in a stop command.
		0	(no op)	
1	START	1	Start	
		0	(no op)	
2	REVERSE	1	Reverse direction	This bit XOR'd with the sign of the reference defines direction.
		0	Forward direction	
3	LOCAL	1	Local mode	When the fieldbus sets this bit, it steals control and the drive moves to fieldbus local control mode.
		0	External mode	
4	RESET	-> 1	Reset	Edge sensitive.
		other	(no op)	
5	EXT2	1	Switch to EXT2	
		0	Switch to EXT1	
6	RUN_DISABLE	1	Run disable	Inverted run enable.
		0	Run enable on	
7	STPMODE_R	1	Normal ramp stop mode	
		0	(no op)	

DCU Profile CONTROL WORD (See Parameter 0301)				
Bit	**Name**	**Value**	**Command/Req.**	**Comments**
8	STPMODE_EM	1	Emergency ramp stop mode	
		0	(no op)	
9	STPMODE_C	1	Coast stop mode	
		0	(no op)	
10	RAMP_2	1	Ramp pair 2	
		0	Ramp pair 1	
11	RAMP_OUT_0	1	Ramp output to 0	
		0	(no op)	
12	RAMP_HOLD	1	Ramp freeze	
		0	(no op)	
13	RAMP_IN_0	1	Ramp input to 0	
		0	(no op)	
14	RREQ_LOCALLOC	1	Local mode lock	In lock, drive will not switch to local mode.
		0	(no op)	
15	TORQLIM2	1	Torque limit pair 2	
		0	Torque limit pair 1	

DCU Profile CONTROL WORD (See Parameter 0302)				
Bit	**Name**	**Value**	**Function**	**Comments**
16…26	Reserved			
27	REF_CONST	1	Constant speed ref.	These bits are only for supervision purposes.
		0	(no op)	
28	REF_AVE	1	Average speed ref.	
		0	(no op)	
29	LINK_ON	1	Master is detected in link	
		0	Link is down	
30	REQ_STARTINH	1	Start inhibit request is pending	
		0	Start inhibit request is OFF	
31	OFF_INTERLOCK	1	Panel OFF button pressed	For the control panel (or PC tool) this is the OFF button interlock.
		0	(no op)	

Status Word

The contents of the STATUS WORD is status information, sent by the drive to the master station.

ABB Drives Profile

The following table and the state diagram later in this sub-section describe the status word content for the ABB Drives Profile.

ABB Drives Profile (EFB) STATUS WORD			
Bit	**Name**	**Value**	**Description (Correspond to states/boxes in the state diagram)**
0	RDY_ON	1	READY TO SWITCH ON
		0	NOT READY TO SWITCH ON
1	RDY_RUN	1	READY TO OPERATE
		0	OFF1 ACTIVE
2	RDY_REF	1	OPERATION ENABLED
		0	OPERATION INHIBITED
3	TRIPPED	0…1	FAULT
		0	No fault
4	OFF_2_STA	1	OFF2 INACTIVE
		0	**OFF2 ACTIVE**
5	OFF_3_STA	1	OFF3 INACTIVE
		0	**OFF3 ACTIVE**
6	SWC_ON_INHIB	1	SWITCH-ON INHIBIT ACTIVE
		0	SWITCH-ON INHIBIT NOT ACTIVE
7	ALARM	1	Warning/alarm (See "Alarm Listing" in the "Diagnostics" section of *ACH550 User's Manual* for details on alarms.)
		0	No warning/alarm
8	AT_SETPOINT	1	OPERATING. Actual value equals (within tolerance limits) the reference value.
		0	Actual value is outside tolerance limits (not equal to reference value).
9	REMOTE	1	Drive control location: REMOTE (EXT1 or EXT2)
		0	Drive control location: LOCAL
10	ABOVE_LIMIT	1	Supervised parameter's value ≥ supervision high limit. Bit remains "1" until supervised parameter's value < supervision low limit. See group 32, Supervision
		0	Supervised parameter's value < supervision low limit. Bit remains "0" until supervised parameter's value > supervision high limit. See group 32, Supervision
11	EXT CTRL LOC	1	External control location 2 (EXT2) selected
		0	External control location 1 (EXT1) selected
12	EXT RUN ENABLE	1	External Run Enable signal received
		0	No External Run Enable signal received
13… 15	Unused		

DCU Profile

The following tables describe the STATUS WORD content for the DCU profile.

DCU Profile STATUS WORD (See Parameter 0303)			
Bit	**Name**	**Value**	**Status**
0	READY	1	Drive is ready to receive start command.
		0	Drive is not ready.
1	ENABLED	1	External run enable signal received.
		0	No external run enable signal received.
2	STARTED	1	Drive has received start command.
		0	Drive has not received start command.
3	RUNNING	1	Drive is modulating.
		0	Drive is not modulating.
4	ZERO_SPEED	1	Drive is at zero speed.
		0	Drive has not reached zero speed.
5	ACCELERATE	1	Drive is accelerating.
		0	Drive is not accelerating.
6	DECELERATE	1	Drive is decelerating.
		0	Drive is not decelerating.
7	AT_SETPOINT	1	Drive is at setpoint.
		0	Drive has not reached setpoint.
8	LIMIT	1	Operation is limited by Group 20 settings.
		0	Operation is within Group 20 settings.
9	SUPERVISION	1	A supervised parameter (Group 32) is outside its limits.
		0	All supervised parameters are within limits.
10	REV_REF	1	Drive reference is in reverse direction.
		0	Drive reference is in forward direction.
11	REV_ACT	1	Drive is running in reverse direction.
		0	Drive is running in forward direction.
12	PANEL_LOCAL	1	Control is in control panel (or PC tool) local mode.
		0	Control is not in control panel local mode.
13	FIELDBUS_LOCAL	1	Control is in fieldbus local mode (steals control panel local).
		0	Control is not in fieldbus local mode.
14	EXT2_ACT	1	Control is in EXT2 mode.
		0	Control is in EXT1 mode.
15	FAULT	1	Drive is in a fault state.
		0	Drive is not in a fault state.

DCU Profile STATUS WORD (See Parameter 0304)			
Bit	**Name**	**Value**	**Status**
16	ALARM	1	An alarm is on.
		0	No alarms are on.
17	REQ_MAINT	1	A maintenance request is pending.
		0	No maintenance request is pending.
18	DIRLOCK	1	Direction lock is ON. (Direction change is locked out.)
		0	Direction lock is OFF.
19	LOCALLOCK	1	Local mode lock is ON. (Local mode is locked out.)
		0	Local mode lock is OFF.
20	CTL_MODE	1	Drive is in vector control mode.
		0	Drive is in scalar control mode.
21…25	Reserved		
26	REQ_CTL	1	Copy the control word
		0	(no op)
27	REQ_REF1	1	Reference 1 requested in this channel.
		0	Reference 1 is not requested in this channel.
28	REQ_REF2	1	Reference 2 requested in this channel.
		0	Reference 2 is not requested in this channel.
29	REQ_REF2EXT	1	External PID reference 2 requested in this channel.
		0	External PID reference 2 is not requested in this channel.
30	ACK_STARTINH	1	A start inhibit from this channel is granted.
		0	A start inhibit from this channel is not granted.
31	ACK_OFF_ILCK	1	Start inhibit due to OFF button
		0	Normal operation

State Diagram

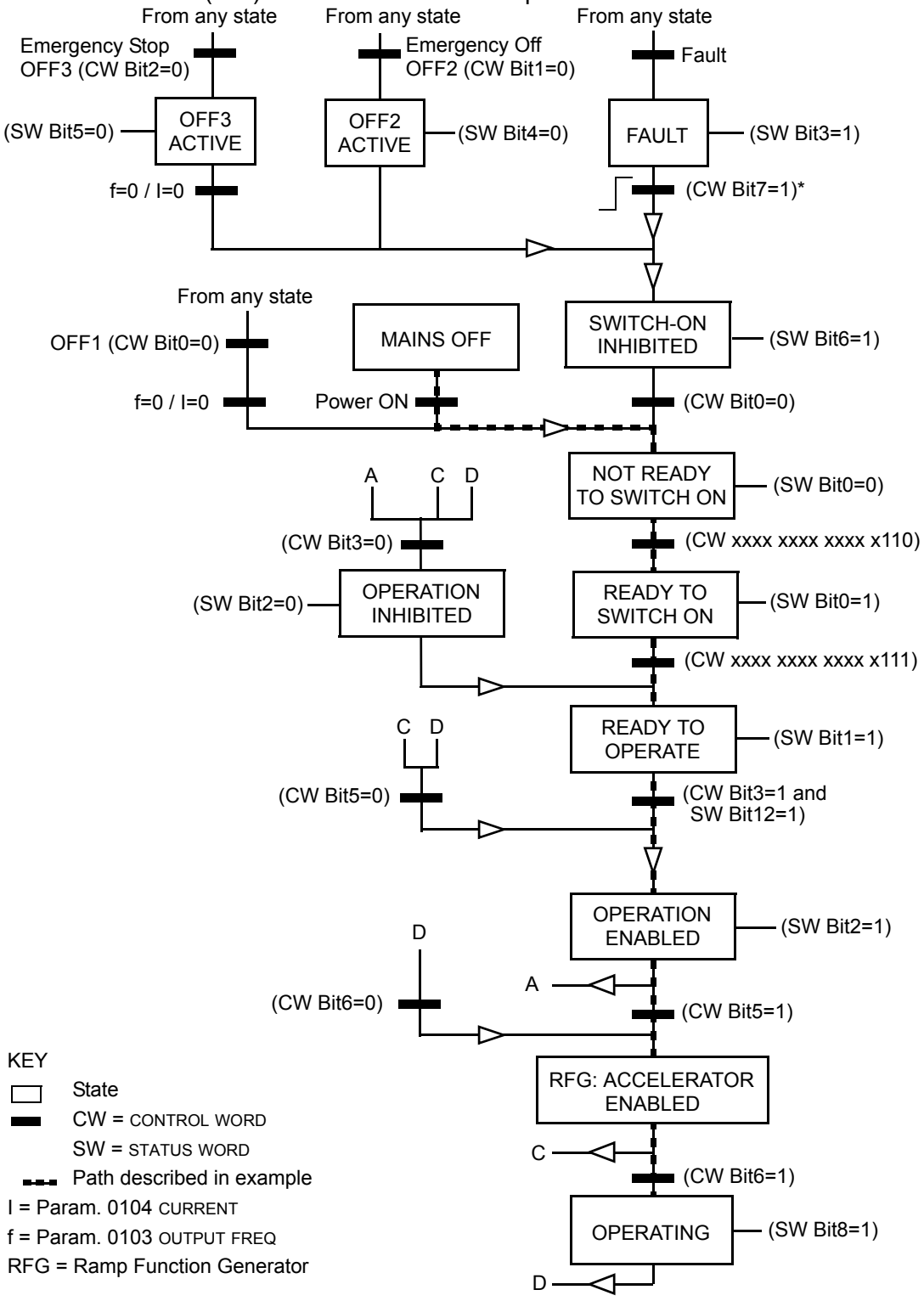
ABB Drives Profile

To illustrate the operation of the state diagram, the following example (ABB DRV LIM implementation of the ABB Drives profile) uses the control word to start the drive:

- First, the requirements for using the CONTROL WORD must be met. See above.
- When the power is first connected, the state of the drive is not ready to switch on. See dotted lined path (▪▪▪) in the state diagram below.
- Use the CONTROL WORD to step through the state machine states until the OPERATING state is reached, meaning that the drive is running and follows the given reference. See table below.

Step	CONTROL WORD **Value**	**Description**
1	CW = 0000 0000 0000 0110 bit 15 bit 0	This CW value changes the drive state to READY TO SWITCH ON.
2		Wait at least 100 ms before proceeding.
3	CW = 0000 0000 0000 0111	This CW value changes the drive state to READY TO OPERATE.
4	CW = 0000 0000 0000 1111	This CW value changes the drive state to OPERATION ENABLED. The drive starts, but will not accelerate.
5	CW = 0000 0000 0010 1111	This CW value releases the ramp function generator (RFG) output, and changes the drive state to RFG: ACCELERATOR ENABLED.
6	CW = 0000 0000 0110 1111	This CW value releases the ramp function generator (RFG) output, and changes the drive state to OPERATING. The drive accelerates to the given reference and follows the reference.

The state diagram below describes the start-stop function of CONTROL WORD (CW) and STATUS WORD (SW) bits for the ABB Drives profile.



*This state transition also occurs if the fault is reset from any other source (e.g. digital input).

Reference Scaling

ABB Drives and DCU Profiles

The following table describes REFERENCE scaling for the ABB Drives profile.

ABB Drives and DCU Profiles				
Reference	**Range**	**Reference Type**	**Scaling**	**Remarks**
REF1	-32767 … +32767	Speed or frequency	-20000 = -**(par. 1105)** 0 = 0 +20000 = **(par. 1105)** (20000 corresponds to 100%)	Final reference limited by 1104/1105. Actual motor speed limited by 2001/2002 (speed) or 2007/2008 (frequency).
REF2	-32767 … +32767	Speed or frequency	-10000 = -**(par. 1108)** 0 = 0 +10000 = **(par. 1108)** (10000 corresponds to 100%)	Final reference limited by 1107/1108. Actual motor speed limited by 2001/2002 (speed) or 2007/2008 (frequency).
		Torque	-10000 = -**(par. 1108)** 0 = 0 +10000 = **(par. 1108)** (10000 corresponds to 100%)	Final reference limited by 2015/2017 (torque1) or 2016/2018 (torque2).
		PID Reference	-10000 = -**(par. 1108)** 0 = 0 +10000 = **(par. 1108)** (10000 corresponds to 100%)	Final reference limited by 4012/4013 (PID set1) or 4112/4113 (PID set2).

Note! The setting of parameter 1104 REF1 MIN and 1107 REF2 MIN has no effect on the scaling of references.

When parameter 1103 REF1 SELECT or 1106 REF2 SELECT is set to COMM+AI1 or COMM*AI1, the reference is scaled as follows:

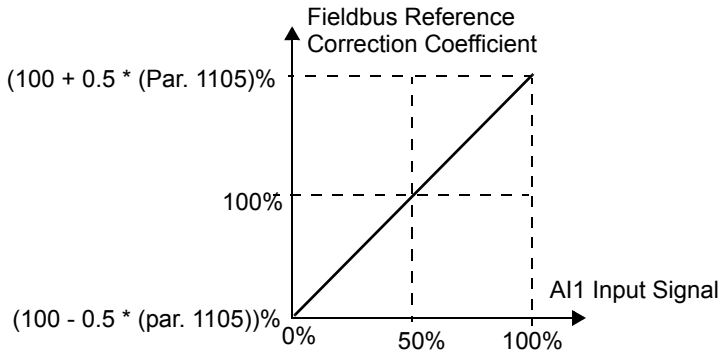
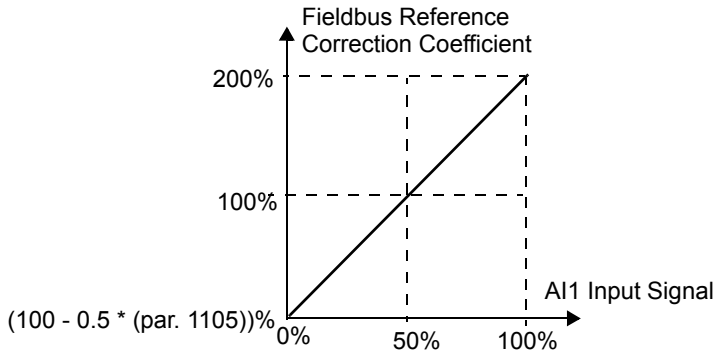
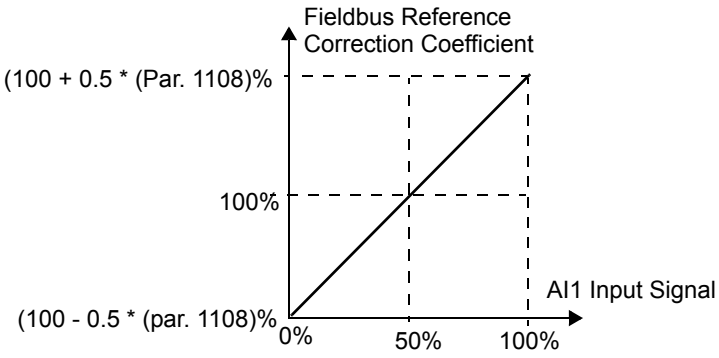
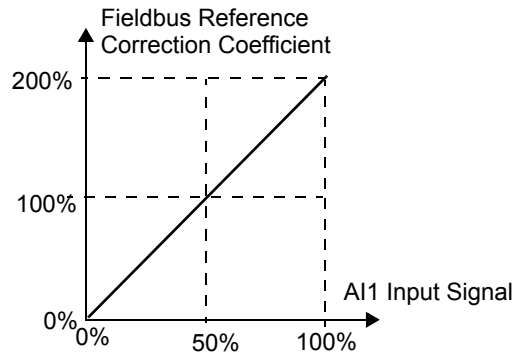
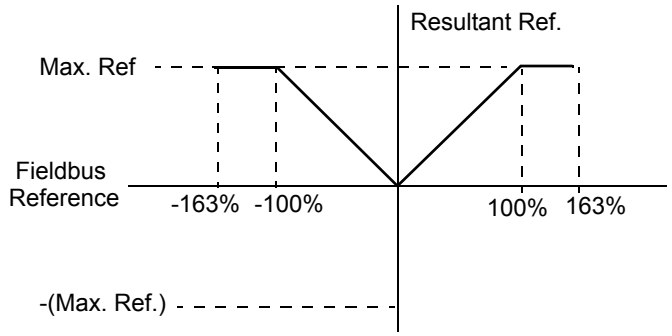
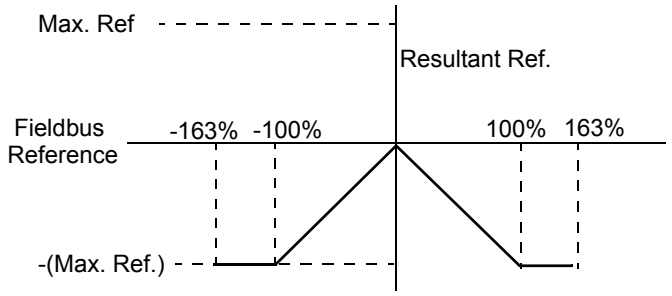
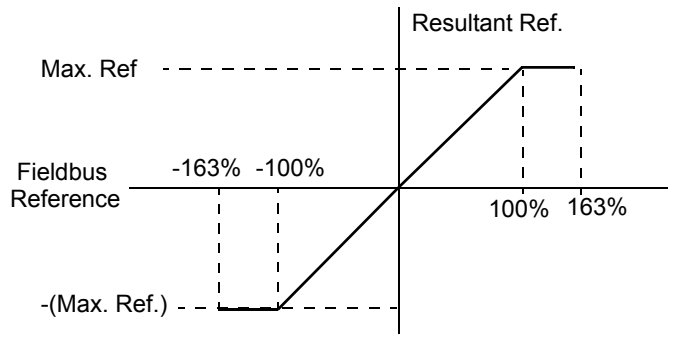
ABB Drives and DCU Profiles		
Reference	**Value Setting**	**AI Reference Scaling**
REF1	COMM+AI1	COMM (%) +(AI (%) - 0.5*REF1 MAX (%)) 

ABB Drives and DCU Profiles		
Reference	**Value Setting**	**AI Reference Scaling**
REF1	COMM*AI1	COMM (%) * (AI (%) / 0.5*REF1 MAX (%)) 
REF2	COMM+AI1	COMM (%) + (AI (%) - 0.5*REF2 MAX (%)) 
REF2	COMM*AI1	COMM (%) * (AI (%) / 0.5*REF2 MAX (%)) 

Reference Handling

Use group 10 parameters to configure for control of rotation direction for each control location (EXT1 and EXT2). The following diagrams illustrate how group 10 parameters and the sign of the fieldbus reference interact to produce REFERENCE values (REF1 and REF2). Note, fieldbus references are bipolar, that is they can be positive or negative.

ABB Drives Profile		
Parameter	**Value Setting**	**AI Reference Scaling**
1003 DIRECTION	1 (FORWARD)	
1003 DIRECTION	2 (REVERSE)	
1003 DIRECTION	3 (REQUEST)	

N2 Protocol Technical Data

Overview

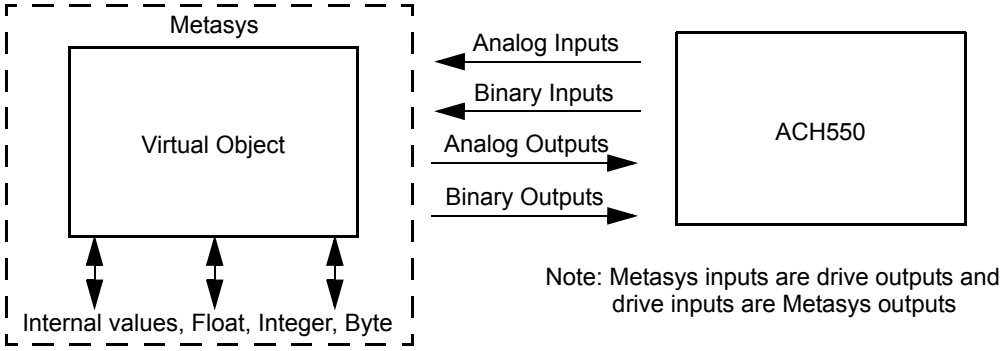
The N2 Fieldbus connection to the ACH550 drives is based on an industry standard RS-485 physical interface. The N2 Fieldbus protocol is a master-slave type, serial communication protocol, used by the Johnson Controls Metasys® system. In the Metasys architecture the N2 Fieldbus connects object interfaces and remote controllers to Network Control Units (NCUs).

The N2 Fieldbus can also be used to connect ACH550 drives to the Metasys Companion product line.

This section describes the use of the N2 Fieldbus with the ACH550 drives' connection and does not describe the protocol in detail.

Supported Features

In the N2 Fieldbus protocol the ACH550 drive appears as a "virtual object".



A virtual object is made up of:

- Analog Inputs
- Binary Inputs
- Analog Outputs
- Binary Outputs
- Internal values for Floating point, Integer, and Byte values.

The ACH550 drive does not support N2 Fieldbus communication "internal values".

All of the Analog and Binary I/O objects are listed below, starting with "N2 Analog Input Objects" on page 40.

Analog Input – The analog input objects support the following features:

- Analog Input actual value in engineering units
- Low Alarm limit
- Low Warning limit
- High Warning limit
- High Alarm limit
- Differential value for the hysteresis of the Alarms and Warnings

- Change of State (COS) enabled
- Alarm Enabled
- Warning Enabled
- Override value is received, but there is no action taken.

Binary Input – The binary input objects support the following features:

- Binary Input actual value
- Normal / Alarm state specification
- Alarm Enabled
- Change of State (COS) enabled
- Override value is received, but there is no action taken.

Analog Output – The analog output objects support the following features:

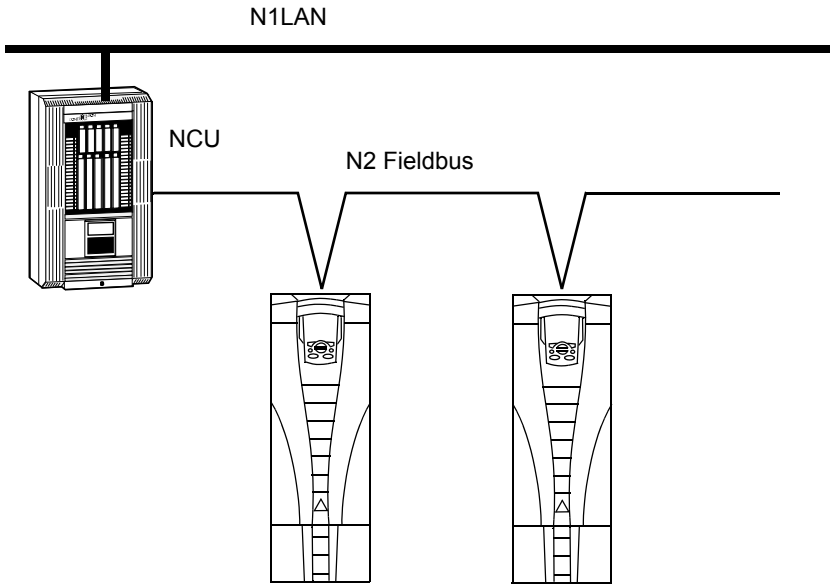
- Analog Output value in engineering units
- Override value is used to change the Analog Output value. It is not possible to return to the previous value by removing the override. The override feature is used only to change the value.

Binary Output – The binary output objects support the following features:

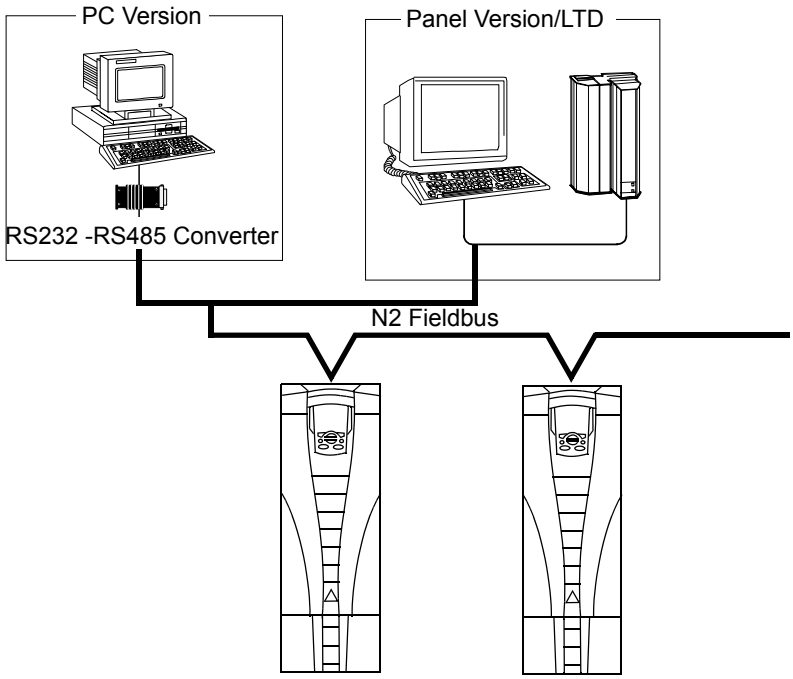
- Binary Output value
- Override value is used to change the Binary Output value. It is not possible to return to the previous value by removing the override. The override feature is used only to change the value.

Metasys Integration

The following diagram shows the drives' integration to the Johnson Controls Metasys system.



The following diagram shows the drives' integration to the Johnson Controls Metasys Companion system.



On the N2 Fieldbus each ACH550 drive can be accessed by the full complement of Metasys FMS features, including Change-of-State (COS) monitoring, alarm notification, scheduling, trend, and totalization.

On one N2 Fieldbus segment there can be up to 32 nodes while integrating ACH550 drives with Johnson Controls Metasys.

Drive Device Type

For the Metasys and Metasys Companion products, the device type for the ACH550 drive is VND.

N2 Analog Input Objects

The following table lists the N2 Analog Input objects defined for the ACH550 drive.

N2 Analog Inputs:					
Number	**Object**	**Drive Parameter**	**Scale Factor**	**Units**	**Range**
AI1	OUTPUT FREQUENCY	0103	10	Hz	0…250
AI2	RATED SPEED	Note 1	10	%	0 …100
AI3	SPEED	0102	1	rpm	0 …9999
AI4	CURRENT	0104	10	A	0…9999
AI5	TORQUE	0105	10	%	-200…200
AI6	POWER	0106	10	kW	0…9999
AI7	DRIVE TEMPERATURE	0110	10	°C	0 …125
AI8	KILOWATT HOURS	0115	1	kWh	0…9999

N2 Analog Inputs:					
Number	**Object**	**Drive Parameter**	**Scale Factor**	**Units**	**Range**
AI9	MEGAWATT HOURS	0141	1	MWh	0…999
AI10	RUN TIME	0114	1	H	0…9999
AI11	DC BUS VOLTAGE	0107	1	V	0…999
AI12	OUTPUT VOLTAGE	0109	1	V	0…999
AI13	PRC PID FEEDBACK	0130	10	%	0…100
AI14	PRC PID DEVIATION	0132	10	%	0…100
AI15	EXT PID FEEDBACK	0131	10	%	0…100
AI16	EXT PID DEVIATION	0133	10	%	0…100
AI17	LAST FAULT	0401	1		fault code
AI18	PREV FAULT	0402	1		fault code
AI19	OLDEST FAULT	0403	1		fault code
AI20	AI 1 ACTUAL	0120	10	%	0…100
AI21	AI 2 ACTUAL	0121	10	%	0…100
AI22	AO 1 ACTUAL	0124	10	mA	0…20
AI23	AO 2 ACTUAL	0125	10	mA	0…20
AI24	MOTOR TEMP	0145	1	°C	0…200
AI25	REVOLUTION CNT	0142	1	MREV	0…32767

1. RATED SPEED is a percent of maximum frequency (parameter 2008) if the drive is in scalar mode, and is a percent of maximum speed (parameter 2002) in speed mode.

N2 Binary Input Objects

The following table lists the N2 Binary Input objects defined for the ACH550 drive.

N2 Binary Inputs:			
Number	**Object**	**Drive Parameter**	**Range**
BI1	STOP/RUN	Status Word	0 = Stop, 1 = Drive Running
BI2	FORWARD/REVERSE	Status Word	0 = Forward, 1 = Reverse
BI3	FAULT STATUS	Status Word	0 = OK, 1 = Drive Fault
BI4	RELAY 1 STATUS	0122 (bit mask 04)	0 = Off, 1 = On
BI5	RELAY 2 STATUS	0122 (bit mask 02)	0 = Off, 1 = On
BI6	RELAY 3 STATUS	0122 (bit mask 01)	0 = Off, 1 = On
BI7	RELAY 4 STATUS	0123 (bit mask 04)	0 = Off, 1 = On
BI8	RELAY 5 STATUS	0123 (bit mask 02)	0 = Off, 1 = On
BI9	RELAY 6 STATUS	0123 (bit mask 01)	0 = Off, 1 = On
BI10	INPUT 1 STATUS	0118 (bit mask 04)	0 = Off, 1 = On
BI11	INPUT 2 STATUS	0118 (bit mask 02)	0 = Off, 1 = On
BI12	INPUT 3 STATUS	0118 (bit mask 01)	0 = Off, 1 = On
BI13	INPUT 4 STATUS	0119 (bit mask 04)	0 = Off, 1 = On
BI14	INPUT 5 STATUS	0119 (bit mask 02)	0 = Off, 1 = On

N2 Binary Inputs:			
Number	**Object**	**Drive Parameter**	**Range**
BI15	INPUT 6 STATUS	0119 (bit mask 01)	0 = Off, 1 = On
BI16	EXTERNAL 2 SELECT	Status Word	0 = EXT1 = EXT2
BI17	HAND/AUTO	Status Word	0 = AUTO, 1 = HAND
BI18	ALARM	Status Word	0 = OK, 1 = ALARM
BI19	MAINTENANCE REQ	Status Word	0 = OK, 1 = MAINT REQ
BI20	DRIVE READY	Status Word	0 = Not Ready, 1 = Ready
BI21	AT SETPOINT	Status Word	0 = No, 1 = At Setpoint
BI22	RUN ENABLED	Status Word	0 = Not Enabled, 1 = Enabled
BI23	N2 LOCAL MODE	Status Word	0 = Auto, 1 = N2 Local
BI24	N2 CONTROL SRC	Status Word	0 = No, 1 = Yes
BI25	N2 REF1 SRC	Status Word	0 = No, 1 = Yes
BI26	N2 REF2 SRC	Status Word	0 = No, 1 = Yes

N2 Analog Output Objects

The following table lists the N2 Analog Output objects defined for the ACH550 drive.

N2 Analog Outputs:					
Number	**Object**	**Drive Parameter**	**Scale Factor**	**Units**	**Range**
AO1	REFERENCE 1	Reference 1	10	%	0…100
AO2	REFERENCE 2	Reference 2	10	%	0…100
AO3	ACCEL TIME 1	2202	10	s	0.1…1800
AO4	DECEL TIME 1	2203	10	s	0.1…1800
AO5	CURRENT LIMIT	2003	10	A	0…1.3*I_{2N}
AO6	PID1-CONT GAIN	4001	10	%	0.1…100
AO7	PID1-CONT I-TIME	4002	10	s	0.1…600
AO8	PID1-CONT D-TIME	4003	10	s	0…10
AO9	PID1-CONT D FILTER	4004	10	s	0…10
AO10	PID2-CONT GAIN	4101	10	%	0.1…100
AO11	PID2-CONT I-TIME	4102	10	s	0.1…600
AO12	PID2-CONT D-TIME	4103	10	s	0…10
AO13	PID2-CONT D FILTER	4104	10	s	0…10
AO14	COMMAND AO 1	135	10	%	0…100
AO15	COMMAND AO 2	136	10	%	0…100
AO16	EXT PID SETPOINT	4211	10	%	0…100
AO17	SPD OUT MIN	2001/2007	10	%	0…200
AO18	SPD OUT MAX	2002/2008	10	%	0…200
A019	MAILBOX PARAMETER		1		0…65535
A020	MAILBOX DATA		1		0…65535

N2 Binary Output Objects

The following table lists the N2 Binary Output objects defined for the ACH550 drive.

N2 Binary Outputs:			
Number	**Object**	**Drive Parameter**	**Range**
BO1	STOP/START	Command Word	0 = Stop, 1 = Start to Speed
BO2	FORWARD/REVERSE	Command Word	0 = Forward, 1 = Reverse
BO3	PANEL LOCK	Command Word	0 = Open, 1 = Locked
BO4	RUN ENABLE	Command Word	0 = Enable, 1 = Disable
BO5	REF1/REF2 SELECT	Command Word	0 = Ref1, 1 = Ref2
BO6	FAULT RESET	Command Word	Change 0 -> 1 Resets
BO7	COMMAND RO 1	134 (bit mask 01)	0 = Off, 1 = On
BO8	COMMAND RO 2	134 (bit mask 02)	0 = Off, 1 = On
BO9	COMMAND RO 3	134 (bit mask 04)	0 = Off, 1 = On
BO10	COMMAND RO 4	134 (bit mask 08)	0 = Off, 1 = On
BO11	COMMAND RO 5	134 (bit mask 10)	0 = Off, 1 = On
BO12	COMMAND RO 6	134 (bit mask 20)	0 = Off, 1 = On
BO13	RESET RUN TIME	114 (indirectly)	0 = N/A, 1 = On (Reset Run Time)
BO14	RESET KWH COUNT	115 (indirectly)	0 = N/A, 1 = On (Reset kWh Count)
BO15	PRC PID SELECT	4027 (indirectly)	0 = SET2, 1 = SET2
BO16	N2 LOCAL CTL (Note 1)	Command Word	0 = Auto, 1 = N2
BO17	N2 LOCAL REF (Note 1)	Command Word	0 = Auto, 1 = N2
BO18	SAVE PARAMETERS	1607 (indirectly)	0 = N/A, 1 = On (Save Parameters)
B019	READ MAILBOX		0 = No, 1 = Yes
B020	WRITE MAILBOX		0 = No, 1 = Yes

1. N2 LOCAL CTL and N2 LOCAL REF have priority over drive input terminals. Use these binary outputs for temporary N2 control of the drive when COMM is not the selected control source.

DDL File for NCU

The listing below is the Data Definition Language (DDL) file for ACH550 drives used with the Network Control Units.

This listing is useful when defining drive I/O objects to the Network Controller Units.

Below is the ACH550.DDL file listing.

```
*****************************************************************
*  ABB Drives, ACH 550 Variable Frequency Drive
*****************************************************************
CSMODEL "ACH_550","VND"

AITITLE "Analog_Inputs"
BITITLE "Binary_Inputs"
AOTITLE "Analog_Outputs"
BOTITLE "Binary_Outputs"
```

```
CSAI "AI1",N,N,"FREQ_ACT","Hz"
CSAI "AI2",N,N,"PCT_ACT","%"
CSAI "AI3",N,N,"SPEED","RPM"
CSAI "AI4",N,N,"CURRENT","A"
CSAI "AI5",N,N,"TORQUE","%"
CSAI "AI6",N,N,"POWER","kW"
CSAI "AI7",N,N,"DRV_TEMP","°C"
CSAI "AI8",N,N,"ENERGY_k","kWh"
CSAI "AI9",N,N,"ENERGY_M","MWh"
CSAI "AI10",N,N,"RUN_TIME","H"
CSAI "AI11",N,N,"DC_VOLT","V"
CSAI "AI12",N,N,"VOLT_ACT","V"
CSAI "AI13",N,N,"PID1_ACT","%"
CSAI "AI14",N,N,"PID2_DEV","%"
CSAI "AI15",N,N,"PID2_ACT","%"
CSAI "AI16",N,N,"PID2_DEV","%"
CSAI "AI17",N,N,"LAST_FLT","Code"
CSAI "AI18",N,N,"PREV_FLT","Code"
CSAI "AI19",N,N,"1ST_FLT","Code"
CSAI "AI20",N,N,"AI_1_ACT","%"
CSAI "AI21",N,N,"AI_2_ACT","%"
CSAI "AI22",N,N,"AO_1_ACT","mA"
CSAI "AI23",N,N,"AO_2_ACT","mA"
CSAI "AI24",N,N,"MTR_TEMP","°C"
CSAI "AI25",N,N,"REVL_CNT",""

CSBI "BI1",N,N,"STOP/RUN","STOP","RUN"
CSBI "BI2",N,N,"FWD/REV","FWD","REV"
CSBI "BI3",N,N,"FAULT","OK","FLT"
CSBI "BI4",N,N,"RELAY_1","OFF","ON"
CSBI "BI5",N,N,"RELAY_2","OFF","ON"
CSBI "BI6",N,N,"RELAY_3","OFF","ON"
CSBI "BI7",N,N,"RELAY_4","OFF","ON"
CSBI "BI8",N,N,"RELAY_5","OFF","ON"
CSBI "BI9",N,N,"RELAY_6","OFF","ON"
CSBI "BI10",N,N,"INPUT_1","OFF","ON"
CSBI "BI11",N,N,"INPUT_2","OFF","ON"
CSBI "BI12",N,N,"INPUT_3","OFF","ON"
CSBI "BI13",N,N,"INPUT_4","OFF","ON"
CSBI "BI14",N,N,"INPUT_5","OFF","ON"
CSBI "BI15",N,N,"INPUT_6","OFF","ON"
CSBI "BI16",N,N,"EXT1/2","EXT1","EXT2"
CSBI "BI17",N,N,"HND/AUTO","HAND","AUTO"
CSBI "BI18",N,N,"ALARM","OFF","ON"
CSBI "BI19",N,N,"MNTNCE_R","OFF","ON"
CSBI "BI20",N,N,"DRV_REDY","NO","YES"
CSBI "BI21",N,N,"AT_SETPT","NO","YES"
CSBI "BI22",N,N,"RUN_ENAB","NO","YES"
CSBI "BI23",N,N,"N2_LOC_M","AUTO","N2_L"
CSBI "BI24",N,N,"N2_CTRL","NO","YES"
```

```
CSBI "BI25",N,N,"N2_R1SRC","NO","YES"
CSBI "BI26",N,N,"N2_R2SRC","NO","YES"
CSAO "AO1",Y,Y,"REF_1","%"
CSAO "AO2",Y,Y,"REF_2","%"
CSAO "AO3",Y,Y,"ACCEL_1","s"
CSAO "AO4",Y,Y,"DECEL_1","s"
CSAO "AO5",Y,Y,"CURR_LIM","A"
CSAO "AO6",Y,Y,"PID1_GN","%"
CSAO "AO7",Y,Y,"PID1_I","s"
CSAO "AO8",Y,Y,"PID1_D","s"
CSAO "AO9",Y,Y,"PID1_FLT","s"
CSAO "AO10",Y,Y,PID2_GN","%"
CSAO "AO11",Y,Y,"PID2_I","s"
CSAO "AO12",Y,Y,"PID2_D","s"
CSAO "AO13",Y,Y,"PID2_FLT","s"
CSAO "AO14",Y,Y,"CMD_AO_1","%"
CSAO "AO15",Y,Y,"CMD_AO_2","%"
CSAO "AO16",Y,Y,"PI2_STPT","%"
CSAO "AO17",Y,Y,"MIN_SPD","%"
CSAO "AO18",Y,Y,"MAX_SPD","%"
CSAO "AO19",Y,Y,"MB_PARAM",""
CSAO "AO20",Y,Y,"MB_DATA",""
CSBO "BO1",Y,Y,"START","STOP","START"
CSBO "BO2",Y,Y,"REVERSE","FWD","REV"
CSBO "BO3",Y,Y,"PAN_LOCK","OPEN","LOCKED"
CSBO "BO4",Y,Y,"RUN_ENAB","DISABLE","ENABLE"
CSBO "BO5",Y,Y,"R1/2_SEL","EXT_1","EXT_2"
CSBO "BO6",Y,Y,"FLT_RSET","-","RESET"
CSBO "BO7",Y,Y,"CMD_RO_1","OFF","ON"
CSBO "BO8",Y,Y,"CMD_RO_2","OFF","ON"
CSBO "BO9",Y,Y,"CMD_RO_3","OFF","ON"
CSBO "BO10",Y,Y,"CMD_RO_4","OFF","ON"
CSBO "BO11",Y,Y,"CMD_RO_5","OFF","ON"
CSBO "BO12",Y,Y,"CMD_RO_6","OFF","ON"
CSBO "BO13",Y,Y,"RST_RTIM","OFF","RESET"
CSBO "BO14",Y,Y,"RST_KWH","OFF","RESET"
CSBO "BO15",Y,Y,"PID_SEL","SET1","SET2"
CSBO "BO16",Y,Y,"N2_LOC_C","AUTO","N2"
CSBO "BO17",Y,Y,"N2_LOC_R","EUTO","N2"
CSBO "BO18",Y,Y,"SAV_PRMS","OFF","SAVE"
CSBO "BO19",Y,Y,"READ_MB","NO","READ"
CSBO "BO20",Y,Y,"WRITE_MB","NO","WRITE"
```

FLN Protocol Technical Data

Overview

The FLN fieldbus connection to the ACH550 drives is based on an industry standard RS-485 physical interface. The FLN (Floor Level Network) Fieldbus protocol is a serial communication protocol, used by the Siemens APOGEE® system. The ACH550 interface is specified in Siemens application 2734.

Supported Features

The ACH550 supports all required FLN features.

Reports

The ACH550 provides seven pre-defined reports. Using a report request generated from the FLN fieldbus controller, select one of the following sets of points. By providing views of selected points, these reports are often easier to work with than views of the full point database.

ABB ACH550

FLN ABB ACH550 Report			
Point		**Subpoint Name**	**Data**
#	**Type**		
01	LAO	CTLR ADDRESS	Each host FLN application (e.g. CIS or Insight) controls both the particular data reported for each point, and the report format.
02	LAO	APPLICATION	
20	LAO	OVRD TIME	
29	LDO	DAY.NIGHT	

Startup

FLN Startup Report			
Point		**Subpoint Name**	**Data**
#	**Type**		
21	LDI	FWD.REV	Each host FLN application (e.g. CIS or Insight) controls both the particular data reported for each point, and the report format.
22	LDO	CMD FWD.REV	
23	LDI	STOP.RUN	
24	LDO	CMD STP.STRT	
25	LDI	EXT1.2 ACT	
26	LDO	EXT1.2 CMD	
34	LDI	ENA.DIS ACT	
35	LDO	ENA.DIS CMD	
36	LDI	FLN LOC ACT	
60	LAO	INPUT REF1	
61	LAO	INPUT REF2	
68	LDO	FLN LOC CTL	
69	LDO	FLN LOC REF	

FLN Startup Report			
Point		Subpoint Name	Data
#	Type		
94	LDO	RESET FAULT	

Overview

FLN Overview Report			
Point		Subpoint Name	Data
#	Type		
03	LAI	FREQ OUTPUT	Each host FLN application (e.g. CIS or Insight) controls both the particular data reported for each point, and the report format.
04	LAI	PCT OUTPUT	
05	LAI	SPEED	
06	LAI	CURRENT	
07	LAI	TORQUE	
08	LAI	POWER	
09	LAI	DRIVE TEMP	
10	LAI	DRIVE KWH	
11	LAI	DRIVE MWH	
12	LAI	RUN TIME	
13	LAI	DC BUS VOLT	
14	LAI	OUTPUT VOLT	
17	LAI	MOTOR TEMP	
18	LAI	MREV COUNTER	
21	LDI	FWD.REV	
23	LDI	STOP.RUN	
25	LDI	EXT1.2 ACT	
27	LDI	DRIVE READY	
28	LDI	AT SETPOINT	
33	LDI	HANDAUTO ACT	
34	LDI	ENA.DIS ACT	
36	LDI	FLN LOC ACT	

Drive I/O

FLN Drive I/O Report			
Point		Subpoint Name	Data
#	Type		
40	LDO	RO 1 COMMAND	Each host FLN application (e.g. CIS or Insight) controls both the particular data reported for each point, and the report format.
41	LDO	RO 2 COMMAND	
42	LDO	RO 3 COMMAND	
43	LDO	RO 4 COMMAND	
44	LDO	RO 5 COMMAND	

FLN Drive I/O Report			
Point		Subpoint Name	Data
#	Type		
45	LDO	RO 6 COMMAND	
46	LAO	AO 1 COMMAND	
47	LAO	AO 2 COMMAND	
70	LDI	DI 1 ACTUAL	
71	LDI	DI 2 ACTUAL	
72	LDI	DI 3 ACTUAL	
73	LDI	DI 4 ACTUAL	
74	LDI	DI 5 ACTUAL	
75	LDI	DI 6 ACTUAL	
76	LDI	RO 1 ACTUAL	
77	LDI	RO 2 ACTUAL	
78	LDI	RO 3 ACTUAL	
79	LDI	RO 4 ACTUAL	
80	LDI	RO 5 ACTUAL	
81	LDI	RO 6 ACTUAL	
85	LAI	AO 2 ACTUAL	

Drive Config

FLN Drive Config. Report			
Point		Subpoint Name	Data
#	Type		
30	LAO	CURRENT LIM	Each host FLN application (e.g. CIS or Insight) controls both the particular data reported for each point, and the report format.
31	LAO	ACCEL TIME 1	
32	LAO	DECEL TIME 1	
48	LDO	RST RUN TIME	
49	LDO	RESET KWH	
59	LDO	LOCK PANEL	
66	LDO	SPD OUT MIN	
67	LDO	SPD OUT MAX	
95	LAO	MBOX PARAM	
96	LAO	MBOX DATA	
97	LDO	MBOX READ	
98	LDO	MBOX WRITE	

Process PID

FLN Process PID Report			
Point		Subpoint Name	Data
#	Type		
15	LAI	PRC PID FBCK	Each host FLN application (e.g. CIS or Insight) controls both the particular data reported for each point, and the report format.
16	LAI	PRC PID DEV	
50	LAO	PRC PID GAIN	
51	LAO	PRC PID ITIM	
52	LAO	PRC PID DTIM	
53	LAO	PRC PID DFIL	
54	LDO	PRC PID SEL	
60	LAO	INPUT REF1	
61	LAO	INPUT REF2	
82	LAI	AI 1 ACTUAL	
83	LAI	AI 2 ACTUAL	
84	LAI	AO 1 ACTUAL	
85	LAI	AO 2 ACTUAL	

External PID

FLN External PID Report			
Point		Subpoint Name	Data
#	Type		
55	LAO	EXT PID GAIN	Each host FLN application (e.g. CIS or Insight) controls both the particular data reported for each point, and the report format.
56	LAO	EXT PID ITIM	
57	LAO	EXT PID DTIM	
58	LAO	EXT PID DFIL	
62	LAO	EXT PID STPT	
63	LAI	EXT PID FBCK	
64	LAI	EXT PID DEV	
82	LAI	AI 1 ACTUAL	
83	LAI	AI 2 ACTUAL	
84	LAI	AO 1 ACTUAL	
85	LAI	AO 2 ACTUAL	

Scaling Drive Feedback Values

Feedback values are provided with units of percent, where 0% and 100% correspond to the range of the sensor being used to measure the control variable. These points have default units in Hz. If other units are required:

- Unbundle these points with appropriate slopes and intercepts.
- The new intercept equals the lowest value of the desired range.

- Calculate the new slope as follows:

$$\text{New Slope} = \frac{\text{(Desired Range, i.e. high - low values) x (Slope of Existing Point)}}{\text{Range of Existing Point}}$$

$$= \frac{\text{(60 Hz - 0 Hz) x (0.01)}}{\text{100\% - 0\%}} = 0.006$$

Example – You are controlling water temperature from a cooling tower using the ACH550 to control a fan. The temperature sensor has a range of 30 to 250 degrees Fahrenheit.

To unbundle the set point (INPUT REF 2), for commanding in degrees Fahrenheit, where 0…60 Hz is equal to 30…250° F:

New Intercept = 30 (the temperature that corresponds to 0%)

$$\text{New Slope} = \frac{\text{(Desired Range) x (Slope of Existing Point)}}{\text{Range of Existing Point}}$$

$$= \frac{\text{(250° F - 30° F) x (0.1)}}{\text{100\% - 0\%}} = 0.22$$

To unbundle the feedback (PRC PID FBCK) for monitoring in degrees Fahrenheit:

New Intercept = 30

$$\text{New Slope} = \frac{\text{(Desired Range) x (Slope of Existing Point)}}{\text{Range of Existing Point}}$$

$$= \frac{\text{(250° F - 30° F) x (0.01)}}{\text{100\% - 0\%}} = 0.022$$

Loop Gains

PRC PID GAIN (Point 50) and PRC PID ITIM (Point 51) are PID parameters similar to the P and I gains in the APOGEE TECs. Because the ABB PI loop and the Siemens loop are structured differently, there is no a one-to-one correspondence between the gains. The following formulas allow translation from ABB gains to Siemens gains and vice versa:

- To convert from ABB PI gains to Siemens P and I gains:

$$\text{P GAIN}_{\text{Siemens}} = \text{PI GAIN}_{\text{ABB}} \times 0.0015$$

$$\text{I GAIN}_{\text{Siemens}} = \frac{\text{PI GAIN}_{\text{ABB}}}{\text{PI GAIN}_{\text{ABB}}} \times 0.0015$$

- To convert from Siemens P and I gains to ABB PI gains:

$$\text{P GAIN}_{\text{ABB}} = \text{PI GAIN}_{\text{Siemens}} \times 667$$

$$\text{I GAIN}_{\text{ABB}} = \frac{\text{PI GAIN}_{\text{Siemens}}}{\text{PI GAIN}_{\text{Siemens}}} \times 667$$

Point Database

The following table lists the point database for FLN / ACH550 (Application 2734).

FLN Point Database								
Point		Subpoint Name	Factory Default	Engr. Units	Slope	Intercept	On Text	Off Text
#	Type		(SI Units)					
01	LAO	CTLR ADDRESS	99	-	1	0	-	-
02	LAO	APPLICATION	2734	-	1		-	-
{03}	LAI	FREQ OUTPUT	0	Hz	0.1	0	-	-
{04}	LAI	PCT OUTPUT	0	PCT	0.1	0	-	-
{05}	LAI	SPEED	0	RPM	1	0	-	-
{06}	LAI	CURRENT	0	A	0.1		-	-
{07}	LAI	TORQUE	0	PCT	0.1	-200	-	-
{08}	LAI	POWER	0 (0)	HP (KW)	0.134 0.1	0 0	-	-
{09}	LAI	DRIVE TEMP	77 (25)	° F (° C)	0.18 (0.1)	32 0	-	-
{10}	LAI	DRIVE KWH	0	KWH	1		-	-
{11}	LAI	DRIVE MWH	0	MWH	1		-	-
{12}	LAI	RUN TIME	0	HRS	1		-	-
{13}	LAI	DC BUS VOLT	0	V	1		-	-
{14}	LAI	OUTPUT VOLT	0	V	1		-	-
{15}	LAI	PRC PID FBCK	0	PCT	0.1		-	-
{16}	LAI	PRC PID DEV	0	PCT	0.1		-	-
{17}	LAI	MOTOR TEMP	77(25)	° F (° C)	1.8 (1)	32 0	-	-
{18}	LAI	MREV COUNTER	0	MREV	1	0	-	-
20	LAO	OVRD TIME	1	hrs	1	0	-	-
{21}	LDI	FWD.REV	FWD	-	1	0	REV	FWD
{22}	LDO	CMD FWD.REV	FWD	-	1	0	REV	FWD
{23}	LDI	STOP.RUN	STOP	-	1	0	RUN	STOP
{24}	LDO	CMD STP.STRT	STOP	-	1	0	RUN	STOP
{25}	LDI	EXT1.2 ACT	EXT1	-	1	0	EXT2	EXT1
{26}	LDO	EXT1.2 CMD	EXT1	-	1	0	EXT2	EXT1
{27}	LDI	DRIVE READY	NOTRDY	-	1	0	READY	NOTRDY
{28}	LDI	AT SETPOINT	NO	-	1	0	YES	NO
{29}	LDO	DAY.NIGHT	DAY	-	1	0	NIGHT	DAY
30	LAO	CURRENT LIM	0	A	0.1	0	-	-
31	LAO	ACCEL TIME 1	300	sec	0.1	0	-	-
32	LAO	DECEL TIME 1	300	sec	0.1	0	-	-
{33}	LDI	HANDAUTO ACT	AUTO	-	1	0	HAND	AUTO

FLN Point Database								
Point		Subpoint Name	Factory Default	Engr. Units	Slope	Intercept	On Text	Off Text
#	Type		(SI Units)					
{34}	LDI	ENA.DIS ACT	DISABL	-	1	0	ENABLE	DISABL
{35}	LDO	ENA.DIS CMD	DISABL	-	1	0	ENABLE	DISABL
{36}	LDI	FLN LOC ACT	AUTO	-	1	0	FLN	AUTO
{37}	LDI	CTL SRC	NO	-	1	0	YES	NO
{38}	LDI	FLN REF1 SRC	NO	-	1	0	YES	NO
{39}	LDI	FLN REF2 SRC	NO	-	1	0	YES	NO
{40}	LDO	RO 1 COMMAND	OFF	-	1	0	ON	OFF
{41}	LDO	RO 2 COMMAND	OFF	-	1	0	ON	OFF
{42}	LDO	RO 3 COMMAND	OFF	-	1	0	ON	OFF
{43}	LDO	RO 4 COMMAND	OFF	-	1	0	ON	OFF
{44}	LDO	RO 5 COMMAND	OFF	-	1	0	ON	OFF
{45}	LDO	RO 6 COMMAND	OFF	-	1	0	ON	OFF
{46}	LAO	AO 1 COMMAND	PCT	PCT	0.1	0	-	-
{47}	LAO	AO 2 COMMAND	PCT	PCT	0.1	0	-	-
48	LDO	RST RUN TIME	NO	-	1	0	RESET	NO
49	LDO	RESET KWH	NO	-	1	0	RESET	NO
50	LAO	PRC PID GAIN	10	PCT	0.1	0	-	-
51	LAO	PRC PID ITIM	600	SEC	0.1	0	-	-
52	LAO	PRC PID DTIM	0	SEC	0.1	0	-	-
53	LAO	PRC PID DFIL	10	SEC	0.1	0	-	-
54	LDO	PRC PID SEL	SET1	-	1	0	SET2	SET1
55	LAO	EXT PID GAIN	10	PCT	0.1	0	-	-
56	LAO	EXT PID ITIM	600	SEC	0.1	0	-	-
57	LAO	EXT PID DTIM	0	SEC	0.1	0	-	-
58	LAO	EXT PID DFIL	10	SEC	0.1	0	-	-
59	LDO	LOCK PANEL	UNLOCK	-	1	0	LOCK	UNLOCK
{60}	LAO	INPUT REF1	0	PCT	0.1	0	-	-
{61}	LAO	INPUT REF2	0	PCT	0.1	0	-	-
{62}	LAO	EXT PID STPT	0	PCT	0.1	0	-	-
{63}	LAI	EXT PID FBCK	0	PCT	0.1	0	-	-
{64}	LAI	EXT PID DEV	0	PCT	0.1	0	-	-

FLN Point Database								
Point		Subpoint Name	Factory Default	Engr. Units	Slope	Intercept	On Text	Off Text
#	Type		(SI Units)					
66	LDO	SPD OUT MIN	0	PCT	0.1	0	-	-
67	LDO	SPD OUT MAX	1000	PCT	0.1	0	-	-
{68}	LDO	FLN LOC CTL	AUTO	-	1	0	FLN	AUTO
{69}	LDO	FLN LOC REF	AUTO	-	1	0	FLN	AUTO
{70}	LDI	DI 1 ACTUAL	OFF	-	1	0	ON	OFF
{71}	LDI	DI 2 ACTUAL	OFF	-	1	0	ON	OFF
{72}	LDI	DI 3 ACTUAL	OFF	-	1	0	ON	OFF
{73}	LDI	DI 4 ACTUAL	OFF	-	1	0	ON	OFF
{74}	LDI	DI 5 ACTUAL	OFF	-	1	0	ON	OFF
{75}	LDI	DI 6 ACTUAL	OFF	-	1	0	ON	OFF
{76}	LDI	RO 1 ACTUAL	OFF	-	1	0	ON	OFF
{77}	LDI	RO 2 ACTUAL	OFF	-	1	0	ON	OFF
{78}	LDI	RO 3 ACTUAL	OFF	-	1	0	ON	OFF
{79}	LDI	RO 4 ACTUAL	OFF	-	1	0	ON	OFF
{80}	LDI	RO 5 ACTUAL	OFF	-	1	0	ON	OFF
{81}	LDI	RO 6 ACTUAL	OFF	-	1	0	ON	OFF
{82}	LAI	AI 1 ACTUAL	0	PCT	0.1	0	-	-
{83}	LAI	AI 2 ACTUAL	0	PCT	0.1	0	-	-
{84}	LAI	AO 1 ACTUAL	0	MA	0.1	0	-	-
{85}	LAI	AO 2 ACTUAL	0	MA	0.1	0	-	-
{86}	LDI	OK.ALARM	OK	-	1	0	ALARM	OK
{87}	LDI	OK.MAINT	OK	-	1	0	MAINT	OK
{88}	LAI	ALARM WORD 1	-	-	1	0	-	-
{89}	LAI	ALARM WORD 2	-	-	1	0	-	-
{90}	LAI	LAST FAULT	-	-	1	0	-	-
{91}	LAI	PREV FAULT 1	-	-	1	0	-	-
{92}	LAI	PREV FAULT 2	-	-	1	0	-	-
{93}	LDI	OK.FAULT	OK	-	1	0	FAULT	OK
{94}	LDO	RESET FAULT	NO	-	1	0	RESET	NO
{95}	LAO	MBOX PARAM	-	-	1	0	-	-
{96}	LAO	MBOX DATA	-	-	1	0	-	-
{97}	LDO	MBOX READ	DONE	-	1	0	READ	DONE
{98}	LDO	MBOX WRITE	DONE	-	1	0	WRITE	DONE
{99}	LAO	ERROR STATUS	-	-	1	0	-	-

a. Points not listed are not used in this application.

b. A single value in a column means that the value is the same in English units and in SI units.

c. Point numbers that appear in brackets { } may be unbundled at the field panel.

Detailed Point Descriptions

FLN Detailed Point Descriptions			
Point		**Description**	**Drive Parameter**
1	CTRL ADDRESS	The FLN address of the drive. It can be set by FLN and by the panel.	5302
2	APPLICATION	The Application ID for FLN on the ACH550. This ID is assigned by Siemens for each unique application. It correlates directly to a particular point list approved at the time of release. Therefore, this point list shall remain fixed once approval is granted. Any changes to the point list shall require a new Application ID and re-approval by Siemens. The Application ID assigned to ACH550 is 2934.	
3	FREQ OUTPUT	The output frequency applied to the motor, in Hertz.	0103
4	PCT OUTPUT	The ratio of output frequency or speed to the corresponding maximum rating, depending on control mode. • For scalar mode, it is the ratio of Output Frequency (parameter 0103) to Maximum Frequency (parameter 2008). • For speed mode, it is the ratio Speed (parameter 0102) to Maximum Speed (2002).	None. This ratio is calculated by the FLN application.
5	SPEED	The calculated speed of the motor, in RPM.	0102
6	CURRENT	The measured output current.	0104
7	TORQUE	The calculated output torque of the motor as a percentage of nominal torque.	0105
8	POWER	The measured output power in KW. The FLN point definition also supports horsepower by selecting English units.	0106
	DRIVE TEMP	The measured heatsink temperature, in ° C. The FLN point definition also supports ° F by selecting English units.	0110
10	DRIVE KWH	The drive's cumulative power consumption in kilowatt-hours. This value may be reset by commanding FLN point 49, RESET KWH.	0115
11	DRIVE MWH	The drive's cumulative power consumption in megawatt hours. This value cannot be reset.	0141
12	RUN TIME	The drive's cumulative run time in hours. This value may be reset by commanding FLN point 48, RESET RUN TIME.	0114
13	DC BUS VOLT	The DC bus voltage level of the drive.	0107
14	OUTPUT VOLT	The AC output voltage applied to the motor.	0109
15	PRC PID FBCK	The Process PID feedback signal.	0130
16	PRC PID DEV	The deviation of the Process PID output signal from its setpoint.	0132
17	MOTOR TEMP	The measured motor temperature as set up in Group 35.	0145
18	ROTATION CNT	The motor's cumulative revolution count, in mega-revolutions.	0142
19	N/A		
20	OVRD TIME	1 of the 5 mandatory FLN points required for compatibility with Siemens control systems. It has no functionality in the drive application.	None

FLN Detailed Point Descriptions			
Point		**Description**	**Drive Parameter**
21	FWD.REV ACT	Indicates the rotational direction of the motor, regardless of control source (1 = REV, 0 = FWD).	
22	FWD.REV CMD	Commanded by FLN to change the rotational direction of the drive. • Parameter 1001 must be set to COMM for FLN to control the direction of the motor by EXT1. • Parameter 1002 must be set to COMM for FLN to control the direction of the motor by EXT2.	
23	RUN.STOP ACT	Indicates the drive's run status, regardless of control source (1 = RUN, 0 = STOP).	
24	RUN.STOP CMD	Commanded by FLN to start the drive. • Parameter 1001 must be set to COMM for FLN to control the run state of the drive by EXT1. • Parameter 1002 must be set to COMM for FLN to have this control.	
25	EXT1.2 ACT	Indicates whether External 1 or External 2 is the active control source (1 = EXT2, 0 = EXT1).	
26	EXT1.2 CMD	Commanded by FLN to select External 1 or External 2 as the active control source (1 = EXT2, 0 = EXT1). Parameter 1102 must be set to COMM for FLN to have this control.	
27	DRIVE READY	Indicates the drive is ready to accept a run command (1 = READY, 0 = NOTRDY).	
28	AT SETPOINT	Indicates the drive has reached its commanded setpoint (1 = YES, 0 = NO)	
29	DAY.NIGHT	1 of the 5 mandatory FLN points required for compatibility with Siemens control systems. It has no functionality in the drive application.	None
30	CURRENT LIM	Sets the output current limit of the drive.	2003
31	ACCEL TIME 1	Sets the acceleration time for Ramp 1.	2202
32	DECEL TIME 1	Sets the deceleration time for Ramp 1.	2203
33	HANDAUTO ACT	Indicates whether the drive is in Hand or Auto control (1 = HAND, 0 = AUTO).	
34	ENA.DIS ACT	Indicates the status of the Run Enable command, regardless of its source (1 = ENABLE, 0 = DISABL).	
35	ENA.DIS CMD	Commanded by FLN to assert the Run Enable command (1 = ENABLE, 0 = DISABL). Parameter 1601 must be set to COMM for FLN to have this control.	
36	FLN LOC ACT	Indicates if the drive has been placed in “FLN LOCAL” mode by commanding either point 68 (FLN LOC CTL) or point 69 (FLN LOC REF). Commanding either of these points to FLN (1) “steals” control from its normal source and places in under FLN control. Note that the HAND mode of the panel has priority over FLN local control.	

FLN Detailed Point Descriptions			
Point		**Description**	**Drive Parameter**
37	FLN CTL SRC	Indicates if FLN is a source for control inputs (1 = YES, 0 = NO). Note that this status point is true if any of the following control inputs are from FLN: Run/Stop, Ext1/2 Select or Run Enable.	
38	FLN REF1 SRC	Indicates if FLN is the source for speed reference 1 (1 = YES, 0 = NO).	
39	FLN REF2 SRC	Indicates if FLN is the source for speed reference 2 (1 = YES, 0 = NO).	
40	RO1 COMMAND	Controls the output state of Relay 1. Parameter 1401 must be set to COMM for FLN to have this control (1 = ON, 0 = OFF).	0134, bit 0
41	RO2 COMMAND	Controls the output state of Relay 2. Parameter 1402 must be set to COMM for FLN to have this control (1 = ON, 0 = OFF).	0134, bit 1
42	RO3 COMMAND	Controls the output state of Relay 3. Parameter 1403 must be set to COMM for FLN to have this control (1 = ON, 0 = OFF).	0134, bit 2
43	RO4 COMMAND	Controls the output state of Relay 4. Access to relay 4 require ACH550 option OREL. Parameter 1410 must be set to COMM for FLN to have this control (1 = ON, 0 = OFF).	0134, bit 3
44	RO5 COMMAND	Controls the output state of Relay 5. Access to relay 5 require ACH550 option OREL. Parameter 1411 must be set to COMM for FLN to have this control (1 = ON, 0 = OFF).	0134, bit 4
45	RO6 COMMAND	Controls the output state of Relay 6. Access to relay 6 require ACH550 option OREL. Parameter 1412 must be set to COMM for FLN to have this control (1 = ON, 0 = OFF).	0134, bit 5
46	AO1 COMMAND	Controls Analog Output 1. Parameter 1501 must be set to this value for FLN to have this control.	0135 (COMM VALUE 1)
47	AO2 COMMAND	Controls Analog Output 2. Parameter 1507 must be set to this value for FLN to have this control.	0136 (COMM VALUE 2)
48	RESET RUN TIME	Commanded by FLN to reset the cumulative run timer (1 = RESET, 0 = NO). The control input is rising-edge sensitive, so, once the command is issued, this point automatically returns to its inactive state. This “momentary” operation avoids any need for an explicit command to clear the point before a subsequent reset can be issued.	
49	RESET KWH	Commanded by FLN to reset the cumulative kilowatt-hour counter (1 = RESET, 0 = NO). The control input is rising-edge sensitive, so, once the command is issued, this point automatically returns to its inactive state. This “momentary” operation avoids any need for an explicit command to clear the point before a subsequent reset can be issued.	

FLN Detailed Point Descriptions			
Point		**Description**	**Drive Parameter**
50	PRC PID GAIN	Sets the proportional gain of the active Process PID set, as selected by Point 54, PRC PID SEL (1 = SET2, 0 = SET1).	4001 (SET1) 4101 (SET2)
51	PRC PID ITIM	Sets the integration time of the active Process PID set, as selected by Point 54, PRC PID SEL (1 = SET2, 0 = SET1).	4002 (SET1) 4102 (SET2)
52	PRC PID DTIM	Sets the derivation time of the active Process PID set, as selected by Point 54, PRC PID SEL (1 = SET2, 0 = SET1).	4001 (SET1) 4101 (SET2)
53	PRC PID DFIL	Sets the time constant for the error-derivative of the active Process PID set, as selected by Point 54, PRC PID SEL (1 = SET2, 0 = SET1).	4004 (SET1) 4104 (SET2)
54	PRC PID SEL	Selects the active Process PID set (1 = SET2, 0 = SET1).	4027
55	EXT PID GAIN	Sets the proportional gain of the External PID controller.	4201
56	EXT PID ITIM	Sets the integration time of the External PID controller.	4202
57	EXT PID DTIM	Sets the derivation time of the External PID controller.	4203
58	EXT PID DFIL	Sets the time constant for the error-derivative of the External PID controller.	4204
59	LOCK PANEL	Command by FLN to lock the panel and prevent parameter changes (1 = LOCK, 0 = UNLOCK).	1602
60	INPUT REF 1	Sets Input Reference 1. Parameter 1102 must be set to COMM for FLN to control this value.	
61	INPUT REF 2	Sets Input Reference 2. Parameter 1106 must be set to COMM for FLN to control this value.	
62	EXT PID STPT	The setpoint for the External PID controller. The function of this point requires parameter 4210, PID Setpoint Select, to be set to 19 (Internal).	4211
63	EXT PID FBCK	The External PID feedback signal.	0131
64	EXT PID DEV	The deviation of the External PID output signal from its setpoint.	0133
65	N/A		
66	SPD OUT MIN	Sets the minimum output speed of the drive as a percentage of the motor nominal rating.	2007 (SCALAR) 2001 (SPEED)
67	SPD OUT MAX	Sets the maximum output speed of the drive as a percentage of the motor nominal rating.	2008 (SCALAR) 2002 (SPEED)
68	FLN LOC CTL	Commanded by FLN to temporarily “steal” start/stop control of the drive from its normal source and place it under FLN control. This functionality is analogous to placing the drive in HAND mode at the panel, with the control being taken by FLN instead. HAND mode at the panel has priority over this point. Thus, this point is only effective in temporarily taking control from the digital inputs or some other internal control functionality.	

FLN Detailed Point Descriptions			
Point		**Description**	**Drive Parameter**
69	FLN LOC REF	Commanded by FLN to temporarily “steal” input reference control of the drive from its normal source and place it under FLN control. This functionality is analogous to placing the drive in HAND mode at the panel, with the reference control being taken by FLN instead. HAND mode at the panel has priority over this point. Thus, this point is only effective in temporarily taking control from the analog inputs or some other internal control functionality.	
70	DI 1 ACTUAL	Indicates the status of Digital Input 1 (1 = ON, 0 = OFF).	0118, bit 2
71	DI 2 ACTUAL	Indicates the status of Digital Input 2 (1 = ON, 0 = OFF).	0118, bit 1
72	DI 3 ACTUAL	Indicates the status of Digital Input 3 (1 = ON, 0 = OFF).	0118, bit 0
73	DI 4 ACTUAL	Indicates the status of Digital Input 4 (1 = ON, 0 = OFF).	0119, bit 2
74	DI 5 ACTUAL	Indicates the status of Digital Input 5 (1 = ON, 0 = OFF).	0119, bit 1
75	DI 6 ACTUAL	Indicates the status of Digital Input 6 (1 = ON, 0 = OFF).	0119, bit 0
76	RO 1 ACTUAL	Indicates the status of Relay Output 1 (1 = ON, 0 = OFF).	0122, bit 2
77	RO 2 ACTUAL	Indicates the status of Relay Output 2 (1 = ON, 0 = OFF).	0122, bit 1
78	RO 3 ACTUAL	Indicates the status of Relay Output 3 (1 = ON, 0 = OFF).	0122, bit 0
79	RO 4 ACTUAL	Indicates the status of Relay Output 4 (1 = ON, 0 = OFF).	0123, bit 2
80	RO 5 ACTUAL	Indicates the status of Relay Output 5 (1 = ON, 0 = OFF).	0123, bit 1
81	RO 6 ACTUAL	Indicates the status of Relay Output 6 (1 = ON, 0 = OFF).	0123, bit 0
82	AI 1 ACTUAL	Indicates the input level of Analog Input 1.	0120
83	AI 2 ACTUAL	Indicates the input level of Analog Input 2.	0121
84	AO 1 ACTUAL	Indicates the output level of Analog Output 1.	0124
85	AO 2 ACTUAL	Indicates the output level of Analog Output 2.	0125
86	OK.ALARM	Indicates the current alarm state of the drive (1 = ALARM, 0 = OK).	
87	OK.MAINT	Indicates the current maintenance state of the drive (1 = MAINT, 0 = OK). Maintenance triggers are configured in drive parameter Group 29.	
88	ALARM WORD1	This point is a bit-field indicating active alarms in the drive.	0308
89	ALARM WORD2	This point is a bit-field indicating active alarms in the drive.	0309
90	LAST FAULT	This point is first in the drive's fault log and indicates the most recent fault declared.	0401
91	PREV FAULT 1	This point is second in the drive's fault log and indicates the previous fault declared.	0412
92	PREV FAULT 2	This point is last in the drive's fault log and indicates the oldest fault in the log.	0413
93	OK.FAULT	Indicates the current fault state of the drive (1 = FAULT, 0 = OK).	

FLN Detailed Point Descriptions			
Point		**Description**	**Drive Parameter**
94	RESET FAULT	Command by FLN to reset a faulted drive (1 = RESET, 0 = NO). Parameter 1604 must be set to COMM for FLN to control this state. The control input is rising-edge sensitive, so, once the command is issued, this point automatically returns to its inactive state. This “momentary” operation avoids any need for an explicit command to clear the point before a subsequent reset can be issued.	
95	MBOX PARAM	Sets the parameter to be used by the mailbox function.	
96	MBOX DATA	Sets or indicates the data value of the mailbox function.	
97	MBOX READ	Command by FLN to read the parameter value specified by Point 95, MBOX PARAM. The parameter value is returned in Point 96, MBOX DATA. The control input is rising-edge sensitive, so, once the command is issued, this point automatically returns to its inactive state. This “momentary” operation avoids any need for an explicit command to clear the point before a subsequent reset can be issued.	
98	MBOX WRITE	Command by FLN to write the data value specified by Point 96, MBOX DATA, to the parameter value specified by Point 95, MBOX PARAM. The control input is rising-edge sensitive, so, once the command is issued, this point automatically returns to its inactive state. This “momentary” operation avoids any need for an explicit command to clear the point before a subsequent reset can be issued.	
99	ERROR STATUS	1 of the 5 mandatory FLN points required for compatibility with Siemens control systems. It has no functionality in the drive application.	None

BACnet Technical Data

Protocol Implementation Conformance Statement (PICS)

PICS Summary

BACnet Standard Device Profile. This version of ACH550 BACnet fully conforms to the 'Application-Specific Controller' standard device profile (B-ASC).

Services Supported. The following services are supported by the ACH550:

- I-Am (Response to Who-Is, also broadcast on power-up & other reset)
- I-Have (Response to Who-Has)
- ReadProperty
- WriteProperty
- DeviceCommunicationControl
- ReinitializeDevice

Data Link Layer. The ACH550 implements MS/TP (Master) Data Link Layer. All standard MS/TP baud rates are supported (9600, 19200, 38400 & 76800).

MAC ID / Device Object Instance. The ACH550 supports separate MAC ID and Device Object Instance parameters:

- Set the MAC ID using drive parameter 5302. Default: 5302 = 1.
- Set the Device Object Instance using drive parameter 5311. Default: 5311 = 0, which causes the MAC ID to “double” as the Device Object Instance. For a separate Device Object Instance value, set using a non-zero value for drive parameter 5311.

Automatic Baud Rate Detection. Set the communication baud rate using drive parameter 5303. However, this value is “overridden” if automatic baud rate detection is enabled and a different baud rate is detected. By default, autobaud detection is disabled – enable by setting drive parameter 5314 to 1. When autobaud detection is enabled, drive parameter 5315 displays the detected baud rate.

Note! Autobaud detection samples for, and adjusts to, only the standard MS/TP baud rates (9600, 19200, 38400 & 76800).

Max Info Frames Property. Configure the Device Object Max Info Frames property using drive parameter 5312. Default: 5312 = 1.

Max Master Property. Configure the Device Object Max Master property using drive parameter 5313. Default: 5313 = 127.

Statement

This statement is part of this Standard and is required for its use.

BACnet Protocol Implementation Conformance Statement	
Date:	June 1, 2004
Vendor Name:	ABB, Inc
Product Name:	Low Voltage AC Motor Drive
Product Model Number:	ACH550
Applications Software Version:	0500
Firmware Revision:	201C
BACnet Protocol Revision:	2
Product Description:	The ACH550 is a high-performance adjustable frequency drive specifically designed for commercial automation applications. This product supports native BACnet, connecting directly to the MS/TP LAN. All standard MS/TP baud rates are supported, as well as master mode functionality. Over BACnet, the drive can be fully controlled as a standard adjustable frequency drive. In addition, up to 16 configurable I/O ports are available over BACnet for user applications.
BACnet Standardized Device Profile (Annex L):	☐ BACnet Operator Workstation (B-OWS) ☐ BACnet Building Controller (B-BC) ☐ BACnet Advanced Application Controller (B-AAC) ☒ BACnet Application Specific Controller (B-ASC) ☐ BACnet Smart Sensor (B-SS) ☐ BACnet Smart Actuator (B-SA)
List all BACnet Interoperability Building Blocks Supported (Annex K):	DS-RP-B, DS-WP-B, DM-DDB-B, DM-DOB-B, DM-DCC-B, DM-RD-B.
Segmentation Capability:	☐ Segmented requests supported. Window Size ____ ☐ Segmented responses supported. Window Size ____
Standard Object Types Supported: An object type is supported if it may be present in the device. For each standard Object Type supported provide the following data: 1) Whether objects of this type are dynamically creatable using the CreateObject service 2) Whether objects of this type are dynamically detectable using the DeleteObject service 3) List of the optional properties supported 4) List of all properties that are writable where not otherwise required by this standard 5) List of proprietary properties and for each its property identifier, datatype, and meaning 6) List of any property range restrictions	See table at "Object/Property Support Matrix" on page 63.

BACnet Protocol Implementation Conformance Statement	
Data Link Layer Options:	☐ BACnet IP, (Annex J) ☐ BACnet IP, (Annex J), Foreign Device ☐ ISO 8802-3, Ethernet (Clause 7) ☐ ANSI/ATA 878.1, 2.5 Mb. ARCNET (Clause 8) ☐ ANSI/ATA 878.1, RS-485 ARCNET (Clause 8), baud rate(s) ___ ☒ MS/TP master (Clause 9), baud rate(s): 9600, 19200, 38400, 76800 ☐ MS/TP slave (Clause 9), baud rate(s): ___ ☐ Point-To-Point, EIA 232 (Clause 10), baud rate(s): ___ ☐ Point-To-Point, modem, (Clause 10), baud rate(s): ___ ☐ LonTalk, (Clause 11), medium: _____ ☐ Other: _____
Device Address Binding: Is static device binding supported? (This is currently necessary for two-way communication with MS/TP slaves and certain other devices.)	☐ Yes ☒ No
Networking Options:	☐ Router, Clause 6 - List all routing configurations, e.g., ARCNET-Ethernet, Ethernet-MS/TP, etc. ☐ Annex H, BACnet Tunneling Router over IP ☐ BACnet/IP Broadcast Management Device (BBMD)
Does the BBMD support registrations by Foreign Devices?	☐ Yes ☐ No
Character Sets Supported: Indicating support for multiple character sets does not imply that they can all be supported simultaneously.	☒ ANSI X3.4 ☐ IBM™/Microsoft™ DBCS ☐ ISO 8859-1 ☐ ISO 10646 (UCS-2) ☐ ISO 10646 (UCS-4) ☐ JIS C 6226
If this product is a communication gateway, describe the types of non-BACnet equipment/networks(s) that the gateway supports:	

BACnet Object Definitions

Object/Property Support Matrix

The following table summarizes the Object Types/Properties Supported:

Property	Object Type						
	Device	Binary Input	Binary Output	Binary Value	Analog Input	Analog Output	Analog Value
Object Identifier	✓	✓	✓	✓	✓	✓	✓
Object Name	✓	✓	✓	✓	✓	✓	✓
Object Type	✓	✓	✓	✓	✓	✓	✓
System Status	✓						
Vendor Name	✓						
Vendor Identifier	✓						
Model Name	✓						
Firmware Revision	✓						
Appl Software Revision	✓						
Protocol Version	✓						
Protocol Revision	✓						
Services Supported	✓						
Object Types Supported	✓						
Object List	✓						
Max APDU Length	✓						
Segmentation Support	✓						
APDU Timeout	✓						
Number APDU Retries	✓						
Max Master	✓						
Max Info Frames	✓						
Device Address Binding	✓						
Database Revision	✓						
Present Value		✓	✓	✓	✓	✓	✓
Status Flags		✓	✓	✓	✓	✓	✓
Event State		✓	✓	✓	✓	✓	✓
Out-of-Service		✓	✓	✓	✓	✓	✓
Units					✓	✓	✓
Priority Array			✓	✓ *		✓	✓ *
Relinquish Default			✓	✓ *		✓	✓ *
Polarity		✓	✓				
Active Text		✓	✓	✓			
Inactive Text		✓	✓	✓			

* For commandable values only.

Binary Input Object Instance Summary

The following table summarizes the Binary Input Objects supported:

Instance ID	Object Name	Description	Active/ Inactive Text	Present Value Access Type
BI0	RO 1 ACT	This object indicates the status of Relay Output 1.	ON/OFF	R
BI1	RO 2 ACT	This object indicates the status of Relay Output 2.	ON/OFF	R
BI2	RO 3 ACT	This object indicates the status of Relay Output 3.	ON/OFF	R
BI3	RO 4 ACT	This object indicates the status of Relay Output 4 (requires OREL-01 option).	ON/OFF	R
BI4	RO 5 ACT	This object indicates the status of Relay Output 5 (requires OREL-01 option)	ON/OFF	R
BI5	RO 6 ACT	This object indicates the status of Relay Output 6 (requires OREL-01 option)	ON/OFF	R
BI6	DI 1 ACT	This object indicates the status of Digital Input 1.	ON/OFF	R
BI7	DI 2 ACT	This object indicates the status of Digital Input 2.	ON/OFF	R
BI8	DI 3 ACT	This object indicates the status of Digital Input 3.	ON/OFF	R
BI9	DI 4 ACT	This object indicates the status of Digital Input 4.	ON/OFF	R
BI10	DI 5 ACT	This object indicates the status of Digital Input 5.	ON/OFF	R
BI11	DI 6 ACT	This object indicates the status of Digital Input 6.	ON/OFF	R

Note! For Present Value Access Types, R = Read-only, W = Writeable, C = Commandable. Commandable values support priority arrays & relinquish defaults.

Binary Output Object Instance Summary

The following table summarizes the Binary Output Objects supported:

Instance ID	Object Name	Description	Active/ Inactive Text	Present Value Access Type
BO0	RO1 COMMAND	This object controls the output state of Relay 1. This control requires that parameter 1401 value = COMM.	ON/OFF	C
BO1	RO2 COMMAND	This object controls the output state of Relay 2. This control requires that parameter 1402 value = COMM.	ON/OFF	C
BO2	RO3 COMMAND	This object controls the output state of Relay 3. This control requires that parameter 1403 value = COMM.	ON/OFF	C

Instance ID	Object Name	Description	Active/ Inactive Text	Present Value Access Type
BO3	RO4 COMMAND	This object controls the output state of Relay 4. This control requires that parameter 1410 value = COMM (also requires OREL-01 option).	ON/OFF	C
BO4	RO5 COMMAND	This object controls the output state of Relay 5. This control requires that parameter 1411 value = COMM (also requires OREL-01 option).	ON/OFF	C
BO5	RO6 COMMAND	This object controls the output state of Relay 6. This control requires that parameter 1412 value = COMM (also requires OREL-01 option).	ON/OFF	C

Note! For Present Value Access Types, R = Read-only, W = Writeable, C = Commandable. Commandable values support priority arrays & relinquish defaults.

Binary Value Object Instance Summary

The following table summarizes the Binary Value Objects supported:

Instance ID	Object Name	Description	Active/Inactive Text	Present Value Access Type
BV0	RUN/STOP ACT	This object indicates the drive Run Status, regardless of the control source.	RUN/STOP	R
BV1	FWD/REV ACT	This object indicates the motor's rotation direction, regardless of the control source.	REV/FWD	R
BV2	FAULT ACT	this object indicates the drive's fault status.	FAULT/OK	R
BV3	EXT 1/2 ACT	This object indicates which control source is active: External 1 or External 2.	EXT2/EXT1	R
BV4	HAND/AUTO ACT	This object indicates whether the drive is under Hand or Auto control.	HAND/AUTO	R
BV5	ALARM ACT	This object indicates the drive's alarm status.	ALARM/OK	R
BV6	MAINT REQ	This object indicates the drive's maintenance status. Refer to Group 29 in the drive's parameter descriptions.	MAINT/OK	R
BV7	DRIVE READY	This object indicates whether the drive is ready to accept a run command.	READY/NOT READY	R
BV8	AT SETPOINT	This object indicates whether the drive is at the commanded setpoint.	YES/NO	R

Instance ID	Object Name	Description	Active/Inactive Text	Present Value Access Type
BV9	RUN ENA ACT	This object indicates the Run Enable command status, regardless of the control source.	ENABLE/ DISABLE	R
BV10	RUN/STOP CMD	This object commands a drive start. Control requires either: • Parameter 1001 value = COMM for control by EXT1 or • Parameter 1002 value = COMM for control by EXT2.	RUN/STOP	C
BV11	FWD/REV CMD	This object commands a motor rotation direction change. Control requires either: • Parameter 1001 value = COMM for control by EXT1 or • Parameter 1002 value = COMM for control by EXT2.	REV/FWD	C
BV12	RUN ENA CMD	This object commands Run Enable. Control requires parameter 1601 value = COMM.	ENABLE/ DISABLE	C
BV13	EXT 1/2 CMD	This object selects ext1 or ext2 as the active control source. Control requires parameter 1102 value = COMM.	EXT2/EXT1	C
BV14	FAULT RESET	This object resets a faulted drive. The command is rising-edge triggered. Control requires parameter 1604 value = COMM.	RESET/NO	C
BV15	MBOX READ	This object reads a parameter (defined by AV25 MBOX PARAM) and returns it in AV26 MBOX DATA.	READ/RESET	W
BV16	MBOX WRITE	This object writes the data value specified by AV26, MBOX DATA, to a parameter (defined by AV25, MBOX PARAM).	WRITE/RESET	W
BV17	LOCK PANEL	This object locks the panel and prevents parameter changes. The corresponding drive parameter is 1602.	LOCK/UNLOCK	W
BV18	CTL OVERRIDE CMD	This object commands the drive into BACnet Control Override. In this mode, BACnet takes drive control from the normal source. However, the control panel's HAND mode has priority over BACnet Control Override.	ON/OFF	C

Instance ID	Object Name	Description	Active/Inactive Text	Present Value Access Type
BV19	CTL OVERRIDE ACT	This object indicates whether the drive is in BACnet Control Override. (See BV18.)	ON/OFF	R
BV20	START ENABLE 1	This object commands start enable1. Control requires pa;ram 1608 value=COMM.	ENABLE/ DISABLE	C
BV21	START ENABLE 2	This object commands start enable1. Control requires pa;ram 1608 value=COMM.	ENABLE/ DISABLE	C

Note! For Present Value Access Types, R = Read-only, W = Writeable, C = Commandable. Commandable values support priority arrays & relinquish defaults.

Analog Input Object Instance Summary

The following table summarizes the Analog Input Objects supported:

Instance ID	Object Name	Description	Units	Present Value Access Type
AI0	ANALOG INPUT 1	This object indicates the value of Analog Input 1. The corresponding drive parameter is 0120.	Percent	R
AI1	ANALOG INPUT 2	This object indicates the value of Analog Input 2. The corresponding drive parameter is 0121.	Percent	R

Note! For Present Value Access Types, R = Read-only, W = Writeable, C = Commandable. Commandable values support priority arrays & relinquish defaults.

Analog Output Object Instance Summary

The following table summarizes the Analog Output Objects supported:

Instance ID	Object Name	Description	Units	Present Value Access Type
AO0	AO 1 COMMAND	This object controls Analog Output 1. The corresponding drive parameter is 0135, COMM VALUE 1. Control requires parameter 1501 value = 135.	Percent	C
AO1	AO 2 COMMAND	This object controls Analog Output 2. The corresponding drive parameter is 0136, COMM VALUE 2. Control requires parameter 1507 value = 136.	Percent	C

Note! For Present Value Access Types, R = Read-only, W = Writeable, C = Commandable. Commandable values support priority arrays & relinquish defaults.

Analog Value Object Instance Summary

The following table summarizes the Analog Value Objects supported:

Instance ID	Object Name	Description	Units	Present Value Access Type
AV0	OUTPUT SPEED	This object indicates the calculated motor speed in RPM. The corresponding drive parameter is 0102.	RPM	R
AV1	OUTPUT FREQ	This object indicates the output frequency applied to the motor in Hz. The corresponding drive parameter is 0103.	Hertz	R
AV2	DC BUS VOLT	This object indicates the drive's DC bus voltage level. The corresponding drive parameter is 0107.	Volts	R
AV3	OUTPUT VOLT	This object indicates the AC output voltage applied to the motor. The corresponding drive parameter is 0109.	Volts	R
AV4	CURRENT	This object indicates the measured output current. The corresponding drive parameter is 0104.	Amps	R
AV5	TORQUE	This object indicates the calculated motor output torque as a percentage of nominal torque. The corresponding drive parameter is 0105.	Percent	R
AV6	POWER	This object indicates the measured output power in kW. The corresponding drive parameter is 0106.	Kilowatts	R
AV7	DRIVE TEMP	This object indicates the measured heatsink temperature in °C. The corresponding drive parameter is 0110.	°C	R
AV8	KWH (R)	This object indicates, in kW hours, the drive's accumulated energy usage since the last reset. The value can be reset to zero. The corresponding drive parameter is 0115.	kWh	W
AV9	KWH (NR)	This object indicates the drive's accumulated energy usage in kW hours. The value cannot be reset.	kWh	R
AV10	PRC PID FBCK	This object is the Process PID feedback signal. The corresponding drive parameter is 0130.	Percent	R
AV11	PRC PID DEV	This object is the Process PID output signal's deviation from its setpoint. The corresponding drive parameter is 0132.	Percent	R
AV12	EXT PID FBCK	This object is the External PID feedback signal. The corresponding drive parameter is 0131.	Percent	R

Instance ID	Object Name	Description	Units	Present Value Access Type
AV13	EXT PID DEV	This object is the External PID output signal's deviation from its setpoint. The corresponding drive parameter is 0133.	Percent	R
AV14	RUN TIME (R)	This object indicates, in hours, the drive's accumulated run time since the last reset. The value can be reset to zero. The corresponding drive parameter is 0114.	Hours	R
AV15	MOTOR TEMP	This object indicates the drive's motor temperature, as set up in parameter Group 35. The corresponding drive parameter is 0145.	°C	R
AV16	INPUT REF 1	This object sets Input Reference 1. Control requires parameter 1102 value = COMM.	Percent	C
AV17	INPUT REF 2	This object sets either: • Input Reference 2. Control requires parameter 1106 value = COMM. • Process PID setpoint. Control requires parameter 1106 value = PID1 OUT and parameter 4010 value = COMM.	Percent	C
AV18	LAST FLT	This object indicates the most recent fault entered in the drive's fault log. The corresponding drive parameter is 0401.	None	R
AV19	PREV FLT 1	This object indicates the second most recent fault entered in the drive's fault log. The corresponding drive parameter is 0412.	None	R
AV20	PREV FLT 2	This object indicates the third most recent fault entered in the drive's fault log. The corresponding drive parameter is 0413.	None	R
AV21	AO 1 ACT	This object indicates Analog Output 1's level. The corresponding drive parameter is 0124.	Milliamps	R
AV22	AO 2 ACT	This object indicates Analog Output 2's level. The corresponding drive parameter is 0125.	Milliamps	R
AV23	ACCEL1 TIME	This object sets the Ramp1 acceleration time. The corresponding drive parameter is 2202.	Seconds	W
AV24	DECEL1 TIME	This object sets the Ramp1 deceleration time. The corresponding drive parameter is 2203.	Seconds	W
AV25	MBOX PARAM	This object defines the parameter to be read or written to by the mailbox function. See BV15 and BV16.	None	W
AV26	MBOX DATA	This object holds the mailbox function's parameter value – a value that was read, or is to be written. See BV15 and BV16.	None	W

Instance ID	Object Name	Description	Units	Present Value Access Type
AV27	EXT PID STPT	This object sets the External PID controller setpoint. The corresponding drive parameter is 4211. Control requires parameter 4210, PID SETPOINT SEL, value = 19 (INTERNAL).	Percent	C

Note! For Present Value Access Types, R = Read-only, W = Writeable, C = Commandable. Commandable values support priority arrays & relinquish defaults.

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